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Chapter 1

Introduction

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

The Zephyr kernel supports multiple architectures, including:

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

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

1.1 Licensing

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

1.2 Distinguishing Features

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

Extensive suite of Kernel services

Zephyr offers a number of familiar services for development:

- Multi-threading Services for cooperative, priority-based, non-preemptive, and preemptive threads with optional round robin time-slicing. Includes POSIX pthreads compatible API support.
- Interrupt Services for compile-time registration of interrupt handlers.
• Memory Allocation Services for dynamic allocation and freeing of fixed-size or variable-size memory blocks.

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

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

• Power Management Services such as tickless idle and an advanced idling infrastructure.

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

• Cooperative and Preemptive Scheduling

• Earliest Deadline First (EDF)

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

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

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

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

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

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

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

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

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

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

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

Bluetooth Low Energy 5.0 support
Bluetooth 5.0 compliant (ESR10) and Bluetooth Low Energy Controller support (LE Link Layer). Includes Bluetooth mesh and a Bluetooth qualification-ready Bluetooth controller.
• Generic Access Profile (GAP) with all possible LE roles.
• GATT (Generic Attribute Profile)
• Pairing support, including the Secure Connections feature from Bluetooth 4.2
• Clean HCI driver abstraction
• Raw HCI interface to run Zephyr as a Controller instead of a full Host stack
• Verified with multiple popular controllers
• Highly configurable

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

Native Linux, macOS, and Windows Development
A command-line CMake build environment runs on popular developer OS systems. A native POSIX port, lets you build and run Zephyr as a native application on Linux and other OSes, aiding development and testing.

Virtual File System Interface with LittleFS and FATFS Support
LittleFS and FATFS Support, FCB (Flash Circular Buffer) for memory constrained applications, and file system enhancements for logging and configuration.

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

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

Settings on non-volatile storage
The settings subsystem gives modules a way to store persistent per-device configuration and run-time state. Settings items are stored as key-value pair strings.

Non-volatile storage (NVS)
NVS allows storage of binary blobs, strings, integers, longs, and any combination of these.

Native POSIX port
Supports running Zephyr as a Linux application with support for various subsystems and networking.

1.3 Community Support

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

1.4 Resources

Here's a quick summary of resources to help you find your way around:
• Help: Asking for Help Tips
• Documentation: http://docs.zephyrproject.org (Getting Started Guide)
1.5 Fundamental Terms and Concepts

See glossary
Chapter 2

Developing with Zephyr

2.1 Getting Started Guide

Follow this guide to:

• Set up a command-line Zephyr development environment on Ubuntu, macOS, or Windows (instructions for other Linux distributions are discussed in Install Linux Host Dependencies)

• Get the source code

• Build, flash, and run a sample application

2.1.1 Select and Update OS

Click the operating system you are using.

Ubuntu

This guide covers Ubuntu version 18.04 LTS and later.

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

macOS

On macOS Mojave or later, select System Preferences > Software Update. Click Update Now if necessary.

On other versions, see this Apple support topic.

Windows

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

2.1.2 Install dependencies

Next, you’ll install some host dependencies using your package manager.

The current minimum required version for the main dependencies are:

<table>
<thead>
<tr>
<th>Tool</th>
<th>Min. Version</th>
</tr>
</thead>
<tbody>
<tr>
<td>CMake</td>
<td>3.20.0</td>
</tr>
<tr>
<td>Python</td>
<td>3.8</td>
</tr>
<tr>
<td>Devicetree compiler</td>
<td>1.4.6</td>
</tr>
</tbody>
</table>
Ubuntu

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

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

2. Use apt to install the required dependencies:

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

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

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

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

macOS

1. Install Homebrew:

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

2. Use brew to install the required dependencies:

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

Windows

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

These instructions must be run in a `cmd.exe` command prompt. The required commands differ on PowerShell.

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

1. Install chocolatey.

2. Open a `cmd.exe` window as Administrator. To do so, press the Windows key, type “cmd.exe”, right-click the result, and choose Run as Administrator.

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

   `choco feature enable -n allowGlobalConfirmation`

4. Use choco to install the required dependencies:
5. Close the window and open a new cmd.exe window as a regular user to continue.

### 2.1.3 Get Zephyr and install Python dependencies

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

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

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

**Ubuntu**

Install within virtual environment

1. Use apt to install Python venv package:
   ```bash
   sudo apt install python3-venv
   ```

2. Create a new virtual environment:
   ```bash
   python3 -m venv ~/zephyrproject/.venv
   ```

3. Activate the virtual environment:
   ```bash
   source ~/zephyrproject/.venv/bin/activate
   ```
   Once activated your shell will be prefixed with (.venv). The virtual environment can be deactivated at any time by running deactivate.

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

4. Install west:
   ```bash
   pip install west
   ```

5. Get the Zephyr source code:
   ```bash
   west init ~/zephyrproject
cd ~/zephyrproject
west update
   ```

6. Export a Zephyr CMake package. This allows CMake to automatically load boilerplate code required for building Zephyr applications.
   ```bash
   west zephyr-export
   ```

7. Zephyr's scripts/requirements.txt file declares additional Python dependencies. Install them with pip.
   ```bash
   pip install -r ~/zephyrproject/zephyr/scripts/requirements.txt
   ```

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

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

2. Get the Zephyr source code:

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

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

   ```bash
   west zephyr-export
   ```

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

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

**macOS**

Install within virtual environment

1. Create a new virtual environment:

   ```bash
   python3 -m venv ~/zephyrproject/.venv
   ```

2. Activate the virtual environment:

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

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

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

3. Install west:

   ```bash
   pip install west
   ```

4. Get the Zephyr source code:

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

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

   ```bash
   west zephyr-export
   ```

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

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

Install globally
1. Install west:

   pip3 install -U west

2. Get the Zephyr source code:

   west init ~/zephyrproject
   cd ~/zephyrproject
   west update

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

   west zephyr-export

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

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

**Windows**

Install within virtual environment

1. Create a new virtual environment:

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

2. Activate the virtual environment:

   :: cmd.exe
   zephyrproject\.venv\Scripts\activate.bat
   :: PowerShell
   zephyrproject\.venv\Scripts\Activate.ps1

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

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

3. Install west:

   pip install west

4. Get the Zephyr source code:

   west init zephyrproject
   cd zephyrproject
   west update

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

   west zephyr-export

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

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

1. Install west:
   
   ```bash
   pip3 install -U west
   ```

2. Get the Zephyr source code:

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

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

   ```bash
   west zephyr-export
   ```

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

   ```bash
   pip3 install -r %HOMEPATH%\zephyrproject\zephyr\scripts\requirements.txt
   ```

### 2.1.4 Install Zephyr SDK

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

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

#### Ubuntu

1. Download and verify the latest Zephyr SDK bundle:

   ```bash
   cd ~
   wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/zephyr-sdk-0.15.2_linux-x86_64.tar.gz
   wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/\sha256.sum | shasum --check --ignore-missing
   ```

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

2. Extract the Zephyr SDK bundle archive:

   ```bash
   tar xvf zephyr-sdk-0.15.2_linux-x86_64.tar.gz
   ```

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

- `$HOME`
- `$HOME/.local`
- `$HOME/.local/opt`
- `$HOME/bin`
- `/opt`
- `/usr/local`
The Zephyr SDK bundle archive contains the zephyr-sdk-0.15.2 directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-0.15.2.

3. Run the Zephyr SDK bundle setup script:

```bash
cd zephyr-sdk-0.15.2
./setup.sh
```

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

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

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

```bash
sudo cp ~/zephyr-sdk-0.15.2/sysroots/x86_64-pokysdk-linux/usr/share/openocd/
   \---contrib/60-openocd.rules /etc/udev/rules.d
sudo udevadm control --reload
```

**macOS**

1. Download and verify the latest Zephyr SDK bundle:

```bash
cd ~
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/
   \---zephyr-sdk-0.15.2_macos-x86_64.tar.gz
wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/
   \---sha256.sum | shasum --check --ignore-missing
```

If your host architecture is 64-bit ARM (Apple Silicon, also known as M1), replace x86_64 with aarch64 in order to download the 64-bit ARM macOS SDK.

2. Extract the Zephyr SDK bundle archive:

```bash
tar xvf zephyr-sdk-0.15.2_macos-x86_64.tar.gz
```

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

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

The Zephyr SDK bundle archive contains the zephyr-sdk-0.15.2 directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-0.15.2.

3. Run the Zephyr SDK bundle setup script:

```bash
cd zephyr-sdk-0.15.2
./setup.sh
```

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

Windows

1. Open a `cmd.exe` window by pressing the Windows key typing “cmd.exe”.
2. Download the latest Zephyr SDK bundle:

   ```bash
   cd %HOMEPATH%
   wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/zephyr-sdk-0.15.2_windows-x86_64.zip
   ```

3. Extract the Zephyr SDK bundle archive:

   ```bash
   unzip zephyr-sdk-0.15.2_windows-x86_64.zip
   ```

   **Note:** It is recommended to extract the Zephyr SDK bundle at one of the following locations:
   - `%HOMEPATH%`
   - `%PROGRAMFILES%`

   The Zephyr SDK bundle archive contains the `zephyr-sdk-0.15.2` directory and, when extracted under `%HOMEPATH%`, the resulting installation path will be `%HOMEPATH%\zephyr-sdk-0.15.2`.

4. Run the Zephyr SDK bundle setup script:

   ```bash
   cd zephyr-sdk-0.15.2
   setup.cmd
   ```

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

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

### 2.1.5 Build the Blinky Sample

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

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

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

**Ubuntu**

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

**macOS**

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

**Windows**

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

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

### 2.1.6 Flash the Sample

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

Then flash the sample using `west flash`:

```bash
west flash
```

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

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

![Fig. 2.1: Phytec reel_board running blinky](image)

### 2.1.7 Next Steps

Here are some next steps for exploring Zephyr:

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

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

Double Check the Zephyr SDK Variables When Updating

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

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

2.1.9 Asking for Help

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

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

How to Ask

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

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

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

Use Copy/Paste

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

Doing this makes it easier for people to help you, and also helps other users search the archives.

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

2.2 Beyond the Getting Started Guide

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

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

Depending on your operating system, you may need to provide the --user flag to the pip3 command when installing new packages. This is documented throughout the instructions. See Installing Packages in the Python Packaging User Guide for more information about pip\(^1\), including information on --user.

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

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

2.2.2 Advanced Platform Setup

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

Install Linux Host Dependencies

Documentation is available for these Linux distributions:

- Ubuntu
- Fedora
- Clear Linux
- Arch Linux

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

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

Update Your Operating System

Ensure your host system is up to date.

Ubuntu

---

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

\(^2\) The package versions requested by Zephyr’s requirements.txt may conflict with other requirements on your system, in which case you may want to set up a virtualenv for Zephyr development.
Install Requirements and Dependencies  Note that both Ninja and Make are installed with these instructions; you only need one.

Ubuntu

```bash
sudo apt-get install --no-install-recommends git cmake ninja-build gperf \
   ccache dfu-util device-tree-compiler wget \
   python3-dev python3-pip python3-setuptools python3-tk python3-wheel xz-utils file␣
   → libpython3.8-dev \
   make gcc gcc-multilib g++-multilib libstdc++ libmagic1
```

Fedora

```bash
sudo dnf group install "Development Tools" "C Development Tools and Libraries"
sudo dnf install git cmake ninja-build gperf ccache dfu-util dtc wget \
   python3-pip python3-tkinter xz file glibc-devel.i686 libstdc++-devel.i686 python38 \
   SDL2-devel
```

Clear Linux

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

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

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

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

Arch Linux

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

CMake  A recent CMake version is required. Check what version you have by using cmake --version. If you have an older version, there are several ways of obtaining a more recent one:
• On Ubuntu, you can follow the instructions for adding the kitware third-party apt repository to get an updated version of cmake using apt.

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

```
cd ~
wget https://github.com/Kitware/CMake/releases/download/v3.21.1/cmake-3.21.1-˓
  --Linux-x86_64.sh
chmod +x cmake-3.21.1-Linux-x86_64.sh
sudo ./cmake-3.21.1-Linux-x86_64.sh --skip-license --prefix=/usr/local
hash -r
```

The `hash -r` command may be necessary if the installation script put cmake into a new location on your PATH.

• Download and install from the pre-built binaries provided by the CMake project itself in the CMake Downloads page. For example, to install version 3.21.1 in `~/bin/cmake`:

```
mkdir $HOME/bin/cmake & cd $HOME/bin/cmake
wget https://github.com/Kitware/CMake/releases/download/v3.21.1/cmake-3.21.1-˓
  --Linux-x86_64.sh
yes | sh cmake-3.21.1-Linux-x86_64.sh | cat
echo "export PATH=$PWD/cmake-3.21.1-Linux-x86_64/bin:\$PATH" >> $HOME/.zephyrrc
```

• Use `pip3`:

```
pip3 install --user cmake
```

Note this won’t uninstall the previous version of cmake and will install the new cmake into your `~/local/bin` folder so you’ll need to add `~/local/bin` to your PATH. (See Python and pip for details.)

• Check your distribution’s beta or unstable release package library for an update.

• On Ubuntu you can also use snap to get the latest version available:

```
sudo snap install cmake
```

After updating cmake, verify that the newly installed cmake is found using `cmake --version`. You might also want to uninstall the CMake provided by your package manager to avoid conflicts. (Use `whereis cmake` to find other installed versions.)

**DTC (Device Tree Compiler)** A recent DTC version is required. Check what version you have by using `dtc --version`. If you have an older version, either install a more recent one by building from source, or use the one that is bundled in the Zephyr SDK by installing it.

**Python** A modern Python 3 version is required. Check what version you have by using `python3 --version`. If you have an older version, you will need to install a more recent Python 3. You can build from source, or use a backport from your distribution’s package manager channels if one is available. Isolating this Python in a virtual environment is recommended to avoid interfering with your system Python.

**Install the Zephyr Software Development Kit (SDK)** The Zephyr Software Development Kit (SDK) contains toolchains for each of Zephyr’s supported architectures. It also includes additional host tools, such as custom QEMU and OpenOCD.

Use of the Zephyr SDK is highly recommended and may even be required under certain conditions (for example, running tests in QEMU for some architectures).
The Zephyr SDK supports the following target architectures:

- ARC (32-bit and 64-bit; ARCv1, ARCv2, ARCv3)
- ARM (32-bit and 64-bit; ARMv6, ARMv7, ARMv8; A/R/M Profiles)
- MIPS (32-bit and 64-bit)
- Nios II
- RISC-V (32-bit and 64-bit; RV32I, RV32E, RV64I)
- x86 (32-bit and 64-bit)
- Xtensa

Follow these steps to install the Zephyr SDK:

1. Download and verify the latest Zephyr SDK bundle:

   ```bash
   wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/
   → zephyr-sdk-0.15.2_linux-x86_64.tar.gz
   get -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/
   → sha256.sum | shasum --check --ignore-missing
   ```

   You can change 0.15.2 to another version if needed; the Zephyr SDK Releases page contains all available SDK releases.

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

2. Extract the Zephyr SDK bundle archive:

   ```bash
   cd <sdk download directory>
   tar xvf zephyr-sdk-0.15.2_linux-x86_64.tar.gz
   ```

3. Run the Zephyr SDK bundle setup script:

   ```bash
   cd zephyr-sdk-0.15.2
   ./setup.sh
   ```

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

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

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

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

The Zephyr SDK bundle archive contains the zephyr-sdk-0.15.2 directory and, when extracted under `$HOME`, the resulting installation path will be `$HOME/zephyr-sdk-0.15.2`.

If you install the Zephyr SDK outside any of these locations, you must register the Zephyr SDK in the CMake package registry by running the setup script, or set `ZEPHYR_SDK_INSTALL_DIR` to point to the Zephyr SDK installation directory.
You can also use `ZEPHYR_SDK_INSTALL_DIR` for pointing to a directory containing multiple Zephyr SDKs, allowing for automatic toolchain selection. For example, `ZEPHYR_SDK_INSTALL_DIR=/company/tools`, where the `company/tools` folder contains the following subfolders:

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

This allows the Zephyr build system to choose the correct version of the SDK, while allowing multiple Zephyr SDKs to be grouped together at a specific path.

**Building on Linux without the Zephyr SDK**  
The Zephyr SDK is provided for convenience and ease of use. It provides toolchains for all Zephyr target architectures, and does not require any extra flags when building applications or running tests. In addition to cross-compilers, the Zephyr SDK also provides pre-built host tools. It is, however, possible to build without the SDK's toolchain by using another toolchain as described in the [Toolchains](#) section.

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

To make sure this variable is unset, run:

```
unset ZEPHYR_SDK_INSTALL_DIR
```

**macOS alternative setup instructions**

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

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

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

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

**Windows alternative setup instructions**

**Windows 10 WSL (Windows Subsystem for Linux)**  
If you are running a recent version of Windows 10 you can make use of the built-in functionality to natively run Ubuntu binaries directly on a standard command-prompt. This allows you to use software such as the Zephyr SDK without setting up a virtual machine.
Warning: Windows 10 version 1803 has an issue that will cause CMake to not work properly and is fixed in version 1809 (and later). More information can be found in Zephyr Issue 10420.

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

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

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

2.2.3 Install a Toolchain

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

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

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

2.2.4 Updating the Zephyr SDK toolchain

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

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

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

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

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

2.2.5 Cloning the Zephyr Repositories

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

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

The `west update` command fetches and keeps *Modules (External projects)* in the `zephyrproject` folder in sync with the code in the local `zephyr` repo.

**Warning:** You must run `west update` any time the `zephyr/west.yml` changes, caused, for example, when you pull the `zephyr` repository, switch branches in it, or perform a `git bisect` inside of it.

### Keeping Zephyr updated

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

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

#### 2.2.6 Export Zephyr CMake package

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

#### 2.2.7 Board Aliases

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

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

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

#### 2.2.8 Build and Run an Application

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

**Build Blinky**

Let's build the blinky-sample sample application.
Zephyr applications are built to run on specific hardware, called a “board”. We’ll use the Phytec reel_board here, but you can change the reel_board build target to another value if you have a different board. See boards or run west boards from anywhere inside the zephyrproject directory for a list of supported boards.

1. Go to the zephyr repository:
   ```
   cd zephyrproject/zephyr
   ```

2. Build the blinky sample for the reel_board:
   ```
   west build -b reel_board samples/basic/blinky
   ```

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

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

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

### Run the Application by Flashing to a Board

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

See [Run an Application](run-an-application-overview) and your specific board’s documentation in boards for additional details.

### Setting udev rules

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

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

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

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

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

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

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

---

2 This has become something of a misnomer over time. While the target can be, and often is, a microprocessor running on its own dedicated hardware board, Zephyr also supports using QEMU to run targets built for other architectures in emulation, targets which produce native host system binaries that implement Zephyr’s driver interfaces with POSIX APIs, and even running different Zephyr-based binaries on CPU cores of differing architectures on the same physical chip. Each of these hardware configurations is called a “board,” even though that doesn’t always make perfect sense in context.
Then, in either case, ask the udev daemon to reload these rules:

```
sudo udevadm control --reload
```

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

### Run the Application in QEMU

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

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

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

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

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

### Run a Sample Application natively (POSIX OS)

You can compile some samples to run as host processes on a POSIX OS. This is currently only tested on Linux hosts. See `native_posix` for more information. On 64-bit host operating systems, you need to install a 32-bit C library; see `native_posix_deps` for details.

First, build Hello World for `native_posix`.

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

Next, run the application.

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

Press Ctrl-C to exit.

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

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

### 2.3 Environment Variables

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

#### 2.3.1 Setting Variables
Option 1: Just Once

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

**Linux/macOS**

```bash
export MY_VARIABLE=foo
```

**Windows**

```cmd
set MY_VARIABLE=foo
```

**Warning:** This is best for experimentation. If you close your terminal window, use another terminal window or tab, restart your computer, etc., this setting will be lost forever.

Using options 2 or 3 is recommended if you want to keep using the setting.

Option 2: In all Terminals

**Linux/macOS**

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

**Windows**

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

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

```cmd
setx MY_VARIABLE foo
```

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

```bash
choco install rapidee
```

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

Option 3: Using `zephyr.rc` files

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

**Linux/macOS**

Create a file named `~/.zephyr.rc` if it doesn't exist, then add this line to it:

```bash
export MY_VARIABLE=foo
```

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

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

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

To get this value back into your current terminal environment, **you must run** `zephyr-env.cmd` in a `cmd.exe` window after changing directory to the main zephyr repository. Among other things, this script runs `%userprofile%\zephyrrc.cmd`. The value will be lost if you close the window, etc.; run `zephyr-env.cmd` again to get it back.

These scripts:

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

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

### 2.3.2 Zephyr Environment Scripts

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

**Linux/macOS**

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

**Windows**

```
zephyr-env.cmd
```

These scripts:

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

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

### 2.3.3 Important Environment Variables

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

- **BOARD**
  
  See Important Build System Variables.

- **CONF_FILE**
  
  See Important Build System Variables.

- **SHIELD**
  
  See Shields.

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

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

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

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

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

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

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

## 2.4 Application Development

**Note:** In this document, we'll assume your application directory is `<home>/app`, and that its build directory is `<home>/app/build`. (These terms are defined in the following Overview.) On Linux/macOS, `<home>` is equivalent to `~`, whereas on Windows it's `%userprofile%`.

### 2.4.1 Overview

Zephyr's build system is based on CMake.

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

Zephyr's base directory hosts Zephyr's own source code, its kernel configuration options, and its build definitions.

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

An application in its simplest form has the following contents:
These contents are:

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

- **Kernel configuration files**: An application typically provides a Kconfig configuration file (usually called `prj.conf`) that specifies application-specific values for one or more kernel configuration options. These application settings are merged with board-specific settings to produce a kernel configuration. See [Kconfig Configuration](#) below for more information.

- **Application source code files**: An application typically provides one or more application-specific files, written in C or assembly language. These files are usually located in a sub-directory called `src`.

Once an application has been defined, you can use CMake to create project files for building it from a directory where you want to host these files. This is known as the **build directory**. Application build artifacts are always generated in a build directory; Zephyr does not support “in-tree” builds.

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

### 2.4.2 Application types

Based on where the source code of the application is located we can distinguish between three basic application types.

- Zephyr repository application
- Zephyr workspace application
- Zephyr freestanding application

You can find out more about how the build system supports all the application types described in this section in the [Zephyr CMake Package](#) section.

#### Zephyr repository application

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

An application located within a workspace, but outside the Zephyr repository (and thus folder) itself, is referred to as a Zephyr workspace application. In the following example, `app` is a Zephyr workspace application:

```
zephyrproject/
  .west/
    config
  zephyr/
  bootloader/
  modules/
  tools/
  <vendor/private-repositories>/
  applications/
    app/
```

Zephyr freestanding application

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

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

2.4.3 Example workspace application

A reference workspace application contained in its own Git repository can be found in the Example Application repository. It can be used as a reference on how to structure out-of-tree, Zephyr-based workspace applications using the T2 star topology. It also demonstrates the out-of-tree use of features commonly used in applications such as:

- Custom boards
- Custom devicetree bindings
- Custom drivers
- Continuous Integration (CI) setup
• An example west extension command

## 2.4.4 Creating an Application

Follow these steps to create a new application directory. (Refer to the Example Application repository for a reference standalone application in its own Git repository or to samples-and-demos for existing applications provided as part of Zephyr.)

1. Create an application directory on your workstation computer, outside of the Zephyr base directory. Usually you’ll want to create it somewhere under your user’s home directory.

   For example, in a Unix shell or Windows cmd.exe prompt, navigate to where you want to create your application, then enter:

   ```bash
   mkdir app
   ```

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

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

   Continuing the previous example, enter:

   ```bash
   cd app
   mkdir src
   ```

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

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

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

   `cmake_minimum_required()` is required to be in your `CMakeLists.txt` by CMake. It is also invoked by the Zephyr package. The most recent of the two versions will be enforced by CMake.

   `find_package(Zephyr)` pulls in the Zephyr build system, which creates a CMake target named `app` (see Zephyr CMake Package). Adding sources to this target is how you include them in the build. The Zephyr package will define `Zephyr-Kernel` as a CMake project and enable support for the C, CXX, ASM languages.

   `project(my_zephyr_app)` is required for defining your application project. This must be called after `find_package(Zephyr)` to avoid interference with Zephyr's `project(Zephyr-Kernel)`.

   `target_sources(app PRIVATE src/main.c)` is to add your source file to the `app` target. This must come after `find_package(Zephyr)` which defines the target.

5. Set Kconfig configuration options. See Kconfig Configuration.

6. Configure any devicetree overlays needed by your application. See Set devicetree overlays.
2.4.5 Important Build System Variables

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

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

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

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

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

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

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

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

- SHIELD: see Shields

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

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

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

2.4.6 Application CMakeLists.txt

Every application must have a CMakeLists.txt file. This file is the entry point, or top level, of the build system. The final zephyr.elf image contains both the application and the kernel libraries.
This section describes some of what you can do in your CMakeLists.txt. Make sure to follow these steps in order:

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

```
set(BOARD qemu_x86)
```

Refer to boards for more information on available boards.

The Zephyr build system determines a value for BOARD by checking the following, in order (when a BOARD value is found, CMake stops looking further down the list):

- Any previously used value as determined by the CMake cache takes highest precedence. This ensures you don't try to run a build with a different BOARD value than you set during the build configuration step.
- Any value given on the CMake command line (directly or indirectly via west build) using `-DBOARD=YOUR_BOARD` will be checked for and used next.
- If an environment variable BOARD is set, its value will then be used.
- Finally, if you set BOARD in your application CMakeLists.txt as described in this step, this value will be used.

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

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

See The Initial Configuration for more information.

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

4. If your application has its own kernel configuration options, create a Kconfig file in the same directory as your application's CMakeLists.txt.

   See the Kconfig section of the manual for detailed Kconfig documentation.

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

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

Structure your Kconfig file like this:

```
# SPDX-License-Identifier: Apache-2.0

mainmenu "Your Application Name"

# Your application configuration options go here

# Sources Kconfig.zephyr in the Zephyr root directory.
#
# Note: All 'source' statements work relative to the Zephyr root directory (due
# to the $srctree environment variable being set to $ZEPHYR_BASE). If you want
# to 'source' relative to the current Kconfig file instead, use 'rsource' (or a
# path relative to the Zephyr root).
source "Kconfig.zephyr"
```
Note: Environment variables in source statements are expanded directly, so you do not need to define an option env="ZEPHYR_BASE" Kconfig "bounce" symbol. If you use such a symbol, it must have the same name as the environment variable.

See Kconfig extensions for more information.

The Kconfig file is automatically detected when placed in the application directory, but it is also possible for it to be found elsewhere if the CMake variable KCONFIG_ROOT is set with an absolute path.

5. Specify that the application requires Zephyr on a new line, after any lines added from the steps above:

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

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

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

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

Below is a simple example CMakeList.txt:

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

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

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

### 2.4.7 CMakeCache.txt

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

For more details about the CMakeCache.txt file see the official CMake documentation runningcmake.

### 2.4.8 Application Configuration
Application Configuration Directory

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

The application configuration directory is defined by the APPLICATION_CONFIG_DIR variable. APPLICATION_CONFIG_DIR will be set by one of the sources below with the highest priority listed first.

1. If APPLICATION_CONFIG_DIR is specified by the user with -DAPPLICATION_CONFIG_DIR=<path> or in a CMake file before find_package(Zephyr) then this folder is used as the application's configuration directory.
2. The application's source directory.

Kconfig Configuration

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

```
CONFIG_CPLUSPLUS=y
```

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

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

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

2.4.9 Experimental features

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

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

```
CONFIG_WARN_EXPERIMENTAL=y
```

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

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

Devicetree Overlays

See Set devicetree overlays.

2.4.10 Application-Specific Code

Application-specific source code files are normally added to the application's src directory. If the application adds a large number of files the developer can group them into sub-directories under src, to whatever depth is needed.
Application-specific source code should not use symbol name prefixes that have been reserved by the kernel for its own use. For more information, see Naming Conventions.

Third-party Library Code

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

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

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

- CMAKE_C_COMPILER, CMAKE_AR.
- ARCH and BOARD, together with several variables that identify the Zephyr kernel version.

samples/application_development/external_lib is a sample project that demonstrates some of these features.

2.4.11 Building an Application

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

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

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

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

Using west:

west build -b reel_board samples/hello_world

Using CMake and ninja:

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

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

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

Using west:

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

- to use `make` by default from now on, run `west config build.generator "Unix Makefiles"`

### Using CMake directly:

```bash
# Use cmake to configure a Make-based build system:
cmake -B build -DBOARD=reel_board samples/hello_world

# Now run ninja on the generated build system:
make -C build
```

### Basics

**Note:** In the below example, west is used outside of a west workspace. For this to work, you must set the ZEPHYR_BASE environment variable to the path of your zephyr git repository, using one of the methods on the Environment Variables page.

1. Navigate to the application directory `<home>/app`.
2. Enter the following commands to build the application’s `zephyr.elf` image for the board specified in the command-line parameters:

   - **Using west:**
     ```
     west build -b <board>
     ```

   - **Using CMake and ninja:**
     ```
     mkdir build & cd build
     # Use cmake to configure a Ninja-based build system:
     cmake -GNinja -DBOARD=<board> ..
     # Now run ninja on the generated build system:
     ninja
     ```

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

   - **Using west:**
     ```
     west build -b <board> -- -DCONF_FILE=prj.alternate.conf
     ```

   - **Using CMake and ninja:**
     ```
     mkdir build & cd build
     cmake -GNinja -DBOARD=<board> -DCONF_FILE=prj.alternate.conf ..
     ninja
     ```

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

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

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

The most notable files in the build directory are:

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

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

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

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

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

Rebuilding an Application

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

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

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

1. Open a terminal console on your host computer, and navigate to the build directory `<home>/app/build`.
2. Enter one of the following commands, depending on whether you want to use `west` or `cmake` directly to delete the application's generated files, except for the `.config` file that contains the application's current configuration information.

   ```bash
   west build -t clean
   ```

   or

   ```bash
   cmake --build . --target clean
   ```
ninja clean

Alternatively, enter one of the following commands to delete all generated files, including the .config files that contain the application’s current configuration information for those board types.

west build -t pristine

or

ninja pristine

If you use west, you can take advantage of its capability to automatically make the build folder pristine whenever it is required.

3. Rebuild the application normally following the steps specified in Building an Application above.

Building for a board revision

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

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

Using west:

west build -b <board>@<revision>

Using CMake and ninja:

mkdir build && cd build

cmake -GNinja -DBOARD=<board>@<revision> ..
ninja

Check your board's documentation for details on whether it has multiple revisions, and what revisions are supported.

When targeting a board revision, the active revision will be printed at CMake configure time, like this:

-- Board: plank, Revision: 1.5.0

2.4.12 Run an Application

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

Running on a Board

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

1. Build your application, as described in Building an Application.

2. Make sure your board is attached to your host computer. Usually, you’ll do this via USB.

3. Run one of these console commands from the build directory, <home>/app/build, to flash the compiled Zephyr image and run it on your board:

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

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

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

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

Running in an Emulator

The kernel has built-in emulator support for QEMU (on Linux/macOS only, this is not yet supported on Windows). It allows you to run and test an application virtually, before (or in lieu of) loading and running it on actual target hardware. Follow these instructions to run an application via QEMU:

1. Build your application for one of the QEMU boards, as described in Building an Application.

   For example, you could set BOARD to:

   • qemu_x86 to emulate running on an x86-based board
   • qemu_cortex_m3 to emulate running on an ARM Cortex M3-based board

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

   west build -t run

   or

   ninja run

3. Press Ctrl A, X to stop the application from running in QEMU.

   The application stops running and the terminal console prompt redisplays.

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

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

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

2.4.13 Application Debugging

This section is a quick hands-on reference to start debugging your application with QEMU. Most content in this section is already covered in QEMU and GNU_Debugger reference manuals.
In this quick reference, you'll find shortcuts, specific environmental variables, and parameters that can help you to quickly set up your debugging environment.

The simplest way to debug an application running in QEMU is using the GNU Debugger and setting a local GDB server in your development system through QEMU.

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

We will use the standard 1234 TCP port to open a GDB (GNU Debugger) server instance. This port number can be changed for a port that best suits the development environment.

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

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

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

The options used above have the following meaning:

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

To debug with QEMU and to start a GDB server and wait for a remote connect, run either of the following inside the build directory of an application:

```
ninja debugserver
```

The build system will start a QEMU instance with the CPU halted at startup and with a GDB server instance listening at the TCP port 1234.

Using a local GDB configuration `.gdbinit` can help initialize your GDB instance on every run. In this example, the initialization file points to the GDB server instance. It configures a connection to a remote target at the local host on the TCP port 1234. The initialization sets the kernel's root directory as a reference.

The `.gdbinit` file contains the following lines:

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

**Note:** Substitute the correct `ZEPHYR_BASE` for your system.

Execute the application to debug from the same directory that you chose for the `.gdbinit` file. The command can include the `--tui` option to enable the use of a terminal user interface. The following commands connects to the GDB server using gdb. The command loads the symbol table from the elf binary file. In this example, the elf binary file name corresponds to `zephyr.elf` file:

```
....../path/to/gdb --tui zephyr.elf
```

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

If you are not using a `.gdbinit` file, issue the following command inside GDB to connect to the remote GDB server on port 1234:

```
(gdb) target remote localhost:1234
```
Finally, the command below connects to the GDB server using the Data Displayer Debugger (ddd). The command loads the symbol table from the elf binary file, in this instance, the zephyr.elf file.

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

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

Both commands execute the GDB (GNU Debugger). The command name might change depending on the toolchain you are using and your cross-development tools.

### 2.4.14 Custom Board, Devicetree and SOC Definitions

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

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

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

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

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

```
    boards
    └── x86
        └── my_custom_board
            └── doc
                └── img
            └── support
        └── src
```

and the `soc` directory hosts any SOC code. You can also have boards that are supported by a SOC that is available in the Zephyr tree.

#### Boards

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

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

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

```
my_custom_board_defconfig
my_custom_board.dts
my_custom_board.yaml
```

(continues on next page)
Once the board structure is in place, you can build your application targeting this board by specifying the location of your custom board information with the \texttt{-DBOARD\_ROOT} parameter to the CMake build system:

Using west:

\begin{verbatim}
west build -b <board name> -- -DBOARD\_ROOT=<path to boards>
\end{verbatim}

Using CMake and ninja:

\begin{verbatim}
cmake -Bbuild -GNinja -DBOARD=<board name> -DBOARD\_ROOT=<path to boards> .
ninja -Cbuild
\end{verbatim}

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

You can also define the \texttt{BOARD\_ROOT} variable in the application \texttt{CMakeLists.txt} file. Make sure to do so before pulling in the Zephyr boilerplate with \texttt{find\_package(Zephyr \ldots).}

\textbf{Note:} When specifying \texttt{BOARD\_ROOT} in a \texttt{CMakeLists.txt}, then an absolute path must be provided, for example \texttt{list(APPEND BOARD\_ROOT \{CMAKE\_CURRENT\_SOURCE\_DIR}/<extra-board-root>\}). When using \texttt{-DBOARD\_ROOT=<board-root>} both absolute and relative paths can be used. Relative paths are treated relatively to the application directory.

\section*{SOC Definitions}

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

\begin{verbatim}
soc
  \hspace{1cm} arm
    \hspace{1cm} st_stm32
      \hspace{1cm} common
      \hspace{1cm} stm32l0
\end{verbatim}

The file \texttt{soc/Kconfig} will create the top-level SoC/CPU/Configuration Selection menu in Kconfig.

Out of tree SoC definitions can be added to this menu using the \texttt{SOC\_ROOT} CMake variable. This variable contains a semicolon-separated list of directories which contain SoC support files.

Following the structure above, the following files can be added to load more SoCs into the menu.

\begin{verbatim}
soc
  \hspace{1cm} arm
    \hspace{1cm} st_stm32
      \hspace{1cm} Kconfig
      \hspace{1cm} Kconfig.soc
      \hspace{1cm} Kconfig.defconfig
\end{verbatim}
The Kconfig files above may describe the SoC or load additional SoC Kconfig files.

An example of loading stm31l0 specific Kconfig files in this structure:

```
soc
  ^ arm
    | st_stm32
      ^ Kconfig.soc
          stm32l0
      Kconfig.series
```

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

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

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

Using west:

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

Using CMake and ninja:

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

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

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

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

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

**Devicetree Definitions**

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

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

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

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

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

Using CMake and ninja:

cmake -Bbuild -GNinja -DBOARD=<board name> -DDTS_ROOT=<path to dts root> .
ninja -Cbuild

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

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

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

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

Using west:

west build -b <board name> -- -DDTS_EXTRA_CPPFLAGS=-DTEST_ENABLE_FEATURE

Using CMake and ninja:

cmake -Bbuild -GNinja -DBOARD=<board name> -DDTS_EXTRA_CPPFLAGS=-DTEST_ENABLE_FEATURE

ninja -Cbuild

2.4.15 Debug with Eclipse

Overview

CMake supports generating a project description file that can be imported into the Eclipse Integrated Development Environment (IDE) and used for graphical debugging.

The GNU MCU Eclipse plug-ins provide a mechanism to debug ARM projects in Eclipse with pyOCD, Segger J-Link, and OpenOCD debugging tools.

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

Set Up the Eclipse Development Environment

1. Download and install Eclipse IDE for C/C++ Developers.

2. In Eclipse, install the GNU MCU Eclipse plug-ins by opening the menu Window->Eclipse Marketplace..., searching for GNU MCU Eclipse, and clicking Install on the matching result.

3. Configure the path to the pyOCD GDB server by opening the menu Window->Preferences, navigating to MCU, and setting the Global pyOCD Path.
Generate and Import an Eclipse Project

1. Set up a GNU Arm Embedded toolchain as described in GNU Arm Embedded.

2. Navigate to a folder outside of the Zephyr tree to build your application.

   # On Windows
   cd %userprofile%

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

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

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

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

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

Create a Debugger Configuration

1. Open the menu Run->Debug Configurations....

2. Select GDB PyOCD Debugging, click the New button, and configure the following options:
   - In the Main tab:
     - Project: my_zephyr_app@build
     - C/C++ Application: zephyr/zephyr.elf
   - In the Debugger tab:
     - pyOCD Setup
       - Executable path: $pyocd_path$/pyocd_executable
       - Uncheck “Allocate console for semihosting”
     - Board Setup
       - Bus speed: 8000000 Hz
       - Uncheck “Enable semihosting”
     - GDB Client Setup
* Executable path example (use your GNUARMMB_TOOLCHAIN_PATH): C:\gcc-arm-none-eabi-6_2017-q2-update\bin\arm-none-eabi-gdb.exe

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

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

3. Click the Debug button to start debugging.

RTOS Awareness

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

2.5 API Status and Guidelines

2.5.1 API Overview

The table lists Zephyr’s APIs and information about them, including their current stability level. More details about API changes between major releases are available in the zephyr_release_notes.

<table>
<thead>
<tr>
<th>API</th>
<th>Status</th>
<th>Version Introduced</th>
</tr>
</thead>
<tbody>
<tr>
<td>ADC</td>
<td>Stable</td>
<td>1.0</td>
</tr>
<tr>
<td>Audio Codec</td>
<td>Experimental</td>
<td>1.13</td>
</tr>
<tr>
<td>Audio DMIC</td>
<td>Experimental</td>
<td>1.13</td>
</tr>
<tr>
<td>Bluetooth APIs</td>
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<td>1.0</td>
</tr>
<tr>
<td>Clock Control</td>
<td>Stable</td>
<td>1.0</td>
</tr>
<tr>
<td>CoAP</td>
<td>Unstable</td>
<td>1.10</td>
</tr>
<tr>
<td>CAN Controller</td>
<td>Unstable</td>
<td>1.14</td>
</tr>
<tr>
<td>Counter</td>
<td>Unstable</td>
<td>1.14</td>
</tr>
<tr>
<td>Crypto APIs</td>
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</tr>
<tr>
<td>DAC</td>
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<td>2.3</td>
</tr>
<tr>
<td>DAI</td>
<td>Experimental</td>
<td>3.1</td>
</tr>
<tr>
<td>DMA</td>
<td>Stable</td>
<td>1.5</td>
</tr>
<tr>
<td>Device Driver Model</td>
<td>Stable</td>
<td>1.0</td>
</tr>
<tr>
<td>Devicetree API</td>
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<td>Disk Access</td>
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</tr>
<tr>
<td>Display Interface</td>
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<td>EC Host Command</td>
<td>Experimental</td>
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</tr>
<tr>
<td>Error Detection And Correction (EDAC)</td>
<td>Experimental</td>
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<td>EEPROM</td>
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</tr>
<tr>
<td>Entropy</td>
<td>Stable</td>
<td>1.10</td>
</tr>
<tr>
<td>File Systems</td>
<td>Stable</td>
<td>1.5</td>
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<tr>
<td>Flash</td>
<td>Stable</td>
<td>1.2</td>
</tr>
<tr>
<td>Flash Circular Buffer (FCB)</td>
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</tr>
<tr>
<td>Fuel Gauges (Experimental API Stub Doc)</td>
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</tr>
<tr>
<td>Flash map</td>
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</tr>
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<td>GPIO</td>
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</table>

continues on next page
Table 2.1 – continued from previous page

<table>
<thead>
<tr>
<th>API</th>
<th>Status</th>
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<td>Stable</td>
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<td>IPM</td>
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<td>LoRa and LoRaWAN</td>
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<tr>
<td>LoRa and LoRaWAN</td>
<td>Experimental</td>
<td>2.5</td>
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<tr>
<td>Networking APIs</td>
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</tr>
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<td>Non-Volatile Storage (NVS)</td>
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</tr>
<tr>
<td>PECI</td>
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<td>Reset Controller</td>
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</tr>
<tr>
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<tr>
<td>Settings</td>
<td>Stable</td>
<td>1.12</td>
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<tr>
<td>TCPC</td>
<td>Experimental</td>
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<td>USB device support</td>
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<tr>
<td>USB-C device support</td>
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<tr>
<td>USB-C VBUS</td>
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<tr>
<td>Utilities</td>
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</tr>
<tr>
<td>Video</td>
<td>Stable</td>
<td>2.1</td>
</tr>
<tr>
<td>W1: Dallas 1-Wire Interface</td>
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<td>3.2</td>
</tr>
<tr>
<td>Watchdog</td>
<td>Stable</td>
<td>1.0</td>
</tr>
</tbody>
</table>

2.5.2 API Lifecycle

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

Fig. 2.2: API Life Cycle

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

**Experimental**

Experimental APIs denote that a feature was introduced recently, and may change or be removed in future versions. Try it out and provide feedback to the community via the Developer mailing list.

The following requirements apply to all new APIs:

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

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

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

**Unstable**

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

**Note:** Changes will not be announced.
Peripheral APIs (Hardware Related) The API shall be promoted from experimental to unstable when it has at least two implementations on different hardware platforms.

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

Stable

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

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

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

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

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

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

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

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

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

<table>
<thead>
<tr>
<th>Title: RFC: API Change: &lt;subsystem&gt;</th>
</tr>
</thead>
<tbody>
<tr>
<td>Contents:</td>
</tr>
<tr>
<td>- Problem Description:</td>
</tr>
<tr>
<td>- Background information on why</td>
</tr>
<tr>
<td>the change is required</td>
</tr>
<tr>
<td>- Proposed Change (detailed):</td>
</tr>
<tr>
<td>- Brief description of the API</td>
</tr>
<tr>
<td>change</td>
</tr>
<tr>
<td>- Detailed RFC:</td>
</tr>
<tr>
<td>- Function call changes</td>
</tr>
<tr>
<td>- Device Tree changes (source</td>
</tr>
<tr>
<td>and bindings)</td>
</tr>
<tr>
<td>- Kconfig option changes</td>
</tr>
<tr>
<td>- Dependencies:</td>
</tr>
<tr>
<td>- Impact to users of the API,</td>
</tr>
<tr>
<td>including the steps required</td>
</tr>
<tr>
<td>to adapt out-of-tree users of</td>
</tr>
<tr>
<td>the API to the change</td>
</tr>
</tbody>
</table>

   Instead of a written description of the changes, the RFC issue may link to a Pull Request containing those changes in code form.
2. The RFC issue must be labeled with the GitHub Stable API Change label
3. The RFC issue must be submitted for discussion in the next Zephyr Architecture meeting
4. An email must be sent to the devel mailing list with a subject identical to the RFC issue title and that links to the RFC issue

The RFC will then receive feedback through issue comments and will also be discussed in the Zephyr Architecture meeting, where the stakeholders and the community at large will have a chance to discuss it in detail.

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

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

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

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

**Note:** Incompatible changes will be announced in the “API Changes” section of the release notes.

---

**Deprecated**

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

The following are the requirements for deprecating an existing API:

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

- **What is required when deprecating:**
  - Mark as deprecated. This can be done by using the compiler itself (\_\_depre\_\_cated for function declarations and \_\_DEPRE\_\_CATED_MACR\_\_0 for macro definitions), or by introducing a Kconfig
option (typically one that contains the DEPRECATED word in it) that, when enabled, reverts the APIs back to their previous form

- Document the deprecation
- Include the deprecation in the “API Changes” of the release notes for the next upcoming release
- Code using the deprecated API needs to be modified to remove usage of said API
- The change needs to be atomic and bisectable
- Create a GitHub issue to track the removal of the deprecated API, and add it to the roadmap targeting the appropriate release (in the example above, 1.16).

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

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

Retired

In this phase, the API is removed.

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

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

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

2.5.3 API Design Guidelines

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

Using Callbacks

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

- The first parameter should be a pointer to the object most closely associated with the callback. In the case of device drivers this would be const struct device *dev. For library functions it may be a pointer to another object that was referenced when the callback was provided.
- The next parameter(s) should be additional information specific to the callback invocation, such as a channel identifier, new status value, and/or a message pointer followed by the message length.
- The final parameter should be a void *user_data pointer carrying context that allows a shared callback function to locate additional material necessary to process the callback.

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

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

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

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

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

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

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

Conditional Data and APIs

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

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

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

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

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

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

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

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

Return Codes

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

- APIs that are supported but not implemented shall return `-ENOSYS`. 

2.5. API Status and Guidelines
• Optional APIs that are not supported by the hardware should be implemented and the return code in this case shall be -ENOTSUP.

• When an API is implemented, but the particular combination of options requested in the call cannot be satisfied by the implementation the call shall return -ENOTSUP. (For example, a request for a level-triggered GPIO interrupt on hardware that supports only edge-triggered interrupts)

2.5.4 API Terminology

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

reschedule
  if executing the function reaches a reschedule point

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

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

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

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

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

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

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

reschedule

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

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

Note that in the case of timeslicing, or reschedule points executed from interrupts, any thread may be suspended in any function.

Functions that are not reschedule may be invoked from either thread or interrupt context.

Functions that are reschedule may be invoked from thread context.

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

sleep

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

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

Functions that are `sleep` are implicitly `reschedule`.

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

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

**no-wait**

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

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

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

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

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

**isr-ok**

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

**Explanation**  Any function that is not `sleep` is inherently `isr-ok`. Functions that are `sleep` are `isr-ok` if the implementation ensures that the documented behavior is implemented even if called from an interrupt context. This may be achieved by having the implementation detect the calling context and transfer the operation that would sleep to a thread, or by documenting that when invoked from a non-thread context the function will return a specific error (generally `-EWOULDBLOCK`).

Note that a function that is no-wait is safe to call from interrupt context only when the no-wait path is selected. `isr-ok` functions need not provide a no-wait path.

**pre-kernel-ok**

The pre-kernel-ok attribute is used on a function to indicate that it works as documented even when invoked before the kernel main thread has been started.
**Explanation**  This attribute is similar to **isr-ok** in function, but is intended for use by any API that is expected to be called in `DEVICE_DEFINE()` or `SYS_INIT()` calls that may be invoked with `PRE_KERNEL_1` or `PRE_KERNEL_2` initialization levels.

Generally a function that is **pre-kernel-ok** checks `k_is_pre_kernel()` when determining whether it can fulfill its required behavior. In many cases it would also check `k_is_in_isr()` so it can be **isr-ok** as well.

**async**

A function is **async** (i.e. asynchronous) if it may return before the operation it initiates has completed. An asynchronous function will generally provide a mechanism by which operation completion is reported, e.g. a callback or event.

A function that is not asynchronous is synchronous, i.e. the operation will always be complete when the function returns. As most functions are synchronous this behavior does not have a distinct attribute to identify it.

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

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

**supervisor**

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

## 2.6 Language Support

### 2.6.1 C Language Support

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

Zephyr is primarily written in C and natively supports applications written in the C language. All Zephyr API functions and macros are implemented in C and available as part of the C header files under the `include` directory, so writing Zephyr applications in C gives the developers access to the most features.

**Language Standards**

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

- inline functions
- standard boolean types (`stdbool.h`)
- fixed-width integer types (`stdint.h`)
- designated initializers
- variadic macros
- `restrict` qualification
Some Zephyr components make use of the features newly introduced in the 2011 release of the ISO C standard (ISO/IEC 9899:2011, hereinafter referred to as C11) such as the type-generic expressions using the _Generic keyword. For example, the cbprintf() component, used as the default formatted output processor for Zephyr, makes use of the C11 type-generic expressions, and this effectively requires most Zephyr applications to be compiled using a compiler toolchain that supports the C11 standard and above.

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

**Standard Library**

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

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

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

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

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

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

**Dynamic Memory Management**  Dynamic memory management in the minimal libc can be enabled by selecting the CONFIG_MINIMAL_LIBC_MALLOC in the application configuration file.

The minimal libc internally uses the kernel memory heap API to manage the memory heap used by the standard dynamic memory management interface functions such as malloc() and free().

The internal memory heap is normally located in the .bss section. When userspace is enabled, however, it is placed in a dedicated memory partition called z_malloc_partition, which can be accessed from the user mode threads. The size of the internal memory heap is specified by the CONFIG_MINIMAL_LIBC_MALLOC_ARENA_SIZE.

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

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

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

A conscious effort is made in Zephyr to keep the values of the minimal libc error numbers consistent with the different implementations of the C standard libraries supported by Zephyr. The minimal libc errno.h is checked against that of the Newlib to ensure that the error numbers are kept aligned.
Below is a list of the error number definitions. For the actual numeric values please refer to `errno.h`.

**group system_errno**

System error numbers Error codes returned by functions. Includes a list of those defined by IEEE Std 1003.1-2017.

**Defines**

**errno**

EPERM

Not owner

ENOENT

No such file or directory

ESRCH

No such context

EINTR

Interrupted system call

EIO

I/O error

ENXIO

No such device or address

E2BIG

Arg list too long

ENOEXEC

Exec format error

EBADF

Bad file number

ECHILD

No children

EAGAIN

No more contexts

ENOMEM

Not enough core

EACCES

Permission denied
EFAULT
   Bad address

ENOTBLK
   Block device required

EBUSY
   Mount device busy

EEXIST
   File exists

EXDEV
   Cross-device link

ENODEV
   No such device

ENOTDIR
   Not a directory

EISDIR
   Is a directory

EINVAL
   Invalid argument

ENFILE
   File table overflow

EMFILE
   Too many open files

ENOTTY
   Not a typewriter

ETXTBSY
   Text file busy

EBIG
   File too large

ENOSPC
   No space left on device

ESPIPE
   Illegal seek
EROFS
   Read-only file system

EMLINK
   Too many links

EPIPE
   Broken pipe

EDOM
   Argument too large

ERANGE
   Result too large

ENOMSG
   Unexpected message type

EDEADLK
   Resource deadlock avoided

ENOLCK
   No locks available

ENOSSR
   STREAMS device required

ENODATA
   Missing expected message data

ETIME
   STREAMS timeout occurred

ENOSR
   Insufficient memory

EPROTO
   Generic STREAMS error

EBADMSG
   Invalid STREAMS message

ENOSYS
   Function not implemented

ENOTEMPTY
   Directory not empty
ENAMETOOLONG
   File name too long

ELOOP
   Too many levels of symbolic links

EOPNOTSUPP
   Operation not supported on socket

EPFNOSUPPORT
   Protocol family not supported

ECONNRESET
   Connection reset by peer

ENOBUFS
   No buffer space available

EAFNOSUPPORT
   Addr family not supported

EPROTOTYPE
   Protocol wrong type for socket

ENOTSOCK
   Socket operation on non-socket

ENOPROTOOPT
   Protocol not available

ESHUTDOWN
   Can’t send after socket shutdown

ECONNREFUSED
   Connection refused

EADDRINUSE
   Address already in use

ECONNABORTED
   Software caused connection abort

ENETUNREACH
   Network is unreachable

ENETDOWN
   Network is down

2.6. Language Support
ETIMEDOUT
   Connection timed out

EHOSTDOWN
   Host is down

EHOSTUNREACH
   No route to host

EINPROGRESS
   Operation now in progress

EALREADY
   Operation already in progress

EDESTADDRREQ
   Destination address required

EMSGSIZE
   Message size

EPROTONOSUPPORT
   Protocol not supported

ESOCKTNOSUPPORT
   Socket type not supported

EADDRNOTAVAIL
   Can't assign requested address

ENETRESET
   Network dropped connection on reset

EISCONN
   Socket is already connected

ENOTCONN
   Socket is not connected

ETOOMANYREFS
   Too many references: can't splice

ENOTSUP
   Unsupported value

EILSEQ
   Illegal byte sequence
EOVERFLOW
Value overflow

ECANCELED
Operation canceled

EWOULDBLOCK
Operation would block

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

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

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

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

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

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

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

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

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

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

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

- Floating point format specifiers (e.g. %f) require CONFIG_NEWLIB_LIBC_FLOAT_PRINTF and CONFIG_NEWLIB_LIBC_FLOAT_SCANF to be enabled.
- C99 format specifiers are not supported in the Newlib nano variant (i.e. %hhX for char, %llX for long long, %jX for intmax_t, %zX for size_t, %tX for ptrdiff_t).
Dynamic Memory Management  Newlib implements an internal heap allocator to manage the memory blocks used by the standard dynamic memory management interface functions (for example, malloc() and free()).

The internal heap allocator implemented by the Newlib may vary across the different types of the Newlib used. For example, the heap allocator implemented in the Full Newlib (libc.a and libm.a) of the Zephyr SDK requests larger memory chunks to the operating system and has a significantly higher minimum memory requirement compared to that of the Nano Newlib (libc_nano.a and libm_nano.a).

The only interface between the Newlib dynamic memory management functions and the Zephyr-side libc hooks is the sbrk() function, which is used by the Newlib to manage the size of the memory pool reserved for its internal heap allocator.

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

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

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

- When MMU is enabled (CONFIG_MMU is selected), the amount of memory space reserved for the Newlib heap is set by the size of the free memory space returned by the k_mem_free_get() function or the CONFIG_NEWLIB_LIBC_MAX_MAPPED_REGION_SIZE, whichever is the smallest.
- When MPU is enabled and the MPU requires power-of-two partition size and address alignment (CONFIG_NEWLIB_LIBC_ALIGNED_HEAP_SIZE is set to a non-zero value), the amount of memory space reserved for the Newlib heap is set by the CONFIG_NEWLIB_LIBC_ALIGNED_HEAP_SIZE.
- Otherwise, the amount of memory space reserved for the Newlib heap is equal to the amount of free (unallocated) memory in the SRAM region.

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

Formatted Output

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

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

Dynamic Memory Management

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

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

- manage its own memory heap either internally or by invoking the hook functions (for example, sbrk()) implemented in libc-hooks.c.
- maintain the architecture- and memory region-specific alignment requirements for the memory blocks allocated by the standard dynamic memory allocation interface (for example, malloc()).
- allocate memory blocks inside the z_malloc_partition memory partition when userspace is enabled. See Pre-defined Memory Partitions.
For more details regarding the C standard library-specific memory management implementation, refer to each C standard library documentation.

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

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

### 2.6.2 C++ Language Support

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

#### Enabling C++ Support

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

To enable C++ support, the compiler toolchain must also include a C++ compiler and the included compiler must be supported by the Zephyr build system. The Zephyr SDK, which includes the GNU C++ Compiler (part of GCC), is supported by Zephyr, and the features and their availability documented here assume the use of the Zephyr SDK.

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

The C++ standard requires the `main()` function to have the return type of `int` while Zephyr uses `void` by default. If your `main()` is defined in a C++ source file, you must select `CONFIG_CPP_MAIN` in the application configuration file so that Zephyr uses `int main(void)` instead of `void main(void)`.

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

#### Language Features

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

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

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

- Inheritance
- Virtual functions
- Virtual tables
- Static global object constructors
- Dynamic object management with the `new` and `delete` operators
- Exceptions
- RTTI (runtime type information)
- Standard Template Library (STL)
Static global object constructors are initialized after the drivers are initialized but before the application main() function. Therefore, use of C++ is restricted to application code.

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

Zephyr C++ Subsystem

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

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

The scope of the C++ subsystem is strictly limited to providing the basic C++ language support, and it does not implement any Standard Template Library (STL) classes and functions. For this reason, it is only suitable for use in the applications that implement their own (non-standard) class library and do rely on the Standard Template Library (STL) components.

Any application that makes use of the Standard Template Library (STL) components, such as std::string and std::vector, must enable the C++ standard library support.

C++ Standard Library

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

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

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

To enable C++ standard library, select the CONFIG_LIB_CPLUSPLUS in the application configuration file.

2.7 Optimizations

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

2.7.1 Optimizing for Footprint

Stack Sizes

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

CONFIG_ISR_STACK_SIZE
Set to 2048 by default

CONFIG_MAIN_STACK_SIZE
Set to 1024 by default
CONFIG_IDLE_STACK_SIZE
Set to 320 by default

CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE
Set to 1024 by default

CONFIG_PRIVILEGED_STACK_SIZE
Set to 1024 by default, depends on userspace feature.

Unused Peripherals

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

CONFIG_GPIO=n
CONFIG_SPI=n

Various Debug/Informational Options

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

CONFIG_BOOT_BANNER
This option can be disabled to save a few bytes.

CONFIG_DEBUG
This option can be disabled for production builds

MPU/MMU Support

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

2.7.2 Optimization Tools

Footprint and Memory Usage

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

Tools that are available as build system targets:

Build Target: pncover  This target uses a 3rd party tools called pncover which can be found here. When this target is built, it will launch a local web server which will allow you to open a web client and browse the files and view their ROM, RAM and stack usage. Before you can use this target, you will have to install the pncover python module:

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

Then:

Using west:
west build -b reel_board samples/hello_world
west build -t puncover

Using CMake and ninja:

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

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

To view worst-case stack usage analysis, build this with the CONFIG_STACK_USAGE enabled.

Using west:

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

Using CMake and ninja:

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

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

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

Use the ram_report target with your board:

Using west:

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

Using CMake and ninja:

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

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

which will generate something similar to the output below:

```
Path                  Size  %  
--------------------- ----- ----

...                      ...     ...

SystemCoreClock         4     0.08%
_kernel                 48    0.99%
_sw_isr_table           384   7.94%
cli.10544
```

(continues on next page)
Build Target: `rom_report` List all compiled objects and their ROM usage in a tabular form with bytes per symbol and the percentage it uses. The data is grouped based on the file system location of the object in the tree and the file containing the symbol.

Use the `rom_report` to get the ROM report:

Using west:

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

Using CMake and ninja:
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=reel_board samples/hello_world

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

which will generate something similar to the output below:

<table>
<thead>
<tr>
<th>Path</th>
<th>Size %</th>
</tr>
</thead>
<tbody>
<tr>
<td>...</td>
<td></td>
</tr>
<tr>
<td>CSWITCH.5</td>
<td>0.02%</td>
</tr>
<tr>
<td>SystemCoreClock</td>
<td>0.02%</td>
</tr>
<tr>
<td>__aeabi_idiv0</td>
<td>0.01%</td>
</tr>
<tr>
<td>__udivmoddi4</td>
<td>3.37%</td>
</tr>
<tr>
<td>__sw_isr_table</td>
<td>1.85%</td>
</tr>
<tr>
<td>delay_machine_code.9114</td>
<td>0.03%</td>
</tr>
<tr>
<td>levels.8826</td>
<td>0.10%</td>
</tr>
<tr>
<td>mpu_config</td>
<td>0.04%</td>
</tr>
<tr>
<td>transitions.10558</td>
<td>0.06%</td>
</tr>
<tr>
<td>arch</td>
<td>5.74%</td>
</tr>
<tr>
<td>arch</td>
<td>5.74%</td>
</tr>
<tr>
<td>core</td>
<td>5.74%</td>
</tr>
<tr>
<td>arch32</td>
<td>5.74%</td>
</tr>
<tr>
<td>cortex_m</td>
<td>4.09%</td>
</tr>
<tr>
<td>fault.c</td>
<td>1.92%</td>
</tr>
<tr>
<td>bus_fault.isra.0</td>
<td>0.29%</td>
</tr>
<tr>
<td>mem_manage_fault.isra.0</td>
<td>0.27%</td>
</tr>
<tr>
<td>usage_fault.isra.0</td>
<td>0.17%</td>
</tr>
<tr>
<td>z_arm_fault</td>
<td>1.11%</td>
</tr>
<tr>
<td>z_arm_fault_init</td>
<td>0.08%</td>
</tr>
<tr>
<td>irq_init.c</td>
<td>0.12%</td>
</tr>
<tr>
<td>z_arm_interrupt_init</td>
<td>0.12%</td>
</tr>
</tbody>
</table>
Data Structures

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

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

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

or in fedora:

```
sudo dnf install dwarves
```

Using west:

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

Using CMake and ninja:

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

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

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

```
2.7. Optimizations
```
2.8 Flashing and Hardware Debugging

2.8.1 Flash & Debug Host Tools

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

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

SAM Boot Assistant (SAM-BA)

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

The typical command to flash the board is:

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

Flash configuration for devices:

With ROM bootloader
These devices don’t need any special configuration. After building your application, just run `west flash` to flash the board.

Without ROM bootloader

For these devices, the user should:

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

2. Have board `.defconfig` file with the `CONFIG_USE_DT_CODE_PARTITION` Kconfig option set to `y` to instruct the build system to use these partitions for code relocation. This option can also be set in `prj.conf` or any other Kconfig fragment.

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

With compatible SAM-BA bootloader

For these devices, the user should:

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

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

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

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

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

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

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

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

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

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

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

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

    code_partition: partition@0 {
      label = "code";
      reg = <0x0 0xF0000>;
      read-only;
    }

    /*
    * The final 64 KiB is reserved for the application.
    * Storage partition will be used by FCB/LittleFS/NVS
    * if enabled.
    */
    storage_partition: partition@F0000 {
      label = "storage";
      reg = <0x000F0000 0x00100000>;
    }
  }
};
```

**Enabling SAM-BA runner** In order to instruct Zephyr west tool to use the SAM-BA bootloader the `board.cmake` file must have include(`${ZEPHYR_BASE}/boards/common/bossac.board.cmake`) entry. Note that Zephyr tool accept more entries to define multiple runners. By default, the first one will be selected when using `west flash` command. The remaining options are available passing the runner option, for instance `west flash -r bossac`.
More implementation details can be found in the boards documentation. As a quick reference, see these three board documentation pages:

- sam4e_xpro (ROM bootloader)
- adafruit_feather_m0_basic_proto (Adafruit UF2 bootloader)
- arduino_nano_33_iot (Arduino bootloader)
- arduino_nano_33_ble (Arduino legacy bootloader)

**J-Link Debug Host Tools**

Segger provides a suite of debug host tools for Linux, macOS, and Windows operating systems:

- J-Link GDB Server: GDB remote debugging
- J-Link Commander: Command-line control and flash programming
- RTT Viewer: RTT terminal input and output
- SystemView: Real-time event visualization and recording

These debug host tools are compatible with the following debug probes:

- LPC-Link2 J-Link Onboard Debug Probe
- OpenSDA J-Link Onboard Debug Probe
- J-Link External Debug Probe
- ST-LINK/V2-1 Onboard Debug Probe

Check if your SoC is listed in J-Link Supported Devices.

Download and install the J-Link Software and Documentation Pack to get the J-Link GDB Server and Commander, and to install the associated USB device drivers. RTT Viewer and SystemView can be downloaded separately, but are not required.

Note that the J-Link GDB server does not yet support Zephyr RTOS-awareness.

**OpenOCD Debug Host Tools**

OpenOCD is a community open source project that provides GDB remote debugging and flash programming support for a wide range of SoCs. A fork that adds Zephyr RTOS-awareness is included in the Zephyr SDK; otherwise see Getting OpenOCD for options to download OpenOCD from official repositories.

These debug host tools are compatible with the following debug probes:

- OpenSDA DAPLink Onboard Debug Probe
- J-Link External Debug Probe
- ST-LINK/V2-1 Onboard Debug Probe

Check if your SoC is listed in OpenOCD Supported Devices.

**Note:** On Linux, openocd is available though the Zephyr SDK. Windows users should use the following steps to install openocd:

- Download openocd for Windows from here: OpenOCD Windows
- Copy bin and share dirs to C:\Program Files\OpenOCD\bin
- Add C:\Program Files\OpenOCD\bin to ‘PATH’ environment variable

2.8. Flashing and Hardware Debugging
pyOCD Debug Host Tools

pyOCD is an open source project from Arm that provides GDB remote debugging and flash programming support for Arm Cortex-M SoCs. It is distributed on PyPi and installed when you complete the Get Zephyr and install Python dependencies step in the Getting Started Guide. pyOCD includes support for Zephyr RTOS-awareness.

These debug host tools are compatible with the following debug probes:

- OpenSDA DAPLink Onboard Debug Probe
- ST-LINK/V2-1 Onboard Debug Probe

Check if your SoC is listed in pyOCD Supported Devices.

Lauterbach TRACE32 Debug Host Tools

Lauterbach TRACE32 is a product line of microprocessor development tools, debuggers and real-time tracer with support for JTAG, SWD, NEXUS or ETM over multiple core architectures, including Arm Cortex-A/-R/-M, RISC-V, Xtensa, etc. Zephyr allows users to develop and program boards with Lauterbach TRACE32 support using `west`.

The runner consists of a wrapper around TRACE32 software, and allows a Zephyr board to execute a custom start-up script (Practice Script) for the different commands supported, including the ability to pass extra arguments from CMake. It is up to the board using this runner to define the actions performed on each command.

Install Lauterbach TRACE32 Software  Download Lauterbach TRACE32 software from the Lauterbach TRACE32 download website (registration required) and follow the installation steps described in Lauterbach TRACE32 Installation Guide.

Flashing and Debugging  Set the environment variable `T32_DIR` to the TRACE32 system directory. Then execute `west flash` or `west debug` commands to flash or debug the Zephyr application as detailed in Building, Flashing and Debugging. The `debug` command launches TRACE32 GUI to allow debug the Zephyr application, while the `flash` command hides the GUI and perform all operations in the background.

By default, the `t32` runner will launch TRACE32 using the default configuration file named `config.t32` located in the TRACE32 system directory. To use a different configuration file, supply the argument `--config CONFIG` to the runner, for example:

```
west flash --config myconfig.t32
```

For more options, run `west flash --context -r t32` to print the usage.

Zephyr RTOS Awareness  To enable Zephyr RTOS awareness follow the steps described in Lauterbach TRACE32 Zephyr OS Awareness Manual.

2.8.2 Debug Probes

A debug probe is special hardware which allows you to control execution of a Zephyr application running on a separate board. Debug probes usually allow reading and writing registers and memory, and support breakpoint debugging of the Zephyr application on your host workstation using tools like GDB. They may also support other debug software and more advanced features such as tracing program execution. For details on the related host software supported by Zephyr, see Flash & Debug Host Tools.

Debug probes are usually connected to your host workstation via USB; they are sometimes also accessible via an IP network or other means. They usually connect to the device running Zephyr using the JTAG or
SWD protocols. Debug probes are either separate hardware devices or circuitry integrated into the same board which runs Zephyr.

Many supported boards in Zephyr include a second microcontroller that serves as an onboard debug probe, usb-to-serial adapter, and sometimes a drag-and-drop flash programmer. This eliminates the need to purchase an external debug probe and provides a variety of debug host tool options.

Several hardware vendors have their own branded onboard debug probe implementations: NXP LPC boards have LPC-Link2, NXP Kinetis (former Freescale) boards have OpenSDA, and ST boards have ST-LINK. Each onboard debug probe microcontroller can support one or more types of firmware that communicate with their respective debug host tools. For example, an OpenSDA microcontroller can be programmed with DAPLink firmware to communicate with pyOCD or OpenOCD debug host tools, or with J-Link firmware to communicate with J-Link debug host tools.

<table>
<thead>
<tr>
<th>Debug Probes &amp; Host Tools Compatibility Chart</th>
<th>Host Tools</th>
</tr>
</thead>
<tbody>
<tr>
<td>Debug Probes</td>
<td>J-Link Debug</td>
</tr>
<tr>
<td>LPC-Link2 J-Link</td>
<td>✓</td>
</tr>
<tr>
<td>OpenSDA DAPLink</td>
<td></td>
</tr>
<tr>
<td>OpenSDA J-Link</td>
<td>✓</td>
</tr>
<tr>
<td>J-Link External</td>
<td>✓</td>
</tr>
<tr>
<td>ST-LINK/V2-1</td>
<td>✓</td>
</tr>
</tbody>
</table>

Some supported boards in Zephyr do not include an onboard debug probe and therefore require an external debug probe. In addition, boards that do include an onboard debug probe often also have an SWD or JTAG header to enable the use of an external debug probe instead. One reason this may be useful is that the onboard debug probe may have limitations, such as lack of support for advanced debuggers or high-speed tracing. You may need to adjust jumpers to prevent the onboard debug probe from interfering with the external debug probe.

**LPC-Link2 J-Link Onboard Debug Probe**

The LPC-Link2 J-Link is an onboard debug probe and usb-to-serial adapter supported on many NXP LPC and i.MX RT development boards.

This debug probe is compatible with the following debug host tools:

- **J-Link Debug Host Tools**

This probe is realized by programming the LPC-Link2 microcontroller with J-Link LPC-Link2 firmware. Download and install LPCScrypt to get the firmware and programming scripts.

**Note:** Verify the firmware supports your board by visiting Firmware for LPCXpresso

1. Put the LPC-Link2 microcontroller into DFU boot mode by attaching the DFU jumper, then powering up the board.
2. Run the program_JLINK script.
3. Remove the DFU jumper and power cycle the board.

**OpenSDA DAPLink Onboard Debug Probe**

The OpenSDA DAPLink is an onboard debug probe and usb-to-serial adapter supported on many NXP Kinetis and i.MX RT development boards. It also includes drag-and-drop flash programming support.
This debug probe is compatible with the following debug host tools:

- pyOCD Debug Host Tools
- OpenOCD Debug Host Tools

This probe is realized by programming the OpenSDA microcontroller with DAPLink OpenSDA firmware. NXP provides OpenSDA DAPLink Board-Specific Firmwares.

Install the debug host tools before you program the firmware.

As with all OpenSDA debug probes, the steps for programming the firmware are:

1. Put the OpenSDA microcontroller into bootloader mode by holding the reset button while you power on the board. Note that “bootloader mode” in this context applies to the OpenSDA microcontroller itself, not the target microcontroller of your Zephyr application.

2. After you power on the board, release the reset button. A USB mass storage device called BOOT-LOADER or MAINTENANCE will enumerate.

3. Copy the OpenSDA firmware binary to the USB mass storage device.

4. Power cycle the board, this time without holding the reset button. You should see three USB devices enumerate: a CDC device (serial port), a HID device (debug port), and a mass storage device (drag-and-drop flash programming).

OpenSDA J-Link Onboard Debug Probe

The OpenSDA J-Link is an onboard debug probe and usb-to-serial adapter supported on many NXP Kinetis and i.MX RT development boards.

This debug probe is compatible with the following debug host tools:

- J-Link Debug Host Tools

This probe is realized by programming the OpenSDA microcontroller with J-Link OpenSDA firmware. Segger provides OpenSDA J-Link Generic Firmwares and OpenSDA J-Link Board-Specific Firmwares, where the latter is generally recommended when available. Board-specific firmwares are required for i.MX RT boards to support their external flash memories, whereas generic firmwares are compatible with all Kinetis boards.

Install the debug host tools before you program the firmware.

As with all OpenSDA debug probes, the steps for programming the firmware are:

1. Put the OpenSDA microcontroller into bootloader mode by holding the reset button while you power on the board. Note that “bootloader mode” in this context applies to the OpenSDA microcontroller itself, not the target microcontroller of your Zephyr application.

2. After you power on the board, release the reset button. A USB mass storage device called BOOT-LOADER or MAINTENANCE will enumerate.

3. Copy the OpenSDA firmware binary to the USB mass storage device.

4. Power cycle the board, this time without holding the reset button. You should see two USB devices enumerate: a CDC device (serial port) and a vendor-specific device (debug port).

J-Link External Debug Probe

Segger J-Link is a family of external debug probes, including J-Link EDU, J-Link PLUS, J-Link ULTRA+, and J-Link PRO, that support a large number of devices from different hardware architectures and vendors.

This debug probe is compatible with the following debug host tools:

- J-Link Debug Host Tools
Install the debug host tools before you program the firmware.

**ST-LINK/V2-1 Onboard Debug Probe**

ST-LINK/V2-1 is a serial and debug adapter built into all Nucleo and Discovery boards. It provides a bridge between your computer (or other USB host) and the embedded target processor, which can be used for debugging, flash programming, and serial communication, all over a simple USB cable.

It is compatible with the following host debug tools:

- **OpenOCD Debug Host Tools**
- **J-Link Debug Host Tools**

For some STM32 based boards, it is also compatible with:

- **pyOCD Debug Host Tools**

While it works out of the box with OpenOCD, it requires some flashing to work with J-Link. To do this, SEGGER offers a firmware upgrading the ST-LINK/V2-1 on board on the Nucleo and Discovery boards. This firmware makes the ST-LINK/V2-1 compatible with J-LinkOB, allowing users to take advantage of most J-Link features like the ultra fast flash download and debugging speed or the free-to-use GDBServer.

More information about upgrading ST-LINK/V2-1 to JLink or restore ST-Link/V2-1 firmware please visit: Segger over ST-Link

### Flash and debug with ST-Link Using OpenOCD

OpenOCD is available by default on ST-Link and configured as the default flash and debug tool. Flash and debug can be done as follows:

```
# From the root of the zephyr repository
west build -b None samples/hello_world
west flash
```

```
# From the root of the zephyr repository
west build -b None samples/hello_world
west debug
```

Using Segger J-Link

Once STLink is flashed with SEGGER FW and J-Link GDB server is installed on your host computer, you can flash and debug as follows:

Use CMake with `-DBOARD_FLASH_RUNNER=jlink` to change the default OpenOCD runner to J-Link. Alternatively, you might add the following line to your application CMakeList.txt file.

```cmake
set(BOARD_FLASH_RUNNER jlink)
```

If you use West (Zephyr's meta-tool) you can modify the default runner using the `--runner (or -r)` option.

```
w west flash --runner jlink
```

To attach a debugger to your board and open up a debug console with jlink.

```
w west debug --runner jlink
```

For more information about West and available options, see West (Zephyr's meta-tool).

If you configured your Zephyr application to use Segger RTT console instead, open telnet:
$ telnet localhost 19021
Trying ::1...
Trying 127.0.0.1...
Connected to localhost.
Escape character is '^]'.
SEGGER J-Link V6.30f - Real time terminal output
J-Link STLink V21 compiled Jun 26 2017 10:35:16 V1.0, SN=773895351
Process: JLinkGDBServerCLExe
Zephyr Shell, Zephyr version: 1.12.99
Type 'help' for a list of available commands
shell>

If you get no RTT output you might need to disable other consoles which conflict with the RTT one if they are enabled by default in the particular sample or application you are running, such as disable UART_CONSOLE in menuconfig

**Updating or restoring ST-Link firmware** ST-Link firmware can be updated using STM32CubeProgrammer Tool. It is usually useful when facing flashing issues, for instance when using twister's device-testing option.

Once installed, you can update attached board ST-Link firmware with the following command

```
s java -jar ~/STMicroelectronics/STM32Cube/STM32CubeProgrammer/Drivers/FirmwareUpgrade/STLinkUpgrade.jar -sn <board_uid>
```

Where board_uid can be obtained using twister's generate-hardware-map option. For more information about twister and available options, see *Test Runner (Twister)*.

## 2.9 Modules (External projects)

Zephyr relies on the source code of several externally maintained projects in order to avoid reinventing the wheel and to reuse as much well-established, mature code as possible when it makes sense. In the context of Zephyr's build system those are called *modules*. These modules must be integrated with the Zephyr build system, as described in more detail in other sections on this page.

To be classified as a candidate for being included in the default list of modules, an external project is required to have its own life-cycle outside the Zephyr Project, that is, reside in its own repository, and have its own contribution and maintenance workflow and release process. Zephyr modules should not contain code that is written exclusively for Zephyr. Instead, such code should be contributed to the main zephyr tree.

Modules to be included in the default manifest of the Zephyr project need to provide functionality or features endorsed and approved by the project Technical Steering Committee and should comply with the *module licensing requirements* and *contribution guidelines*. They should also have a Zephyr developer that is committed to maintain the module codebase.

Zephyr depends on several categories of modules, including but not limited to:

- Debugger integration
- Silicon vendor Hardware Abstraction Layers (HALs)
- Cryptography libraries
- File Systems
- Inter-Process Communication (IPC) libraries

Additionally, in some cases modules (particularly vendor HALs) can contain references to optional *binary blobs*. 

---

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This page summarizes a list of policies and best practices which aim at better organizing the workflow in Zephyr modules.

2.9.1 Module Repositories

- All modules included in the default manifest shall be hosted in repositories under the zephyrproject-rtos GitHub organization.
- The module repository codebase shall include a `module.yml` file in a `zephyr/` folder at the root of the repository.
- Module repository names should follow the convention of using lowercase letters and dashes instead of underscores. This rule will apply to all new module repositories, except for repositories that are directly tracking external projects (hosted in Git repositories); such modules may be named as their external project counterparts.

Note: Existing module repositories that do not conform to the above convention do not need to be renamed to comply with the above convention.

- Module repositories names should be explicitly set in the `zephyr/module.yml` file.
- Modules should use “zephyr” as the default name for the repository main branch. Branches for specific purposes, for example, a module branch for an LTS Zephyr version, shall have names starting with the ‘zephyr_’ prefix.
- If the module has an external (upstream) project repository, the module repository should preserve the upstream repository folder structure.

Note: It is not required in module repositories to maintain a ‘master’ branch mirroring the master branch of the external repository. It is not recommended as this may generate confusion around the module’s main branch, which should be ‘zephyr’.

- Modules should expose all provided header files with an include pathname beginning with the module-name. (E.g., mcuboot should expose its `bootutil/bootutil.h` as “mcu-boot/bootutil/bootutil.h”.)

Synchronizing with upstream

It is preferred to synchronize a module repository with the latest stable release of the corresponding external project. It is permitted, however, to update a Zephyr module repository with the latest development branch tip, if this is required to get important updates in the module codebase. When synchronizing a module with upstream it is mandatory to document the rationale for performing the particular update.

Requirements for allowed practices

Changes to the main branch of a module repository, including synchronization with upstream code base, may only be applied via pull requests. These pull requests shall be verifiable by Zephyr CI and mergeable (e.g. with the Rebase and merge, or Create a merge commit option using Github UI). This ensures that the incoming changes are always reviewable, and the downstream module repository history is incremental (that is, existing commits, tags, etc. are always preserved). This policy also allows to run Zephyr CI, git lint, identity, and license checks directly on the set of changes that are to be brought into the module repository.

Note: Force-pushing to a module’s main branch is not allowed.
Allowed practices  The following practices conform to the above requirements and should be followed in all modules repositories. It is up to the module code owner to select the preferred synchronization practice, however, it is required that the selected practice is consistently followed in the respective module repository.

Updating modules with a diff from upstream: Upstream changes brought as a single snapshot commit (manual diff) in a pull request against the module’s main branch, which may be merged using the Rebase & merge operation. This approach is simple and should be applicable to all modules with the downside of suppressing the upstream history in the module repository.

Note: The above practice is the only allowed practice in modules where the external project is not hosted in an upstream Git repository.

The commit message is expected to identify the upstream project URL, the version to which the module is updated (upstream version, tag, commit SHA, if applicable, etc.), and the reason for the doing the update.

Updating modules by merging the upstream branch: Upstream changes brought in by performing a Git merge of the intended upstream branch (e.g. main branch, latest release branch, etc.) submitting the result in pull request against the module main branch, and merging the pull request using the Create a merge commit operation. This approach is applicable to modules with an upstream project Git repository. The main advantages of this approach is that the upstream repository history (that is, the original commit SHAs) is preserved in the module repository. The downside of this approach is that two additional merge commits are generated in the downstream main branch.

2.9.2 Contributing to Zephyr modules

Individual Roles & Responsibilities

To facilitate management of Zephyr module repositories, the following individual roles are defined.

Administrator: Each Zephyr module shall have an administrator who is responsible for managing access to the module repository, for example, for adding individuals as Collaborators in the repository at the request of the module owner. Module administrators are members of the Administrators team, that is a group of project members with admin rights to module GitHub repositories.

Module owner: Each module shall have a module code owner. Module owners will have the overall responsibility of the contents of a Zephyr module repository. In particular, a module owner will:

• coordinate code reviewing in the module repository
• be the default assignee in pull-requests against the repository’s main branch
• request additional collaborators to be added to the repository, as they see fit
• regularly synchronize the module repository with its upstream counterpart following the policies described in Synchronizing with upstream
• be aware of security vulnerability issues in the external project and update the module repository to include security fixes, as soon as the fixes are available in the upstream code base
• list any known security vulnerability issues, present in the module codebase, in Zephyr release notes.

Note: Module owners are not required to be Zephyr Maintainers.

Merger: The Zephyr Release Engineering team has the right and the responsibility to merge approved pull requests in the main branch of a module repository.
Maintaining the module codebase

Updates in the zephyr main tree, for example, in public Zephyr APIs, may require patching a module's codebase. The responsibility for keeping the module codebase up to date is shared between the contributor of such updates in Zephyr and the module owner. In particular:

- the contributor of the original changes in Zephyr is required to submit the corresponding changes that are required in module repositories, to ensure that Zephyr CI on the pull request with the original changes, as well as the module integration testing are successful.
- the module owner has the overall responsibility for synchronizing and testing the module codebase with the zephyr main tree. This includes occasional advanced testing of the module's codebase in addition to the testing performed by Zephyr's CI. The module owner is required to fix issues in the module's codebase that have not been caught by Zephyr pull request CI runs.

Contributing changes to modules

Submitting and merging changes directly to a module's codebase, that is, before they have been merged in the corresponding external project repository, should be limited to:

- changes required due to updates in the zephyr main tree
- urgent changes that should not wait to be merged in the external project first, such as fixes to security vulnerabilities.

Non-trivial changes to a module's codebase, including changes in the module design or functionality should be discouraged, if the module has an upstream project repository. In that case, such changes shall be submitted to the upstream project, directly.

Submitting changes to modules describes in detail the process of contributing changes to module repositories.

Contribution guidelines

Contributing to Zephyr modules shall follow the generic project Contribution guidelines.

Pull Requests: may be merged with minimum of 2 approvals, including an approval by the PR assignee. In addition to this, pull requests in module repositories may only be merged if the introduced changes are verified with Zephyr CI tools, as described in more detail in other sections on this page.

The merging of pull requests in the main branch of a module repository must be coupled with the corresponding manifest file update in the zephyr main tree.

Issue Reporting: GitHub issues are intentionally disabled in module repositories, in favor of a centralized policy for issue reporting. Tickets concerning, for example, bugs or enhancements in modules shall be opened in the main zephyr repository. Issues should be appropriately labeled using GitHub labels corresponding to each module, where applicable.

Note: It is allowed to file bug reports for zephyr modules to track the corresponding upstream project bugs in Zephyr. These bug reports shall not affect the Release Quality Criteria.

2.9.3 Licensing requirements and policies

All source files in a module's codebase shall include a license header, unless the module repository has main license file that covers source files that do not include license headers.

Main license files shall be added in the module's codebase by Zephyr developers, only if they exist as part of the external project, and they contain a permissive OSI-compliant license. Main license files should preferably contain the full license text instead of including an SPDX license identifier. If multiple main
license files are present it shall be made clear which license applies to each source file in a module's codebase.

Individual license headers in module source files supersede the main license.

Any new content to be added in a module repository will require to have license coverage.

---

**Note:** Zephyr recommends conveying module licensing via individual license headers and main license files. This is not a hard requirement; should an external project have its own practice of conveying how licensing applies in the module's codebase (for example, by having a single or multiple main license files), this practice may be accepted by and be referred to in the Zephyr module, as long as licensing requirements, for example OSI compliance, are satisfied.

---

**License policies**

When creating a module repository a developer shall:

- import the main license files, if they exist in the external project, and
- document (for example in the module README or .yml file) the default license that covers the module's codebase.

---

**License checks** License checks (via CI tools) shall be enabled on every pull request that adds new content in module repositories.

---

### 2.9.4 Documentation requirements

All Zephyr module repositories shall include an .rst file documenting:

- the scope and the purpose of the module
- how the module integrates with Zephyr
- the owner of the module repository
- synchronization information with the external project (commit, SHA, version etc.)
- licensing information as described in **Licensing requirements and policies**.

The file shall be required for the inclusion of the module and the contained information should be kept up to date.

---

### 2.9.5 Testing requirements

All Zephyr modules should provide some level of **integration** testing, ensuring that the integration with Zephyr works correctly. Integration tests:

- may be in the form of a minimal set of samples and tests that reside in the zephyr main tree
- should verify basic usage of the module (configuration, functional APIs, etc.) that is integrated with Zephyr.
- shall be built and executed (for example in QEMU) as part of twister runs in pull requests that introduce changes in module repositories.

**Note:** New modules, that are candidates for being included in the Zephyr default manifest, shall provide some level of integration testing.
The purpose of integration testing is not to provide functional verification of the module; this should be part of the testing framework of the external project.

Certain external projects provide test suites that reside in the upstream testing infrastructure but are written explicitly for Zephyr. These tests may (but are not required to) be part of the Zephyr test framework.

### 2.9.6 Deprecating and removing modules

Modules may be deprecated for reasons including, but not limited to:

- Lack of maintainership in the module
- Licensing changes in the external project
- Codebase becoming obsolete

The module information shall indicate whether a module is deprecated and the build system shall issue a warning when trying to build Zephyr using a deprecated module.

Deprecated modules may be removed from the Zephyr default manifest after 2 Zephyr releases.

**Note:** Repositories of removed modules shall remain accessible via their original URL, as they are required by older Zephyr versions.

### 2.9.7 Integrate modules in Zephyr build system

The build system variable `ZEPHYR_MODULES` is a CMake list of absolute paths to the directories containing Zephyr modules. These modules contain CMakeLists.txt and Kconfig files describing how to build and configure them, respectively. Module CMakeLists.txt files are added to the build using CMake's `add_subdirectory()` command, and the Kconfig files are included in the build's Kconfig menu tree.

If you have `west` installed, you don't need to worry about how this variable is defined unless you are adding a new module. The build system knows how to use west to set `ZEPHYR_MODULES`. You can add additional modules to this list by setting the `ZEPHYR_EXTRA_MODULES` CMake variable or by adding a `ZEPHYR_EXTRA_MODULES` line to `.zephyrrc` (See the section on Environment Variables for more details). This can be useful if you want to keep the list of modules found with west and also add your own.

**Note:** If the module `FOO` is provided by `west` but also given with `-DZEPHYR_EXTRA_MODULES=<path>/foo` then the module given by the command line variable `ZEPHYR_EXTRA_MODULES` will take precedence. This allows you to use a custom version of `FOO` when building and still use other Zephyr modules provided by `west`. This can for example be useful for special test purposes.

If you want to permanently add modules to the zephyr workspace and you are using zephyr as your manifest repository, you can also add a west manifest file into the submanifests directory. See submanifests/README.txt for more details.

See Basics for more on west workspaces.

Finally, you can also specify the list of modules yourself in various ways, or not use modules at all if your application doesn't need them.
2.9.8 Module yaml file description

A module can be described using a file named `zephyr/module.yml`. The format of `zephyr/module.yml` is described in the following:

**Module name**

Each Zephyr module is given a name by which it can be referred to in the build system. The name should be specified in the `zephyr/module.yml` file. This will ensure the module name is not changeable through user-defined directory names or `west` manifest files:

```yaml
name: <name>
```

In CMake the location of the Zephyr module can then be referred to using the CMake variable `ZEPHYR_<MODULE_NAME>_MODULE_DIR` and the variable `ZEPHYR_<MODULE_NAME>_CMAKE_DIR` holds the location of the directory containing the module's `CMakeLists.txt` file.

**Note:** When used for CMake and Kconfig variables, all letters in module names are converted to uppercase and all non-alphanumeric characters are converted to underscores (_). As example, the module `foo-bar` must be referred to as `ZEPHYR_FOO_BAR_MODULE_DIR` in CMake and Kconfig.

Here is an example for the Zephyr module `foo`:

```yaml
name: foo
```

**Note:** If the `name` field is not specified then the Zephyr module name will be set to the name of the module folder. As example, the Zephyr module located in `<workspace>/modules/bar` will use `bar` as its module name if nothing is specified in `zephyr/module.yml`.

**Module integration files (in-module)**

Inclusion of build files, `CMakeLists.txt` and `Kconfig`, can be described as:

```yaml
build:
  cmake: <cmake-directory>
  kconfig: <directory>/Kconfig
```

The `cmake: <cmake-directory>` part specifies that `<cmake-directory>` contains the `CMakeLists.txt` to use. The `kconfig: <directory>/Kconfig` part specifies the `Kconfig` file to use. Neither is required: `cmake` defaults to `zephyr`, and `kconfig` defaults to `zephyr/Kconfig`.

Here is an example `module.yml` file referring to `CMakeLists.txt` and `Kconfig` files in the root directory of the module:

```yaml
build:
  cmake: .
  kconfig: Kconfig
```

**Build system integration**

When a module has a `module.yml` file, it will automatically be included into the Zephyr build system. The path to the module is then accessible through Kconfig and CMake variables.
In both Kconfig and CMake, the variable `ZEPHYR_<MODULE_NAME>_MODULE_DIR` contains the absolute path to the module.

In CMake, `ZEPHYR_<MODULE_NAME>_CMAKE_DIR` contains the absolute path to the directory containing the `CMakeLists.txt` file that is included into CMake build system. This variable's value is empty if the module.yml file does not specify a `CMakeLists.txt`.

To read these variables for a Zephyr module named `foo`:

- In CMake: use `${ZEPHYR_FOO_MODULE_DIR}` for the module's top level directory, and `${ZEPHYR_FOO_CMAKE_DIR}` for the directory containing its `CMakeLists.txt`
- In Kconfig: use `$(ZEPHYR_FOO_MODULE_DIR)` for the module's top level directory

Notice how a lowercase module name `foo` is capitalized to `FOO` in both CMake and Kconfig.

These variables can also be used to test whether a given module exists. For example, to verify that `foo` is the name of a Zephyr module:

```cpp
if(ZEPHYR_FOO_MODULE_DIR)
    # Do something if FOO exists.
endif()
```

In Kconfig, the variable may be used to find additional files to include. For example, to include the file `some/Kconfig` in module `foo`:

```cpp
source "$(ZEPHYR_FOO_MODULE_DIR)/some/Kconfig"
```

During CMake processing of each Zephyr module, the following two variables are also available:

- the current module's top level directory: `${ZEPHYR_CURRENT_MODULE_DIR}`
- the current module's `CMakeLists.txt` directory: `${ZEPHYR_CURRENT_CMAKE_DIR}`

This removes the need for a Zephyr module to know its own name during CMake processing. The module can source additional CMake files using these `CURRENT` variables. For example:

```cpp
include(${ZEPHYR_CURRENT_MODULE_DIR}/cmake/code.cmake)
```

It is possible to append values to a Zephyr CMake list variable from the module's first `CMakeLists.txt` file. To do so, append the value to the list and then set the list in the `PARENT_SCOPE` of the `CMakeLists.txt` file. For example, to append `bar` to the `FOO_LIST` variable in the Zephyr `CMakeLists.txt` scope:

```cpp
list(APPEND FOO_LIST bar)
set(FOO_LIST ${FOO_LIST} PARENT_SCOPE)
```

An example of a Zephyr list where this is useful is when adding additional directories to the `SYSCALL_INCLUDE_DIRS` list.

### Zephyr module dependencies

A Zephyr module may be dependent on other Zephyr modules to be present in order to function correctly. Or it might be that a given Zephyr module must be processed after another Zephyr module, due to dependencies of certain CMake targets.

Such a dependency can be described using the `depends` field.

```cpp
build:
    depends:
        - <module>
```

Here is an example for the Zephyr module `foo` that is dependent on the Zephyr module `bar` to be present in the build system:
name: foo
build:
  depends:
    - bar

This example will ensure that bar is present when foo is included into the build system, and it will also ensure that bar is processed before foo.

**Module integration files (external)**

Module integration files can be located externally to the Zephyr module itself. The `MODULE_EXT_ROOT` variable holds a list of roots containing integration files located externally to Zephyr modules.

**Module integration files in Zephyr** The Zephyr repository contain `CMakeLists.txt` and `Kconfig` build files for certain known Zephyr modules.

Those files are located under

```
<ZEPHYR_BASE>
  modules
    <module_name>
      CMakeLists.txt
      Kconfig
```

**Module integration files in a custom location** You can create a similar `MODULE_EXT_ROOT` for additional modules, and make those modules known to Zephyr build system.

Create a `MODULE_EXT_ROOT` with the following structure

```
<MODULE_EXT_ROOT>
  modules
    modules.cmake
    <module_name>
      CMakeLists.txt
      Kconfig
```

and then build your application by specifying `-DMODULE_EXT_ROOT` parameter to the CMake build system. The `MODULE_EXT_ROOT` accepts a CMake list of roots as argument.

A Zephyr module can automatically be added to the `MODULE Ext_ROOT` list using the module description file `zephyr/module.yml`, see *Build settings*.

**Note:** `ZEPHYR_BASE` is always added as a `MODULE Ext_ROOT` with the lowest priority. This allows you to overrule any integration files under `<ZEPHYR_BASE>/modules/<module_name>` with your own implementation your own `MODULE Ext_ROOT`.

The `modules.cmake` file must contain the logic that specifies the integration files for Zephyr modules via specifically named CMake variables.

To include a module's CMake file, set the variable `ZEPHYR-_MODULE_NAME_-CMAKE_DIR` to the path containing the CMake file.

To include a module's Kconfig file, set the variable `ZEPHYR-_MODULE_NAME_-KCONFIG` to the path to the Kconfig file.

The following is an example on how to add support the the FOO module.

Create the following structure
and inside the `modules.cmake` file, add the following content:

```cmake
set(ZEPHYR_FOO_CMAKE_DIR ${CMAKE_CURRENT_LIST_DIR}/foo)
set(ZEPHYR_FOO_KCONFIG  ${CMAKE_CURRENT_LIST_DIR}/foo/Kconfig)
```

**Module integration files (zephyr/module.yml)** The module description file `zephyr/module.yml` can be used to specify that the build files, CMakeLists.txt and Kconfig, are located in a Module integration files (external).

Build files located in a `MODULE_EXT_ROOT` can be described as:

```yaml
build:
  cmake-ext: True
  kconfig-ext: True
```

This allows control of the build inclusion to be described externally to the Zephyr module.

The Zephyr repository itself is always added as a Zephyr module ext root.

**Build settings**

It is possible to specify additional build settings that must be used when including the module into the build system.

All root settings are relative to the root of the module.

Build settings supported in the `module.yml` file are:

- `board_root`: Contains additional boards that are available to the build system. Additional boards must be located in a `<board_root>/boards` folder.
- `dts_root`: Contains additional dts files related to the architecture/soc families. Additional dts files must be located in a `<dts_root>/dts` folder.
- `soc_root`: Contains additional SoCs that are available to the build system. Additional SoCs must be located in a `<soc_root>/soc` folder.
- `arch_root`: Contains additional architectures that are available to the build system. Additional architectures must be located in a `<arch_root>/arch` folder.
- `module_ext_root`: Contains CMakeLists.txt and Kconfig files for Zephyr modules, see also Module integration files (external).

Example of a `module.yml` file containing additional roots, and the corresponding file system layout.

```yaml
build:
  settings:
    board_root: .
    dts_root: .
    soc_root: .
    arch_root: .
    module_ext_root: .
```

requires the following folder structure:
Twister (Test Runner)

To execute both tests and samples available in modules, the Zephyr test runner (twister) should be pointed to the directories containing those samples and tests. This can be done by specifying the path to both samples and tests in the `zephyr/module.yml` file. Additionally, if a module defines out of tree boards, the module file can point twister to the path where those files are maintained in the module. For example:

```
build:
  cmake: .
samples:
  - samples
tests:
  - tests
boards:
  - boards
```

Binary Blobs

Zephyr supports fetching and using binary blobs, and their metadata is contained entirely in `zephyr/module.yml`. This is because a binary blob must always be associated with a Zephyr module, and thus the blob metadata belongs in the module’s description itself.

Binary blobs are fetched using `west blobs`. If `west` is not used, they must be downloaded and verified manually.

The `blobs` section in `zephyr/module.yml` consists of a sequence of maps, each of which has the following entries:

- **path**: The path to the binary blob, relative to the `zephyr/blobs/` folder in the module repository
- **sha256**: SHA-256 checksum of the binary blob file
- **type**: The type of binary blob. Currently limited to `img` or `lib`
- **version**: A version string
- **license-path**: Path to the license file for this blob, relative to the root of the module repository
- **url**: URL that identifies the location the blob will be fetched from, as well as the fetching scheme to use
- **description**: Human-readable description of the binary blob
- **doc-url**: A URL pointing to the location of the official documentation for this blob

Module Inclusion

**Using West** If west is installed and `ZEPHYR_MODULES` is not already set, the build system finds all the modules in your west installation and uses those. It does this by running `west list` to get the paths of all the projects in the installation, then filters the results to just those projects which have the necessary module metadata files.
Each project in the west list output is tested like this:

- If the project contains a file named `zephyr/module.yml`, then the content of that file will be used to determine which files should be added to the build, as described in the previous section.
- Otherwise (i.e. if the project has no `zephyr/module.yml`), the build system looks for `zephyr/CMakeLists.txt` and `zephyr/Kconfig` files in the project. If both are present, the project is considered a module, and those files will be added to the build.
- If neither of those checks succeed, the project is not considered a module, and is not added to `ZEPHYR_MODULES`.

**Without West** If you don't have west installed or don't want the build system to use it to find Zephyr modules, you can set `ZEPHYR_MODULES` yourself using one of the following options. Each of the directories in the list must contain either a `zephyr/module.yml` file or the files `zephyr/CMakeLists.txt` and `Kconfig`, as described in the previous section.

1. At the CMake command line, like this:
   
   ```
cmake -DZEPHYR_MODULES=<path-to-module1>[;<path-to-module2>[...]] ...
   ```

2. At the top of your application's top level CMakeLists.txt, like this:

   ```
set(ZEPHYR_MODULES <path-to-module1> <path-to-module2> [...] )
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
```

   If you choose this option, make sure to set the variable **before** calling `find_package(Zephyr ...)`, as shown above.

3. In a separate CMake script which is pre-loaded to populate the CMake cache, like this:

   ```
   # Put this in a file with a name like "zephyr-modules.cmake"
   set(ZEPHYR_MODULES <path-to-module1> <path-to-module2>
    CACHE STRING "pre-cached modules")
   ```

   You can tell the build system to use this file by adding `-C zephyr-modules.cmake` to your CMake command line.

**Not using modules** If you don't have west installed and don't specify `ZEPHYR_MODULES` yourself, then no additional modules are added to the build. You will still be able to build any applications that don't require code or Kconfig options defined in an external repository.

### 2.9.9 Submitting changes to modules

When submitting new or making changes to existing modules the main repository Zephyr needs a reference to the changes to be able to verify the changes. In the main tree this is done using revisions. For code that is already merged and part of the tree we use the commit hash, a tag, or a branch name. For pull requests however, we require specifying the pull request number in the revision field to allow building the zephyr main tree with the changes submitted to the module.

To avoid merging changes to master with pull request information, the pull request should be marked as DNM (Do Not Merge) or preferably a draft pull request to make sure it is not merged by mistake and to allow for the module to be merged first and be assigned a permanent commit hash. Once the module is merged, the revision will need to be changed either by the submitter or by the maintainer to the commit hash of the module which reflects the changes.

Note that multiple and dependent changes to different modules can be submitted using exactly the same process. In this case you will change multiple entries of all modules that have a pull request against them.
Process for submitting a new module

Please follow the process in *Submission and review process* and obtain the TSC approval to integrate the external source code as a module.

If the request is approved, a new repository will be created by the project team and initialized with basic information that would allow submitting code to the module project following the project contribution guidelines.

If a module is maintained as a fork of another project on Github, the Zephyr module related files and changes in relation to upstream need to be maintained in a special branch named `zephyr`.

Maintainers from the Zephyr project will create the repository and initialize it. You will be added as a collaborator in the new repository. Submit the module content (code) to the new repository following the guidelines described [here](#), and then add a new entry to the `west.yml` with the following information:

```yaml
- name: <name of repository>
  path: <path to where the repository should be cloned>
  revision: <ref pointer to module pull request>
```

For example, to add `my_module` to the manifest:

```yaml
- name: my_module
  path: modules/lib/my_module
  revision: pull/23/head
```

Where 23 in the example above indicated the pull request number submitted to the `my_module` repository. Once the module changes are reviewed and merged, the revision needs to be changed to the commit hash from the module repository.

Process for submitting changes to existing modules

1. Submit the changes using a pull request to an existing repository following the *contribution guidelines*.
2. Submit a pull request changing the entry referencing the module into the `west.yml` of the main Zephyr tree with the following information:

```yaml
- name: <name of repository>
  path: <path to where the repository should be cloned>
  revision: <ref pointer to module pull request>
```

For example, to add `my_module` to the manifest:

```yaml
- name: my_module
  path: modules/lib/my_module
  revision: pull/23/head
```

Where 23 in the example above indicated the pull request number submitted to the `my_module` repository. Once the module changes are reviewed and merged, the revision needs to be changed to the commit hash from the module repository.

## 2.10 West (Zephyr’s meta-tool)

The Zephyr project includes a swiss-army knife command line tool named `west`. West is developed in its own repository.

1 Zephyr is an English name for the Latin *Zephyrus*, the ancient Greek god of the west wind.
West's built-in commands provide a multiple repository management system with features inspired by Google's Repo tool and Git submodules. West is also “pluggable”: you can write your own west extension commands which add additional features to west. Zephyr uses this to provide conveniences for building applications, flashing and debugging them, and more.

Like git and docker, the top-level west command takes some common options, a sub-command to run, and then options and arguments for that sub-command:

```
west [common-opts] <command> [opts] <args>
```

Since west v0.8, you can also run west like this:

```
python3 -m west [common-opts] <command> [opts] <args>
```

You can run `west --help` (or `west -h` for short) to get top-level help for available west commands, and `west <command> -h` for detailed help on each command.

The following pages document west's v0.14.x releases, and provide additional context about the tool.

### 2.10.1 Installing west

West is written in Python 3 and distributed through PyPI. Use `pip3` to install or upgrade west:

On Linux:

```
pip3 install --user -U west
```

On Windows and macOS:

```
pip3 install -U west
```

**Note:** See [Python and pip](#) for additional clarification on using the `--user` switch.

Afterwards, you can run `pip3 show -f west` for information on where the west binary and related files were installed.

Once west is installed, you can use it to **clone the Zephyr repositories**.

#### Structure

West's code is distributed via PyPI in a Python package named `west`. This distribution includes a launcher executable, which is also named `west` (or `west.exe` on Windows).

When west is installed, the launcher is placed by `pip3` somewhere in the user's filesystem (exactly where depends on the operating system, but should be in the PATH environment variable). This launcher is the command-line entry point to running both built-in commands like `west init`, `west update`, along with any extensions discovered in the workspace.

In addition to its command-line interface, you can also use west's Python APIs directly. See [west-apis](#) for details.

#### Enabling shell completion

West currently supports shell completion in the following combinations of platform and shell:

- Linux: bash
- macOS: bash
In order to enable shell completion, you will need to obtain the corresponding completion script and have it sourced every time you enter a new shell session.

To obtain the completion script you can use the `west completion` command:

```bash
cd /path/to/zephyr/
west completion bash > ~/.west-completion.bash
```

**Note:** Remember to update your local copy of the completion script using `west completion` when you update Zephyr.

Next, you need to import `west-completion.bash` into your bash shell.

On Linux, you have the following options:

- Copy `west-completion.bash` to `/etc/bash_completion.d/`.
- Copy `west-completion.bash` to `/usr/share/bash-completion/completions/`.
- Copy `west-completion.bash` to a local folder and source it from your `~/.bashrc`.

On macOS, you have the following options:

- Copy `west-completion.bash` to a local folder and source it from your `~/.bash_profile`.
- Install the `bash-completion` package with `brew`:
  ```bash
  brew install bash-completion
  ```
  Then source the main bash completion script in your `~/.bash_profile`:
  ```bash
  source /usr/local/etc/profile.d/bash_completion.sh
  ```
  and finally copy `west-completion.bash` to `/usr/local/etc/bash_completion.d/`.

### 2.10.2 West Release Notes

**v0.14.0**

Bug fixes:

- West commands that were run with a bad local configuration file dumped stack in a confusing way. This has been fixed and west now prints a sensible error message in this case.

- A bug in the way west looks for the zephyr repository was fixed. The bug itself usually appeared when running an extension command like `west build` in a new workspace for the first time; this used to fail (just for the first time, not on subsequent command invocations) unless you ran the command in the workspace's top level directory.

- West now prints sensible error messages when the user lacks permission to open the manifest file instead of dumping stack traces.

API changes:

- The `west.manifest.MalformedConfig` exception type has been moved to the `west.configuration` module

- The `west.manifest.MalformedConfig` exception type has been moved to the `west.configuration` module

- The `west.configuration.Configuration` class now raises `MalformedConfig` instead of `RuntimeError` in some cases
v0.13.1

Bug fix:

- When calling `west.manifest.Manifest.from_file()` when outside of a workspace, west again falls back on the ZEPHYR_BASE environment variable to locate the workspace.

v0.13.0

New features:

- You can now associate arbitrary user data with the manifest repository itself in the `manifest:
  self: userdata: value`, like so:

  ```yaml
  manifest:
    self:
      userdata: <any YAML value can go here>
  ```

Bug fixes:

- The path to the manifest repository reported by west could be incorrect in certain circumstances detailed in [issue #572](https://github.com/zephyrproject-rtos/west/issues/572). This has been fixed as part of a larger overhaul of path handling support in the west.manifest API module.
- The `west.Manifest.ManifestProject.__repr__` return value was fixed

API changes:

- `west.configuration.Configuration`: new object-oriented interface to the current configuration. This reflects the system, global, and workspace-local configuration values, and allows you to read, write, and delete configuration options from any or all of these locations.
- `west.commands.WestCommand`:
  - `config`: new attribute, returns a Configuration object or aborts the program if none is set. This is always usable from within extension command `do_run()` implementations.
  - `has_config`: new boolean attribute, which is True if and only if reading `self.config` will abort the program.
- The path handling in the `west.manifest` package has been overhauled in a backwards-incompatible way. For more details, see commit [56cfe8d1d1f3c9b45de3793c738ac62db52ac](https://github.com/zephyrproject-rtos/west/commit/56cfe8d1d1f3c9b45de3793c738ac62db52ac).
- `west.manifest.Manifest.validate()`: this now returns the validated data as a Python dict. This can be useful if the value passed to this function was a str, and the dict is desired.
- `west.manifest.Manifest: new:
  - path attributes abspath, posixpath, relative_path, yaml_path, repo_path, repo_posixpath
  - userdata attribute, which contains the parsed value from `manifest: self: userdata:`, or is None
  - `from_topdir()` factory method
- `west.manifest.ManifestProject: new userdata attribute, which also contains the parsed value from `manifest: self: userdata:`, or is None
- `west.manifest.ManifestImportFailed`: the constructor can now take any value; this can be used to reflect failed imports from a `map` or other compound value.
- Deprecated configuration APIs:
The following APIs are now deprecated in favor of using a Configuration object. Usually this will be done via `self.config` from a `WestCommand` instance, but this can be done directly by instantiating a Configuration object for other usages.

- `west.configuration.config`
- `west.configuration.read_config`
- `west.configuration.update_config`
- `west.configuration.delete_config`

v0.12.0

New features:

- West now works on the MSYS2 platform.
- West manifest files can now contain arbitrary user data associated with each project. See Repository user data for details.

Bug fixes:

- The `west list` command's `{sha}` format key has been fixed for the manifest repository; it now prints `N/A" ("not applicable") as expected.

API changes:

- The `west.manifest.Project.userdata` attribute was added to support project user data.

v0.11.1

New features:

- `west status` now only prints output for projects which have a nonempty status.

Bug fixes:

- The manifest file parser was incorrectly allowing project names which contain the path separator characters `/` and `.`. These invalid characters are now rejected.

  Note: if you need to place a project within a subdirectory of the workspace `topdir`, use the `path:` key. If you need to customize a project's fetch URL relative to its remote `url-base`, use `repo-path:`. See Projects for examples.

- The changes made in west v0.10.1 to the `west init --manifest-rev` option which selected the default branch name were leaving the manifest repository in a detached HEAD state. This has been fixed by using `git clone` internally instead of `git init` and `git fetch`. See issue #522 for details.

- The `WEST_CONFIG_LOCAL` environment variable now correctly overrides the default location, `<workspace topdir>/.west/config`.

- `west update --fetch=smart` (smart is the default) now correctly skips fetches for project revisions which are lightweight tags (it already worked correctly for annotated tags; only lightweight tags were unnecessarily fetched).

Other changes:

- The fix for issue #522 mentioned above introduces a new restriction. The `west init --manifest-rev` option value, if given, must now be either a branch or a tag. In particular, "pseudo-branches" like GitHub's `pull/1234/head` references which could previously be used to fetch a pull request can no longer be passed to `--manifest-rev`. Users must now fetch and check out such revisions manually after running `west init`.

API changes:
• `west.manifest.Manifest.get_projects()` avoids incorrect results in some edge cases described in issue #523.
• `west.manifest.Project.sha()` now works correctly for tag revisions. (This applies to both lightweight and annotated tags.)

v0.11.0
New features:
• `west update` now supports `--narrow`, `--name-cache`, and `--path-cache` options. These can be influenced by the `update.narrow`, `update.name-cache`, and `update.path-cache` `Configuration` options. These can be used to optimize the speed of the update.
• `west update` now supports a `--fetch-opt` option that will be passed to the `git fetch` command used to fetch remote revisions when updating each project.

Bug fixes:
• `west update` now synchronizes Git submodules in projects by default. This avoids issues if the URL changes in the manifest file from when the submodule was first initialized. This behavior can be disabled by setting the `update.sync-submodules` configuration option to `false`.

Other changes:
• the `west-apis-manifest` module has fixed docstrings for the `Project` class

v0.10.1
New features:
• The `west init` command's `--manifest-rev (--mr)` option no longer defaults to `master`. Instead, the command will query the repository for its default branch name and use that instead. This allows users to move from `master` to `main` without breaking scripts that do not provide this option.

v0.10.0
New features:
• The `name` key in a project's `submodules list` is now optional.

Bug fixes:
• West now checks that the manifest schema version is one of the explicitly allowed values documented in `Version`. The old behavior was just to check that the schema version was newer than the `west` version where the `manifest:` `version:` key was introduced. This incorrectly allowed invalid schema versions, like `0.8.2`.

Other changes:
• A manifest file's `group-filter` is now propagated through an import. This is a change from how `west v0.9.x` handled this. In `west v0.9.x`, only the top level manifest file's `group-filter` had any effect; the group filter lists from any imported manifests were ignored.

Starting with `west v0.10.0`, the group filter lists from imported manifests are also imported. For details, see `Group Filters and Imports`.

The new behavior will take effect if `manifest: version:` is not given or is at least 0.10. The old behavior is still available in the top level manifest file only with an explicit `manifest: version:` 0.9. See `Version` for more information on schema versions.

See `west pull request #482` for the motivation for this change and additional context.
v0.9.1

Bug fixes:
- Commands like `west manifest --resolve` now correctly include group and group filter information.

Other changes:
- West now warns if you combine `import` with `group-filter`. Semantics for this combination have changed starting with v0.10.x. See the v0.10.0 release notes above for more information.

v0.9.0

**Warning:** The `west config` fix described below comes at a cost: any comments or other manual edits in configuration files will be removed when setting a configuration option via that command or the `west.configuration` API.

**Warning:** Combining the `group-filter` feature introduced in this release with manifest imports is discouraged. The resulting behavior has changed in west v0.10.

New features:
- West manifests now support *Git Submodules in Projects*. This allows you to clone Git submodules into a west project repository in addition to the project repository itself.
- West manifests now support *Project Groups and Active Projects*. Project groups can be enabled and disabled to determine what projects are “active”, and therefore will be acted upon by the following commands: `west update`, `west list`, `west diff`, `west status`, `west forall`.
- `west update` no longer updates inactive projects by default. It now supports a `--group-filter` option which allows for one-time modifications to the set of enabled and disabled project groups.
- Running `west list`, `west diff`, `west status`, or `west forall` with no arguments does not print information for inactive projects by default. If the user specifies a list of projects explicitly at the command line, output for them is included regardless of whether they are active. These commands also now support `--all` arguments to include all projects, even inactive ones.
- `west list` now supports a `{groups}` format string key in its `--format` argument.

Bug fixes:
- The `west config` command and `west.configuration` API did not correctly store some configuration values, such as strings which contain commas. This has been fixed; see commit 36f3f91e for details.
- A manifest file with an empty `manifest: self: path: value` is invalid, but west used to let it pass silently. West now rejects such manifests.
- A bug affecting the behavior of the `west init -l` command was fixed; see issue #435.

API changes:
- added `west.manifest.Manifest.is_active()`
- added `west.manifest.Manifest.group_filter`
- added `submodules` attribute to `west.manifest.Project`, which has newly added type `west.manifest.Submodule`

Other changes:
• The Manifest Imports feature now supports the terms allowlist and blocklist instead of whitelist and blacklist, respectively.

The old terms are still supported for compatibility, but the documentation has been updated to use the new ones exclusively.

v0.8.0

This is a feature release which changes the manifest schema by adding support for a path-prefix: key in an import: mapping, along with some other features and fixes.

• Manifest import mappings now support a path-prefix: key, which places the project and its imported repositories in a subdirectory of the workspace. See Example 3.4: Import into a subdirectory for an example.

• The west command line application can now also be run using python3 -m west. This makes it easier to run west under a particular Python interpreter without modifying the PATH environment variable.

• west manifest -path prints the absolute path to west.yml

• west init now supports an --mf foo.yml option, which initializes the workspace using foo.yml instead of west.yml.

• west list now prints the manifest repository's path using the manifest.path configuration option, which may differ from the self: path: value in the manifest data. The old behavior is still available, but requires passing a new --manifest-path-from-yaml option.

• Various Python API changes; see west-apis for details.

v0.7.3

This is a bugfix release.

• Fix an error where a failed import could leave the workspace in an unusable state (see [PR #415](https://github.com/zephyrproject-rtos/west/pull/415) for details)

v0.7.2

This is a bugfix and minor feature release.

• Filter out duplicate extension commands brought in by manifest imports

• Fix west.Manifest.get_projects() when finding the manifest repository by path

v0.7.1

This is a bugfix and minor feature release.

• west update --stats now prints timing for operations which invoke a subprocess, time spent in west's Python process for each project, and total time updating each project.

• west todir always prints a POSIX style path

• minor console output changes
The main user-visible feature in west 0.7 is the Manifest Imports feature. This allows users to load west manifest data from multiple different files, resolving the results into a single logical manifest.

Additional user-visible changes:

- The idea of a “west installation” has been renamed to “west workspace” in this documentation and in the west API documentation. The new term seems to be easier for most people to work with than the old one.
- West manifests now support a schema version.
- The “west config” command can now be run outside of a workspace, e.g. to run `west config --global section.key value` to set a configuration option’s value globally.
- There is a new `west todir` command, which prints the root directory of the current west workspace.
- The `west -vv init` command now prints the git operations being performed, and their results.
- The restriction that no project can be named “manifest” is now enforced; the name “manifest” is reserved for the manifest repository, and is usable as such in commands like `west list manifest`, instead of `west list path-to-manifest-repository` being the only way to say that
- It’s no longer an error if there is no project named “zephyr”. This is part of an effort to make west generally usable for non-Zephyr use cases.
- Various bug fixes.

The developer-visible changes to the west-apis are:

- west.build and west.cmake: deprecated; this is Zephyr-specific functionality and should never have been part of west. Since Zephyr v1.14 LTS relies on it, it will continue to be included in the distribution, but will be removed when that version of Zephyr is obsoleted.
- west.commands:
  - `WestCommand.requires_installation`: deprecated; use `requires_workspace` instead
  - `WestCommand.requires_workspace`: new
  - `WestCommand.has_manifest`: new
  - `WestCommand.manifest`: this is now settable
- west.configuration: callers can now identify the workspace directory when reading and writing configuration files
- west.log:
  - `msg()`: new
- west.manifest:
  - The module now uses the standard logging module instead of `west.log`
  - `QUAL_REFS_WEST`: new
  - `SCHEMA_VERSION`: new
  - Defaults: removed
  - `Manifest.as_dict()`: new
  - `Manifest.as_frozen_yaml()`: new
  - `Manifest.as_yaml()`: new
  - `Manifest.from_file()` and `from_data()`: these factory methods are more flexible to use and less reliant on global state
  - `Manifest.validate()`: new
- ManifestImportFailed: new
- ManifestProject: semi-deprecated and will likely be removed later.
- Project: the constructor now takes a todir argument
- Project.format() and its callers are removed. Use f-strings instead.
- Project.name_and_path: new
- Project.remote_name: new
- Project.sha() now captures stderr
- Remote: removed

West now requires Python 3.6 or later. Additionally, some features may rely on Python dictionaries being insertion-ordered; this is only an implementation detail in CPython 3.6, but is part of the language specification as of Python 3.7.

v0.6.3

This point release fixes an error in the behavior of the deprecated west.cmake module.

v0.6.2

This point release fixes an error in the behavior of west update --fetch=smart, introduced in v0.6.1. All v0.6.1 users must upgrade.

v0.6.1

**Warning:** Do not use this point release. Make sure to use v0.6.2 instead.

The user-visible features in this point release are:

- The `west update` command has a new `--fetch` command line flag and `update.fetch` configuration option. The default value, "smart", skips fetching SHAs and tags which are available locally.
- Better and more consistent error-handling in the `west diff`, `west status`, `west forall`, and `west update` commands. Each of these commands can operate on multiple projects; if a subprocess related to one project fails, these commands now continue to operate on the rest of the projects. All of them also now report a nonzero error code from the west process if any of these subprocesses fails (this was previously not true of `west forall` in particular).
- The `west manifest` command also handles errors better.
- The `west list` command now works even when the projects are not cloned, as long as its format string only requires information which can be read from the manifest file. It still fails if the format string requires data stored in the project repository, e.g. if it includes the `{sha}` format string key.
- Commands and options which operate on git revisions now accept abbreviated SHAs. For example, `west init --mr SHA_PREFIX` now works. Previously, the `--mr` argument needed to be the entire 40 character SHA if it wasn’t a branch or a tag.

The developer-visible changes to the west-apis are:

- `west.log.banner()`: new
- `west.log.small_banner()`: new
- `west.manifest.Manifest.get_projects()`: new
• west.manifest.Project.is_cloned(): new
• west.commands.WestCommand instances can now access the parsed Manifest object via a new
  self.manifest property during the do_run() call. If read, it returns the Manifest object or aborts the
  command if it could not be parsed.
• west.manifest.Project.git() now has a capture_stderr kwarg

v0.6.0

• No separate bootstrapper

In west v0.5.x, the program was split into two components, a bootstrapper and a per-installation
clone. See Multiple Repository Management in the v1.14 documentation for more details.

This is similar to how Google’s Repo tool works, and lets west iterate quickly at first. It caused
confusion, however, and west is now stable enough to be distributed entirely as one piece via PyPI.

From v0.6.x onwards, all of the core west commands and helper classes are part of the west package
distributed via PyPI. This eliminates complexity and makes it possible to import west modules from
anywhere in the system, not just extension commands.

• The selfupdate command still exists for backwards compatibility, but now simply exits after print-
ing an error message.
• Manifest syntax changes
  - A west manifest file's projects elements can now specify their fetch URLs directly, like so:

    ```
    manifest:
      projects:
        - name: example-project-name
          url: https://github.com/example/example-project
    ```

    Project elements with url attributes set in this way may not also have remote attributes.
  - Project names must be unique: this restriction is needed to support future work, but was not
    possible in west v0.5.x because distinct projects may have URLs with the same final pathname
    component, like so:

    ```
    manifest:
      remotes:
        - name: remote-1
          url-base: https://github.com/remote-1
        - name: remote-2
          url-base: https://github.com/remote-2
      projects:
        - name: project
          remote: remote-1
          path: remote-1-project
        - name: project
          remote: remote-2
          path: remote-2-project
    ```

    These manifests can now be written with projects that use url instead of remote, like so:

    ```
    manifest:
      projects:
        - name: remote-1-project
          url: https://github.com/remote-1/project
        - name: remote-2-project
          url: https://github.com/remote-2/project
    ```
• The `west list` command now supports a `{sha}` format string key
• The default format string for `west list` was changed to "{name:12} {path:28} {revision:40} {url}".
• The command `west manifest --validate` can now be run to load and validate the current manifest file, among other error-handling fixes related to manifest parsing.
• Incompatible API changes were made to `west`'s APIs. Further changes are expected until API stability is declared in `west v1.0`.

  – The `west.manifest.Project` constructor's `remote` and `defaults` positional arguments are now kwargs. A new `url` kwarg was also added; if given, the `Project` URL is set to that value, and the `remote` kwarg is ignored.
  – `west.manifest.MANIFEST_SECTIONS` was removed. There is only one section now, namely `manifest`. The `sections` kwarg in the `west.manifest.Manifest` factory methods and constructor were also removed.
  – The `west.manifest.SpecialProject` class was removed. Use `west.manifest.ManifestProject` instead.

v0.5.x

West v0.5.x is the first version used widely by the Zephyr Project as part of its v1.14 Long-Term Support (LTS) release. The `west v0.5.x documentation` is available as part of the Zephyr's v1.14 documentation.

West's main features in v0.5.x are:

• Multiple repository management using Git repositories, including self-update of west itself
• Hierarchical configuration files
• Extension commands

Versions Before v0.5.x

Tags in the `west` repository before v0.5.x are prototypes which are of historical interest only.

2.10.3 Troubleshooting West

This page covers common issues with `west` and how to solve them.

`west update` fetching failures

One good way to troubleshoot fetching issues is to run `west update` in verbose mode, like this:

```sh
west -v update
```

The output includes Git commands run by `west` and their outputs. Look for something like this:

```sh
=== updating your_project (path/to/your/project):
w west.manifest: your_project: checking if cloned
[...other west.manifest logs...]
--- your_project: fetching, need revision SOME_SHA
w west.manifest: running 'git fetch ... https://github.com/your-username/your_project .. --.' in /some/directory
```
The `git fetch` command example in the last line above is what needs to succeed.

One strategy is to go to `/some/directory`, copy/paste and run the entire `git fetch` command, then debug from there using the documentation for your credential storage helper.

If you’re behind a corporate firewall and may have proxy or other issues, `curl -v FETCH_URL` (for HTTPS URLs) or `ssh -v FETCH_URL` (for SSH URLs) may be helpful.

If you can get the `git fetch` command to run successfully without prompting for a password when you run it directly, you will be able to run `west update` without entering your password in that same shell.

"'west' is not recognized as an internal or external command, operable program or batch file.'"

On Windows, this means that either west is not installed, or your `PATH` environment variable does not contain the directory where pip installed `west.exe`.

First, make sure you’ve installed west; see `Installing west`. Then try running `west` from a new `cmd.exe` window. If that still doesn't work, keep reading.

You need to find the directory containing `west.exe`, then add it to your `PATH`. (This `PATH` change should have been done for you when you installed Python and pip, so ordinarily you should not need to follow these steps.)

Run this command in `cmd.exe`:

```
pip3 show west
```

Then:

1. Look for a line in the output that looks like `Location: C:\foo\python\python38\lib\site-packages`. The exact location will be different on your computer.

2. Look for a file named `west.exe` in the `scripts` directory `C:\foo\python\python38\scripts`.

    **Important:** Notice how `lib\site-packages` in the `pip3 show` output was changed to `scripts`!

3. If you see `west.exe` in the `scripts` directory, add the full path to `scripts` to your `PATH` using a command like this:

    ```
    setx PATH "%PATH%;C:\foo\python\python38\scripts"
    ```

4. Close your `cmd.exe` window and open a new one. You should be able to run `west`.

"'Error: unexpected keyword argument 'requires_workspace'"

This error occurs on some Linux distributions after upgrading to west 0.7.0 or later from 0.6.x. For example:

```
$ west update
[... stack trace ...]
TypeError: __init__() got an unexpected keyword argument 'requires_workspace'
```

This appears to be a problem with the distribution's pip; see this comment in west issue 373 for details. Some versions of Ubuntu and Linux Mint are known to have this problem. Some users report issues on Fedora as well.

Neither macOS nor Windows users have reported this issue. There have been no reports of this issue on other Linux distributions, like Arch Linux, either.
Workaround 1: remove the old version, then upgrade:

```
$ pip3 show west | grep Location: | cut -f 2 -d ' ' 
/home/foo/.local/lib/python3.6/site-packages
$ rm -r /home/foo/.local/lib/python3.6/site-packages/west
$ pip3 install --user west==0.7.0
```

Workaround 2: install west in a Python virtual environment

One option is to use the venv module that's part of the Python 3 standard library. Some distributions remove this module from their base Python 3 packages, so you may need to do some additional work to get it installed on your system.

“invalid choice: ‘build’” (or ‘flash’, etc.)

If you see an unexpected error like this when trying to run a Zephyr extension command (like west flash, west build, etc.):

```
$ west build [...]  
west: error: argument <command>: invalid choice: 'build' (choose from 'init', [...] )
```

```
$ west flash [...]  
west: error: argument <command>: invalid choice: 'flash' (choose from 'init', [...] )
```

The most likely cause is that you're running the command outside of a west workspace. West needs to know where your workspace is to find Extensions.

To fix this, you have two choices:

1. Run the command from inside a workspace (e.g. the zephyrproject directory you created when you got started).
   For example, create your build directory inside the workspace, or run west flash --build-dir YOUR_BUILD_DIR from inside the workspace.

2. Set the ZEPHYR_BASE environment variable and re-run the west extension command. If set, west will use ZEPHYR_BASE to find your workspace.

If you're unsure whether a command is built-in or an extension, run west help from inside your workspace. The output prints extension commands separately, and looks like this for mainline Zephyr:

```
$ west help

built-in commands for managing git repositories:
  init: create a west workspace
  [...]  

other built-in commands:
  help: get help for west or a command
  [...]  

extension commands from project manifest (path: zephyr):
  build: compile a Zephyr application
  flash: flash and run a binary on a board
  [...]  
```

“invalid choice: ‘post-init’”

If you see this error when running west init:
west: error: argument <command>: invalid choice: 'post-init'
(choose from 'init', 'update', 'list', 'manifest', 'diff',
'status', 'forall', 'config', 'selfupdate', 'help')

Then you have an old version of west installed, and are trying to use it in a workspace that requires a more recent version.

The easiest way to resolve this issue is to upgrade west and retry as follows:

1. Install the latest west with the -U option for pip3 install as shown in Installing west.
2. Back up any contents of zephyrproject/.west/config that you want to save. (If you don't have any configuration options set, it's safe to skip this step.)
3. Completely remove the zephyrproject/.west directory (if you don't, you will get the “already in a workspace” error message discussed next).
4. Run west init again.

“already in an installation”

You may see this error when running west init with west 0.6:

FATAL ERROR: already in an installation (<some directory>), aborting

If this is unexpected and you're really trying to create a new west workspace, then it's likely that west is using the ZEPHYR_BASE environment variable to locate a workspace elsewhere on your system.

This is intentional; it allows you to put your Zephyr applications in any directory and still use west to build, flash, and debug them, for example.

To resolve this issue, unset ZEPHYR_BASE and try again.

2.10.4 Basics

This page introduces west's basic concepts and provides references to further reading.

West's built-in commands allow you to work with projects (Git repositories) under a common workspace directory.

Example workspace

If you've followed the upstream Zephyr getting started guide, your workspace looks like this:

```
zephyrproject/   # west topdir
    .west/       # marks the location of the topdir
        config  # per-workspace local configuration file

    # The manifest repository, never modified by west after creation:
    zephyr/      # .git/ repo
        west.yml # manifest file
            [... other files ...]

    # Projects managed by west:
    modules/
        lib/
            tinycbor/  # .git/ project
    net-tools/  # .git/ project
            [... other projects ...]
```
Workspace concepts

Here are the basic concepts you should understand about this structure. Additional details are in Workspaces.

topdir

Above, zephyrproject is the name of the workspace’s top level directory, or topdir. (The name zephyrproject is just an example – it could be anything, like z, my-zephyr-workspace, etc.) You’ll typically create the topdir and a few other files and directories using west init.

.west directory

The topdir contains the .west directory. When west needs to find the topdir, it searches for .west, and uses its parent directory. The search starts from the current working directory (and starts again from the location in the ZEPHYR_BASE environment variable as a fallback if that fails).

configuration file

The file .west/config is the workspace’s local configuration file.

manifest repository

Every west workspace contains exactly one manifest repository, which is a Git repository containing a manifest file. The location of the manifest repository is given by the manifest.path configuration option in the local configuration file. For upstream Zephyr, zephyr is the manifest repository, but you can configure west to use any Git repository in the workspace as the manifest repository. The only requirement is that it contains a valid manifest file. See Topologies supported for information on other options, and West Manifests for details on the manifest file format.

manifest file

The manifest file is a YAML file that defines projects, which are the additional Git repositories in the workspace managed by west. The manifest file is named west.yml by default; this can be overridden using the manifest.file local configuration option. You use the west update command to update the workspace’s projects based on the contents of the manifest file.

projects

Projects are Git repositories managed by west. Projects are defined in the manifest file and can be located anywhere inside the workspace. In the above example workspace, tinycbor and net-tools are projects. By default, the Zephyr build system uses west to get the locations of all the projects in the workspace, so any code they contain can be used as Modules (External projects).

extensions

Any repository known to west (either the manifest repository or any project repository) can define Extensions. Extensions are extra west commands you can run when using that workspace. The zephyr repository uses this feature to provide Zephyr-specific commands like west build. Defining these as extensions keeps west’s core agnostic to the specifics of any workspace’s Zephyr version, etc.

ignored files

A workspace can contain additional Git repositories or other files and directories not managed by west. West basically ignores anything in the workspace except .west, the manifest repository, and the projects specified in the manifest file.

west init and west update

The two most important workspace-related commands are west init and west update.
west init basics  This command creates a west workspace.

**Important:** West doesn't change your manifest repository contents after `west init` is run. Use ordinary Git commands to pull new versions, etc.

You will typically run it once, like this:

```shell
west init -m https://github.com/zephyrproject-rtos/zephyr --mr v2.5.0 zephyrproject
```

This will:

1. Create the topdir, `zephyrproject`, along with `.west` and `.west/config` inside it
2. Clone the manifest repository from `https://github.com/zephyrproject-rtos/zephyr`, placing it into `zephyrproject/zephyr`
3. Check out the `v2.5.0` git tag in your local zephyr clone
4. Set `manifest.path` to `zephyr` in `.west/config`
5. Set `manifest.file` to `west.yml`

Your workspace is now almost ready to use; you just need to run `west update` to clone the rest of the projects into the workspace to finish.

For more details, see `west init`.

west update basics  This command makes sure your workspace contains Git repositories matching the projects in the manifest file.

**Important:** Whenever you check out a different revision in your manifest repository, you should run `west update` to make sure your workspace contains the project repositories the new revision expects.

The `west update` command reads the manifest file's contents by:

1. Finding the topdir. In the `west init` example above, that means finding `zephyrproject`.
2. Loading `.west/config` in the topdir to read the `manifest.path` (e.g. `zephyr`) and `manifest.file` (e.g. `west.yml`) options.
3. Loading the manifest file given by these options (e.g. `zephyrproject/zephyr/west.yml`).

It then uses the manifest file to decide where missing projects should be placed within the workspace, what URLs to clone them from, and what Git revisions should be checked out locally. Project repositories which already exist are updated in place by fetching and checking out their respective Git revisions in the manifest file.

For more details, see `west update`.

Other built-in commands

See *[Built-in commands]*.

Zephyr Extensions

See the following pages for information on Zephyr's extension commands:

- *Building, Flashing and Debugging*
- *Signing Binaries*
Additional Zephyr extension commands

Enabling shell completion

Troubleshooting

See Troubleshooting West.

2.10.5 Built-in commands

This page describes west's built-in commands, some of which were introduced in Basics, in more detail. Some commands are related to Git commands with the same name, but operate on the entire workspace. For example, west diff shows local changes in multiple Git repositories in the workspace.

Some commands take projects as arguments. These arguments can be project names as specified in the manifest file, or (as a fallback) paths to them on the local file system. Omitting project arguments to commands which accept them (such as west list, west forall, etc.) usually defaults to using all projects in the manifest file plus the manifest repository itself.

For additional help, run west <command> -h (e.g. west init -h).

west init

This command creates a west workspace. It can be used in two ways:

1. Cloning a new manifest repository from a remote URL
2. Creating a workspace around an existing local manifest repository

**Option 1**: to clone a new manifest repository from a remote URL, use:

```
west init [-m URL] [--mr REVISION] [--mf FILE] [directory]
```

The new workspace is created in the given directory, creating a new .west inside this directory. You can give the manifest URL using the -m switch, the initial revision to check out using --mr, and the location of the manifest file within the repository using --mf.

For example, running:

```
wes init -m https://github.com/zephyrproject-rtos/zephyr --mr v1.14.0 zp
```

would clone the upstream official zephyr repository into zp/zephyr, and check out the v1.14.0 release. This command creates zp/.west, and set the manifest.path configuration option to zephyr to record the location of the manifest repository in the workspace. The default manifest file location is used.

The -m option defaults to https://github.com/zephyrproject-rtos/zephyr. The --mf option defaults to west.yml. Since west v0.10.1, west will use the default branch in the manifest repository unless the --mr option is used to override it. (In prior versions, --mr defaulted to master.)

If no directory is given, the current working directory is used.

**Option 2**: to create a workspace around an existing local manifest repository, use:

```
west init -l [--mf FILE] directory
```

This creates .west next to directory in the file system, and sets manifest.path to directory.

As above, --mf defaults to west.yml.

Reconfiguring the workspace:
If you change your mind later, you are free to change `manifest.path` and `manifest.file` using `west config` after running `west init`. Just be sure to run `west update` afterwards to update your workspace to match the new manifest file.

```bash
west update
```

```bash
west update [-f {always,smart}] [-k] [-r]
            [--group-filter FILTER] [--stats] [PROJECT ...]
```

**Which projects are updated:**

By default, this command parses the manifest file, usually `west.yml`, and updates each project specified there. If your manifest uses `project groups`, then only the active projects are updated.

To operate on a subset of projects only, give `PROJECT` argument(s). Each `PROJECT` is either a project name as given in the manifest file, or a path that points to the project within the workspace. If you specify projects explicitly, they are updated regardless of whether they are active.

**Project update procedure:**

For each project that is updated, this command:

1. Initializes a local Git repository for the project in the workspace, if it does not already exist
2. Inspects the project's `revision` field in the manifest, and fetches it from the remote if it is not already available locally
3. Sets the project's `manifest-rev` branch to the commit specified by the revision in the previous step
4. Checks out `manifest-rev` in the local working copy as a detached HEAD
5. If the manifest file specifies a `submodules` key for the project, recursively updates the project's submodules as described below.

To avoid unnecessary fetches, `west update` will not fetch project `revision` values which are Git SHAs or tags that are already available locally. This is the behavior when the `-f` (`--fetch`) option has its default value, `smart`. To force this command to fetch from project remotes even if the revisions appear to be available locally, either use `-f always` or set the `update.fetch` configuration option to `always`. SHAs may be given as unique prefixes as long as they are acceptable to Git.

If the project `revision` is a Git ref that is neither a tag nor a SHA (i.e. if the project is tracking a branch), `west update` always fetches, regardless of `-f` and `update.fetch`.

Some branch names might look like short SHAs, like `deadbeef`. West treats these like SHAs. You can disambiguate by prefixing the revision value with `refs/heads/`, e.g. `revision: refs/heads/deadbeef`.

For safety, `west update` uses `git checkout --detach` to check out a detached HEAD at the manifest revision for each updated project, leaving behind any branches which were already checked out. This is typically a safe operation that will not modify any of your local branches.

However, if you had added some local commits onto a previously detached HEAD checked out by west, then git will warn you that you've left behind some commits which are no longer referred to by any branch. These may be garbage-collected and lost at some point in the future. To avoid this if you have local commits in the project, make sure you have a local branch checked out before running `west update`.

If you would rather rebase any locally checked out branches instead, use the `-r` (`--rebase`) option.

If you would like `west update` to keep local branches checked out as long as they point to commits that are descendants of the new `manifest-rev`, use the `-k` (`--keep-descendants`) option.

---

1 West may fetch all refs from the Git server when given a SHA as a revision. This is because some Git servers have historically not allowed fetching SHAs directly.
**Note:** `west update --rebase` will fail in projects that have git conflicts between your branch and new commits brought in by the manifest. You should immediately resolve these conflicts as you usually do with git, or you can use `git -C <project_path> rebase --abort` to ignore incoming changes for the moment.

With a clean working tree, a plain `west update` never fails because it does not try to hold on to your commits and simply leaves them aside.

`west update --keep-descendants` offers an intermediate option that never fails either but does not treat all projects the same:

- in projects where your branch diverged from the incoming commits, it does not even try to rebase and leaves your branches behind just like a plain `west update` does;
- in all other projects where no rebase or merge is needed it keeps your branches in place.

**One-time project group manipulation:**

The `--group-filter` option can be used to change which project groups are enabled or disabled for the duration of a single `west update` command. See *Project Groups and Active Projects* for details on the project group feature.

The `west update` command behaves as if the `--group-filter` option's value were appended to the `manifest.group-filter` configuration option.

For example, running `west update --group-filter=+foo,-bar` would behave the same way as if you had temporarily appended the string "+foo,-bar" to the value of `manifest.group-filter`, run `west update`, then restored `manifest.group-filter` to its original value.

Note that using the syntax `--group-filter=VALUE` instead of `--group-filter VALUE` avoids issues parsing command line options if you just want to disable a single group, e.g. `--group-filter=-bar`.

**Submodule update procedure:**

If a project in the manifest has a `submodules` key, the submodules are updated as follows, depending on the value of the submodules key.

If the project has `submodules: true`, west first synchronizes the project's submodules with:

```sh
git submodule sync --recursive
```

West then runs one of the following in the project repository, depending on whether you run `west update` with the `--rebase` option or without it:

```sh
# without --rebase, e.g. "west update":
git submodule update --init --checkout --recursive

# with --rebase, e.g. "west update --rebase":
git submodule update --init --rebase --recursive
```

Otherwise, the project has `submodules: <list-of-submodules>`. In this case, west synchronizes the project's submodules with:

```sh
git submodule sync --recursive -- <submodule-path>
```

Then it updates each submodule in the list as follows, depending on whether you run `west update` with the `--rebase` option or without it:

```sh
# without --rebase, e.g. "west update":
git submodule update --init --checkout --recursive <submodule-path>

# with --rebase, e.g. "west update --rebase":
git submodule update --init --rebase --recursive <submodule-path>
```
The `git submodule sync` commands are skipped if the `update.sync-submodules` Configuration option is false.

**Other project commands**

West has a few more commands for managing the projects in the workspace, which are summarized here. Run `west <command> -h` for detailed help.

- `west list`: print a line of information about each project in the manifest, according to a format string
- `west manifest`: manage the manifest file. See *Manifest Command*.
- `west diff`: run `git diff` in local project repositories
- `west status`: run `git status` in local project repositories
- `west forall`: run an arbitrary command in local project repositories

**Other built-in commands**

Finally, here is a summary of other built-in commands.

- `west config`: get or set configuration options
- `west todir`: print the top level directory of the west workspace
- `west help`: get help about a command, or print information about all commands in the workspace, including Extensions

### 2.10.6 Workspaces

This page describes the `west workspace` concept introduced in *Basics* in more detail.

**The manifest-rev branch**

West creates and controls a Git branch named `manifest-rev` in each project. This branch points to the revision that the manifest file specified for the project at the time `west update` was last run. Other workspace management commands may use `manifest-rev` as a reference point for the upstream revision as of this latest update. Among other purposes, the `manifest-rev` branch allows the manifest file to use SHAs as project revisions.

Although `manifest-rev` is a normal Git branch, west will recreate and/or reset it on the next update. For this reason, it is dangerous to check it out or otherwise modify it yourself. For instance, any commits you manually add to this branch may be lost the next time you run `west update`. Instead, check out a local branch with another name, and either rebase it on top of a new `manifest-rev`, or merge `manifest-rev` into it.

**Note:** West does not create a `manifest-rev` branch in the manifest repository, since `west` does not manage the manifest repository’s branches or revisions.

**The refs/west/* Git refs**

West also reserves all Git refs that begin with `refs/west/` (such as `refs/west/foo`) for itself in local project repositories. Unlike `manifest-rev`, these refs are not regular branches. West's behavior here is an implementation detail; users should not rely on these refs' existence or behavior.
Private repositories

You can use west to fetch from private repositories. There is nothing west-specific about this.

The west update command essentially runs `git fetch YOUR_PROJECT_URL` when a project's manifest-rev branch must be updated to a newly fetched commit. It's up to your environment to make sure the fetch succeeds.

You can either enter the password manually or use any of the credential helpers built in to Git. Since Git has credential storage built in, there is no need for a west-specific feature.

The following sections cover common cases for running `west update` without having to enter your password, as well as how to troubleshoot issues.

**Fetching via HTTPS**  On Windows when fetching from GitHub, recent versions of Git prompt you for your GitHub password in a graphical window once, then store it for future use (in a default installation). Passwordless fetching from GitHub should therefore work "out of the box" on Windows after you have done it once.

In general, you can store your credentials on disk using the "store" git credential helper. See the [git-credential-store](https://git-scm.com/docs/git-credential-store) manual page for details.

To use this helper for all the repositories in your workspace, run:

```bash
west forall -c "git config credential.helper store"
```

To use this helper on just the projects `foo` and `bar`, run:

```bash
west forall -c "git config credential.helper store" foo bar
```

To use this helper by default on your computer, run:

```bash
git config --global credential.helper store
```

On GitHub, you can set up a [personal access token](https://github.com/settings/applications/new) to use in place of your account password. (This may be required if your account has two-factor authentication enabled, and may be preferable to storing your account password in plain text even if two-factor authentication is disabled.)

You can use the Git credential store to authenticate with a GitHub PAT (Personal Access Token) like so:

```bash
echo "https://x-access-token:$GH_TOKEN@github.com" >> ~/.git-credentials
```

If you don't want to store any credentials on the file system, you can store them in memory temporarily using [git-credential-cache](https://git-scm.com/docs/git-credential-cache) instead.

If you setup fetching via SSH, you can use Git URL rewrite feature. The following command instructs Git to use SSH URLs for GitHub instead of HTTPS ones:

```bash
git config --global url."git@github.com:".insteadOf "https://github.com/"
```

**Fetching via SSH**  If your SSH key has no password, fetching should just work. If it does have a password, you can avoid entering it manually every time using [ssh-agent](https://manpages.ubuntu.com/manpages/bionic/man1/ssh-agent.1.html).

On GitHub, see [Connecting to GitHub with SSH](https://docs.github.com/en/extending-github/enterprise/set-up-ssh-for-github) for details on configuration and key creation.

**Project locations**

Projects can be located anywhere inside the workspace, but they may not “escape” it.

In other words, project repositories need not be located in subdirectories of the manifest repository or as immediate subdirectories of the topdir. However, projects must have paths inside the workspace.
You may replace a project's repository directory within the workspace with a symbolic link to elsewhere on your computer, but west will not do this for you.

**Topologies supported**

The following are example source code topologies supported by west.

- **T1**: star topology, zephyr is the manifest repository
- **T2**: star topology, a Zephyr application is the manifest repository
- **T3**: forest topology, freestanding manifest repository

**T1: Star topology, zephyr is the manifest repository**

- The zephyr repository acts as the central repository and specifies its *Modules (External projects)* in its `west.yml`
- Analogy with existing mechanisms: Git submodules with zephyr as the super-project

This is the default. See *Workspace concepts* for how mainline Zephyr is an example of this topology.

**T2: Star topology, application is the manifest repository**

- Useful for those focused on a single application
- A repository containing a Zephyr application acts as the central repository and names other projects required to build it in its `west.yml`. This includes the zephyr repository and any modules.
- Analogy with existing mechanisms: Git submodules with the application as the super-project, zephyr and other projects as submodules

A workspace using this topology looks like this:

```
west-workspace/
  application/ # .git/
    CMakeLists.txt
    prj.conf
    src/
      main.c
      west.yml # main manifest with optional import(s) and override(s)
  modules/
    lib/     # .git/ project from either the main manifest or some import.
      tinycbor/ # .git/ project from either the main manifest or some import.
    zephyr/ # .git/ project
      west.yml # This can be partially imported with lower precedence or ignored.

# Only the 'manifest-rev' version can be imported.
```

Here is an example application/west.yml which uses *Manifest Imports*, available since west 0.7, to import Zephyr v2.5.0 and its modules into the application manifest file:

```
# Example T2 west.yml, using manifest imports.
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
```

(continues on next page)
projects:
  - name: zephyr
    remote: zephyrproject-rtos
    revision: v2.5.0
    import: true
  self:
    path: application

You can still selectively “override” individual Zephyr modules if you use import: in this way; see Example 1.3: Downstream of a Zephyr release, with module fork for an example.

Another way to do the same thing is to copy/paste zephyr/west.yml to application/west.yml, adding an entry for the zephyr project itself, like this:

```yaml
# Equivalent to the above, but with manually maintained Zephyr modules.
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  defaults:
    remote: zephyrproject-rtos
  projects:
    - name: zephyr
      revision: v2.5.0
      west-commands: scripts/west-commands.yml
    - name: net-tools
      revision: some-sha-goes-here
      path: tools/net-tools
    # ... other Zephyr modules go here ...
  self:
    path: application
```

(The west-commands is there for Building, Flashing and Debugging and other Zephyr-specific Extensions. It's not necessary when using import.)

The main advantage to using import is not having to track the revisions of imported projects separately. In the above example, using import means Zephyr's module versions are automatically determined from the zephyr/west.yml revision, instead of having to be copy/pasted (and maintained) on their own.

### T3: Forest topology

- Useful for those supporting multiple independent applications or downstream distributions with no “central” repository
- A dedicated manifest repository which contains no Zephyr source code, and specifies a list of projects all at the same “level”
- Analogy with existing mechanisms: Google repo-based source distribution

A workspace using this topology looks like this:

```
west-workspace/
  app1/     # .git/ project
   |         
   |         
   |         CMakeLists.txt
   |         prj.conf
   |         src/
   |             main.c
  app2/     # .git/ project
   |         
   |         CMakeLists.txt
```

(continues on next page)
Here is an example T3 manifest-repo/west.yml which uses Manifest Imports, available since west 0.7, to import Zephyr v2.5.0 and its modules, then add the app1 and app2 projects:

```yaml
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
    - name: your-git-server
      url-base: https://git.example.com/your-company
  defaults:
    remote: your-git-server
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v2.5.0
      import: true
    - name: app1
      revision: SOME_SHA_OR_BRANCH_OR_TAG
    - name: app2
      revision: ANOTHER_SHA_OR_BRANCH_OR_TAG
  self:
    path: manifest-repo
```

You can also do this “by hand” by copy/pasting zephyr/west.yml as shown above for the T2 topology, with the same caveats.

### 2.10.7 West Manifests

This page contains detailed information about west’s multiple repository model, manifest files, and the west manifest command. For API documentation on the west.manifest module, see west-apis-manifest. For a more general introduction and command overview, see Basics.

#### Multiple Repository Model

West’s view of the repositories in a west workspace, and their history, looks like the following figure (though some parts of this example are specific to upstream Zephyr’s use of west):

The history of the manifest repository is the line of Git commits which is “floating” on top of the gray plane. Parent commits point to child commits using solid arrows. The plane below contains the Git commit history of the repositories in the workspace, with each project repository boxed in by a rectangle. Parent/child commit relationships in each repository are also shown with solid arrows.
The commits in the manifest repository (again, for upstream Zephyr this is the zephyr repository itself) each have a manifest file. The manifest file in each commit specifies the corresponding commits which it expects in each of the project repositories. This relationship is shown using dotted line arrows in the diagram. Each dotted line arrow points from a commit in the manifest repository to a corresponding commit in a project repository.

Notice the following important details:

- Projects can be added (like P1 between manifest repository commits D and E) and removed (P2 between the same manifest repository commits)
- Project and manifest repository histories don’t have to move forwards or backwards together:
  - P2 stays the same from A → B, as do P1 and P3 from F → G.
  - P3 moves forward from A → B.
  - P3 moves backward from C → D.

One use for moving backward in project history is to “revert” a regression by going back to a revision before it was introduced.

- Project repository commits can be “skipped”: P3 moves forward multiple commits in its history from B → C.
- In the above diagram, no project repository has two revisions “at the same time”: every manifest file refers to exactly one commit in the projects it cares about. This can be relaxed by using a branch name as a manifest revision, at the cost of being able to bisect manifest repository history.

**Manifest Files**

West manifests are YAML files. Manifests have a top-level `manifest` section with some subsections, like this:

```yaml
manifest:
  remotes:
```

(continues on next page)
In YAML terms, the manifest file contains a mapping, with a `manifest` key. Any other keys and their contents are ignored (west v0.5 also required a `west` key, but this is ignored starting with v0.6).

The manifest contains subsections, like `defaults`, `remotes`, `projects`, and `self`. In YAML terms, the value of the `manifest` key is also a mapping, with these “subsections” as keys. As of west v0.10, all of these “subsection” keys are optional.

The `projects` value is a list of repositories managed by west and associated metadata. We'll discuss it soon, but first we will describe the `remotes` section, which can be used to save typing in the `projects` list.

### Remotes

The `remotes` subsection contains a sequence which specifies the base URLs where projects can be fetched from.

Each `remotes` element has a name and a “URL base”. These are used to form the complete Git fetch URL for each project. A project's fetch URL can be set by appending a project-specific path onto a remote URL base. (As we'll see below, projects can also specify their complete fetch URLs.)

For example:

```yaml
manifest:
    # ...
remotes:
    - name: remote1
      url-base: https://git.example.com/base1
    - name: remote2
      url-base: https://git.example.com/base2
```

The `remotes` keys and their usage are in the following table.

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>name</td>
<td>Mandatory; a unique name for the remote.</td>
</tr>
<tr>
<td>url-base</td>
<td>A prefix that is prepended to the fetch URL for each project with this remote.</td>
</tr>
</tbody>
</table>

Above, two remotes are given, with names `remote1` and `remote2`. Their URL bases are respectively `https://git.example.com/base1` and `https://git.example.com/base2`. You can use SSH URL bases as well; for example, you might use `git@example.com:base1` if `remote1` supported Git over SSH as well. Anything acceptable to Git will work.

### Projects

The `projects` subsection contains a sequence describing the project repositories in the west workspace. Every project has a unique name. You can specify what Git remote URLs to use when cloning and fetching the projects, what revisions to track, and where the project should be stored on the local file system.

Here is an example. We'll assume the `remotes` given above.
manifest:
  # [... same remotes as above...]
projects:
- name: proj1
  remote: remote1
  path: extra/project-1
- name: proj2
  repo-path: my-path
  remote: remote2
  revision: v1.3
- name: proj3
  url: https://github.com/user/project-three
  revision: abcde413a111

In this manifest:

- proj1 has remote remote1, so its Git fetch URL is https://git.example.com/base1/proj1. The remote url-base is appended with a / and the project name to form the URL.

  Locally, this project will be cloned at path extra/project-1 relative to the west workspace's root directory, since it has an explicit path attribute with this value.

  Since the project has no revision specified, master is used by default. The current tip of this branch will be fetched and checked out as a detached HEAD when west next updates this project.

- proj2 has a remote and a repo-path, so its fetch URL is https://git.example.com/base2/my-path. The repo-path attribute, if present, overrides the default name when forming the fetch URL.

  Since the project has no path attribute, its name is used by default. It will be cloned into a directory named proj2. The commit pointed to by the v1.3 tag will be checked out when west updates the project.

- proj3 has an explicit url, so it will be fetched from https://github.com/user/project-three.

  Its local path defaults to its name, proj3. Commit abcde413a111 will be checked out when it is next updated.

The available project keys and their usage are in the following table. Sometimes we'll refer to the defaults subsection; it will be described next.
Table 2.3: projects elements keys

<table>
<thead>
<tr>
<th>Key(s)</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>name</td>
<td>Mandatory; a unique name for the project. The name cannot be one of the reserved values “west” or “manifest”. The name must be unique in the manifest file.</td>
</tr>
<tr>
<td>remote, url</td>
<td>Mandatory (one of the two, but not both). If the project has a remote, that remote’s url-base will be combined with the project’s name (or repo-path, if it has one) to form the fetch URL instead. If the project has a url, that’s the complete fetch URL for the remote Git repository. If the project has neither, the defaults section must specify a remote, which will be used as the the project’s remote. Otherwise, the manifest is invalid.</td>
</tr>
<tr>
<td>repo-path</td>
<td>Optional. If given, this is concatenated on to the remote’s url-base instead of the project’s name to form its fetch URL. Projects may not have both url and repo-path attributes.</td>
</tr>
<tr>
<td>revision</td>
<td>Optional. The Git revision that west update should check out. This will be checked out as a detached HEAD by default, to avoid conflicting with local branch names. If not given, the revision value from the defaults subsection will be used if present. A project revision can be a branch, tag, or SHA. The default revision is master if not otherwise specified. Using HEAD~0(^1) as the revision will cause west to keep the current state of the project.</td>
</tr>
<tr>
<td>path</td>
<td>Optional. Relative path specifying where to clone the repository locally, relative to the top directory in the west workspace. If missing, the project’s name is used as a directory name.</td>
</tr>
<tr>
<td>clone-depth</td>
<td>Optional. If given, a positive integer which creates a shallow history in the cloned repository limited to the given number of commits. This can only be used if the revision is a branch or tag.</td>
</tr>
<tr>
<td>west-commands</td>
<td>Optional. If given, a relative path to a YAML file within the project which describes additional west commands provided by that project. This file is named west-commands.yml by convention. See Extensions for details.</td>
</tr>
<tr>
<td>import</td>
<td>Optional. If true, imports projects from manifest files in the given repository into the current manifest. See Manifest Imports for details.</td>
</tr>
<tr>
<td>groups</td>
<td>Optional, a list of groups the project belongs to. See Project Groups and Active Projects for details.</td>
</tr>
<tr>
<td>submodules</td>
<td>Optional. You can use this to make west update also update Git submodules defined by the project. See Git Submodules in Projects for details.</td>
</tr>
<tr>
<td>userdata</td>
<td>Optional. The value is an arbitrary YAML value. See Repository user data.</td>
</tr>
</tbody>
</table>

**Defaults** The defaults subsection can provide default values for project attributes. In particular, the default remote name and revision can be specified here. Another way to write the same manifest we have been describing so far using defaults is:

```yaml
manifest:
  defaults:
    remote: remote1
    revision: v1.3

remotes:
  - name: remote1
    url-base: https://git.example.com/base1
  - name: remote2
    url-base: https://git.example.com/base2
```

\(^1\) In git, HEAD is a reference, whereas HEAD~\(<n>\) is a valid revision but not a reference. West fetches references, such as refs/heads/main or HEAD, and commits not available locally, but will not fetch commits if they are already available. HEAD~0 is resolved to a specific commit that is locally available, and therefore west will simply checkout the locally available commit, identified by HEAD~0.
The available **defaults** keys and their usage are in the following table.

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>remote</td>
<td>Optional. This will be used for a project’s <code>remote</code> if it does not have a <code>url</code> or <code>remote</code> key set.</td>
</tr>
<tr>
<td>revision</td>
<td>Optional. This will be used for a project’s <code>revision</code> if it does not have one set. If not given, the default is <code>master</code>.</td>
</tr>
</tbody>
</table>

**Self**  The **self** subsection can be used to control the manifest repository itself.

As an example, let’s consider this snippet from the zephyr repository’s `west.yml`:

```yaml
manifest:
    # ...
    self:
        path: zephyr
        west-commands: scripts/west-commands.yml
```

This ensures that the zephyr repository is cloned into path `zephyr`, though as explained above that would have happened anyway if cloning from the default manifest URL, `https://github.com/zephyrproject-rtos/zephyr`. Since the zephyr repository does contain extension commands, its `self` entry declares the location of the corresponding `west-commands.yml` relative to the repository root.

The available **self** keys and their usage are in the following table.

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>path</td>
<td>Optional. The <code>path west init</code> should clone the manifest repository into, relative to the west workspace <code>topdir</code>. If not given, the basename of the path component in the manifest repository URL will be used by default. For example, if the URL is <code>https://git.example.com/project-repo</code>, the manifest repository would be cloned to the directory <code>project-repo</code>.</td>
</tr>
<tr>
<td>west-commands</td>
<td>Optional. This is analogous to the same key in a project sequence element.</td>
</tr>
<tr>
<td>import</td>
<td>Optional. This is also analogous to the <code>projects</code> key, but allows importing projects from other files in the manifest repository. See <a href="#">Manifest Imports</a>.</td>
</tr>
</tbody>
</table>

**Version**  The `version` subsection can be used to mark the lowest version of the manifest file schema that can parse this file’s data:
The `manifest` schema `manifest-schema.yml` in the west source code repository is used to validate the manifest section. The current manifest version is 0.13, which is supported by west version v0.13.x.

The `version` value may be any one of these values: "0.7", "0.8", "0.9", "0.10", "0.12", "0.13". West v0.11 did not include any new features which broke the previous schema, so "0.11" is not a valid schema version.

West v0.10.x can load manifests with any of these version values, while west v0.9.x can only load versions up to "0.9", and so on.

West halts with an error if you ask it to load a manifest file written in a version it cannot handle.

Quoting the `version` value as shown above forces the YAML parser to treat it as a string. Without quotes, 0.10 in YAML is just the floating point value 0.1. You can omit the quotes if the value is the same when cast to string, but it’s best to include them. Always use quotes if you’re not sure.

**Group-filter** See *Project Groups and Active Projects*.

### Project Groups and Active Projects

You can use the `groups` and `group-filter` keys briefly described *above* to place projects into groups, and filter which groups are enabled. These keys appear in the manifest like this:

```yaml
manifest:
  version: "0.10"
  # marks that this file uses version 0.10 of the west manifest
  # file format.

The pykwalify schema `manifest-schema.yml` in the west source code repository is used to validate the manifest section. The current manifest version is 0.13, which is supported by west version v0.13.x.

The `version` value may be any one of these values: "0.7", "0.8", "0.9", "0.10", "0.12", "0.13". West v0.11 did not include any new features which broke the previous schema, so "0.11" is not a valid schema version.

West v0.10.x can load manifests with any of these version values, while west v0.9.x can only load versions up to "0.9", and so on.

West halts with an error if you ask it to load a manifest file written in a version it cannot handle.

Quoting the `version` value as shown above forces the YAML parser to treat it as a string. Without quotes, 0.10 in YAML is just the floating point value 0.1. You can omit the quotes if the value is the same when cast to string, but it’s best to include them. Always use quotes if you’re not sure.

**Group-filter** See *Project Groups and Active Projects*.

### Project Group Examples

You can enable or disable project groups using `group-filter`. Projects whose groups are all disabled are inactive; west essentially ignores inactive projects unless explicitly requested not to.

The next section introduces project groups; the following sections describe *Enabled and Disabled Project Groups* and *Active and Inactive Projects*. There are some basic examples in *Project Group Examples*.

Finally, *Group Filters and Imports* provides a simplified overview of how `group-filter` interacts with the `Manifest Imports` feature.

**Project Groups** Inside `manifest: projects:`, you can add a project to one or more groups. The `groups` key is a list of group names. Group names are strings.

For example, in this manifest fragment:

```yaml
manifest:
  projects:
    - name: project-1
      groups:
        - groupA
      - name: project-2
        groups:
          - groupB
          - groupC
      - name: project-3
```
The projects are in these groups:

- **project-1**: one group, named `groupA`
- **project-2**: two groups, named `groupB` and `groupC`
- **project-3**: no groups

Project group names must not contain commas (,), colons (:), or whitespace.

Group names must not begin with a dash (-) or the plus sign (+), but they may contain these characters elsewhere in their names. For example, `foo-bar` and `foo+bar` are valid groups, but `-foobar` and `+foobar` are not.

Group names are otherwise arbitrary strings. Group names are case sensitive.

As a restriction, no project may use both `import:` and `groups:`. (This avoids some edge cases whose semantics are difficult to specify.)

---

**Enabled and Disabled Project Groups**  
All project groups are enabled by default. You can enable or disable groups in both your manifest file and *Configuration*.

Within a manifest file, `manifest: group-filter:` is a YAML list of groups to enable and disable.

To enable a group, prefix its name with a plus sign (+). For example, `groupA` is enabled in this manifest fragment:

```yaml
manifest:
  group-filter: [+groupA]
```

Although this is redundant for groups that are already enabled by default, it can be used to override settings in an imported manifest file. See *Group Filters and Imports* for more information.

To disable a group, prefix its name with a dash (-). For example, `groupA` and `groupB` are disabled in this manifest fragment:

```yaml
manifest:
  group-filter: [-groupA,-groupB]
```

---

**Note:** Since `group-filter` is a YAML list, you could have written this fragment as follows:

```yaml
manifest:
  group-filter:
    - -groupA
    - -groupB
```

However, this syntax is harder to read and therefore discouraged.

---

In addition to the manifest file, you can control which groups are enabled and disabled using the `manifest.group-filter` configuration option. This option is a comma-separated list of groups to enable and/or disable.

To enable a group, add its name to the list prefixed with +. To disable a group, add its name prefixed with -. For example, setting `manifest.group-filter` to `+groupA,-groupB` enables `groupA`, and disables `groupB`.

The value of the configuration option overrides any data in the manifest file. You can think of this as if the `manifest.group-filter` configuration option is appended to the `manifest: group-filter:` list from YAML, with "last entry wins" semantics.
Active and Inactive Projects  All projects are active by default. Projects with no groups are always active. A project is inactive if all of its groups are disabled. This is the only way to make a project inactive.

Most west commands that operate on projects will ignore inactive projects by default. For example, west update when run without arguments will not update inactive projects. As another example, running west list without arguments will not print information for inactive projects.

Project Group Examples  This section contains example situations involving project groups and active projects. The examples use both manifest: group-filter: YAML lists and manifest.group-filter configuration lists, to show how they work together.

Note that the defaults and remotes data in the following manifests isn’t relevant except to make the examples complete and self-contained.

Example 1: no disabled groups  The entire manifest file is:

```yaml
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB
    - name: baz
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is not set (you can ensure this by running west config -D manifest.group-filter).

No groups are disabled, because all groups are enabled by default. Therefore, all three projects (foo, bar, and baz) are active. Note that there is no way to make project baz inactive, since it has no groups.

Example 2: Disabling one group via manifest  The entire manifest file is:

```yaml
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB
  group-filter: [-groupA]
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

(continues on next page)
The manifest.group-filter configuration option is not set (you can ensure this by running west config -D manifest.group-filter).

Since groupA is disabled, project foo is inactive. Project bar is active, because groupB is enabled.

**Example 3: Disabling multiple groups via manifest**  The entire manifest file is:

```plaintext
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB

  group-filter: [-groupA,-groupB]

defaults:
  remote: example-remote

remotes:
  - name: example-remote
    url-base: https://git.example.com
```

The manifest.group-filter configuration option is not set (you can ensure this by running west config -D manifest.group-filter).

Both foo and bar are inactive, because all of their groups are disabled.

**Example 4: Disabling a group via configuration**  The entire manifest file is:

```plaintext
manifest:
  projects:
    - name: foo
      groups:
        - groupA
    - name: bar
      groups:
        - groupA
        - groupB

  defaults:
    remote: example-remote

remotes:
  - name: example-remote
    url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to -groupA (you can ensure this by running west config manifest.group-filter -- -groupA; the extra -- is required so the argument parser does not treat -groupA as a command line option -g with value roupA).

Project foo is inactive because groupA has been disabled by the manifest.group-filter configuration option. Project bar is active because groupB is enabled.
Example 5: Overriding a disabled group via configuration  The entire manifest file is:

```
manifest:
  projects:
    - name: foo
    - name: bar
      groups:
        - groupA
      groups:
        - name: baz
        groups:
          - groupA
          - groupB
  group-filter: [-groupA]
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to +groupA (you can ensure this by running west config manifest.group-filter +groupA).

In this case, groupA is enabled: the manifest.group-filter configuration option has higher precedence than the manifest: group-filter: [-groupA] content in the manifest file.

Therefore, projects foo and bar are both active.

Example 6: Overriding multiple disabled groups via configuration  The entire manifest file is:

```
manifest:
  projects:
    - name: foo
    - name: bar
      groups:
        - groupA
      groups:
        - name: baz
        groups:
          - groupA
          - groupB
  group-filter: [-groupA,-groupB]
  defaults:
    remote: example-remote
  remotes:
    - name: example-remote
      url-base: https://git.example.com
```

The manifest.group-filter configuration option is set to +groupA,+groupB (you can ensure this by running west config manifest.group-filter "+groupA,+groupB").

In this case, both groupA and groupB are enabled, because the configuration value overrides the manifest file for both groups.

Therefore, projects foo and bar are both active.

Example 7: Disabling multiple groups via configuration  The entire manifest file is:
manifest:
  projects:
    - name: foo
    - name: bar
      groups:
        - groupA
    - name: baz
      groups:
        - groupA
        - groupB

defaults:
  remote: example-remote
remotes:
  - name: example-remote
    url-base: https://git.example.com

The manifest.group-filter configuration option is set to `-groupA,-groupB` (you can ensure this by running `west config manifest.group-filter -- "-groupA,-groupB"`).

In this case, both groupA and groupB are disabled.

Therefore, projects foo and bar are both inactive.

Group Filters and Imports This section provides a simplified description of how the manifest.group-filter: value behaves when combined with Manifest Imports. For complete details, see Manifest Import Details.

**Warning:** The below semantics apply to west v0.10.0 and later. West v0.9.x semantics are different, and combining group-filter with import in west v0.9.x is discouraged.

In short:

- if you only import one manifest, any groups it disables in its group-filter are also disabled in your manifest
- you can override this in your manifest file's manifest: group-filter: value, your workspace's manifest.group-filter configuration option, or both

Here are some examples.

**Example 1: no overrides** You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  projects:
    - name: child
      url: https://git.example.com/child
      import: true
    - name: project-1
      url: https://git.example.com/project-1
        groups:
          - unstable
```

And child/west.yml contains:
Only child and project-2 are active in the resolved manifest.

The unstable group is disabled in child/west.yml, and that is not overridden in parent/west.yml. Therefore, the final group-filter for the resolved manifest is [-unstable].

Since project-1 and project-3 are in the unstable group and are not in any other group, they are inactive.

**Example 2: overriding an imported group-filter via manifest**

You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  group-filter: [+unstable,-optional]
projects:
  - name: child
    url: https://git.example.com/child
    import: true
  - name: project-1
    url: https://git.example.com/project-1
    groups:
      - unstable
```

And child/west.yml contains:

```yaml
# child/west.yml:
manifest:
  group-filter: [-unstable]
projects:
  - name: project-2
    url: https://git.example.com/project-2
    groups:
      - optional
    - name: project-3
      url: https://git.example.com/project-3
      groups:
        - unstable
```

Only the child, project-1, and project-3 projects are active.

The [-unstable] group filter in child/west.yml is overridden in parent/west.yml, so the unstable group is enabled. Since project-1 and project-3 are in the unstable group, they are active.

The same parent/west.yml file disables the optional group, so project-2 is inactive.

The final group filter specified by parent/west.yml is [+unstable,-optional].
Example 3: overriding an imported group-filter via configuration

You are using this parent/west.yml manifest:

```yaml
# parent/west.yml:
manifest:
  projects:
    - name: child
      url: https://git.example.com/child
      import: true
    - name: project-1
      url: https://git.example.com/project-1
      groups:
      - unstable
```

And child/west.yml contains:

```yaml
# child/west.yml:
manifest:
  group-filter: [-unstable]
  projects:
    - name: project-2
      url: https://git.example.com/project-2
      groups:
        - optional
    - name: project-3
      url: https://git.example.com/project-3
      groups:
        - unstable
```

If you run:

```
west config manifest.group-filter +unstable,-optional
```

Then only the child, project-1, and project-3 projects are active.

The -unstable group filter in child/west.yml is overridden in the manifest.group-filter configuration option, so the unstable group is enabled. Since project-1 and project-3 are in the unstable group, they are active.

The same configuration option disables the optional group, so project-2 is inactive.

The final group filter specified by parent/west.yml and the manifest.group-filter configuration option is [+unstable,-optional].

Git Submodules in Projects

You can use the submodules keys briefly described above to force west update to also handle any Git submodules configured in project's git repository. The submodules key can appear inside projects, like this:

```yaml
manifest:
  projects:
    - name: some-project
      submodules: ...
```

The submodules key can be a boolean or a list of mappings. We’ll describe these in order.

**Option 1: Boolean**  
This is the easiest way to use submodules.
If `submodules` is true as a projects attribute, `west update` will recursively update the project's Git submodules whenever it updates the project itself. If it's false or missing, it has no effect.

For example, let's say you have a source code repository `foo`, which has some submodules, and you want `west update` to keep all of them them in sync, along with another project named `bar` in the same workspace.

You can do that with this manifest file:

```yaml
manifest:
  projects:
    - name: foo
      submodules: true
    - name: bar
```

Here, `west update` will initialize and update all submodules in `foo`. If `bar` has any submodules, they are ignored, because `bar` does not have a `submodules` value.

**Option 2: List of mappings** The `submodules` key may be a list of mappings, one list element for each desired submodule. Each submodule listed is updated recursively. You can still track and update unlisted submodules with `git` commands manually; present or not they will be completely ignored by `west`.

The `path` key must match exactly the path of one submodule relative to its parent west project, as shown in the output of `git submodule status`. The `name` key is optional and not used by `west` for now; it's not passed to `git submodule` commands either. The `name` key was briefly mandatory in `west` version 0.9.0, but was made optional in 0.9.1.

For example, let's say you have a source code repository `foo`, which has many submodules, and you want `west update` to keep some but not all of them in sync, along with another project named `bar` in the same workspace.

You can do that with this manifest file:

```yaml
manifest:
  projects:
    - name: foo
      submodules:
        - path: path/to/foo-first-sub
          name: foo-second-sub
        - path: path/to/foo-second-sub
    - name: bar
```

Here, `west update` will recursively initialize and update just the submodules in `foo` with paths `path/to/foo-first-sub` and `path/to/foo-second-sub`. Any submodules in `bar` are still ignored.

**Repository user data**

`west` versions v0.12 and later support an optional `userdata` key in projects.

`west` versions v0.13 and later supports this key in the `manifest: self:` section.

It is meant for consumption by programs that require user-specific project metadata. Beyond parsing it as YAML, `west` itself ignores the value completely.

The key's value is arbitrary YAML. `west` parses the value and makes it accessible to programs using `west-apis` as the `userdata` attribute of the corresponding `west.manifest.Project` object.

Example manifest fragment:
manifest:
  projects:
  - name: foo
  - name: bar
    userdata: a-string
  - name: baz
    userdata:
      key: value
  self:
    userdata: blub

Example Python usage:

manifest = west.manifest.Manifest.from_file()

foo, bar, baz = manifest.get_projects(['foo', 'bar', 'baz'])

foo.userdata # None
bar.userdata # 'a-string'
baz.userdata # {'key': 'value'}
manifest.userdata # 'blub'

**Manifest Imports**

You can use the import key briefly described above to include projects from other manifest files in your west.yml. This key can be either a project or self section attribute:

manifest:
  projects:
  - name: some-project
    import: ...
  self:
    import: ...

You can use a “self: import:” to load additional files from the repository containing your west.yml. You can use a “project: ... import:” to load additional files defined in that project’s Git history.

West resolves the final manifest from individual manifest files in this order:

1. imported files in self
2. your west.yml file
3. imported files in projects

During resolution, west ignores projects which have already been defined in other files. For example, a project named foo in your west.yml makes west ignore other projects named foo imported from your projects list.

The import key can be a boolean, path, mapping, or sequence. We’ll describe these in order, using examples:

- **Boolean**
  - Example 1.1: Downstream of a Zephyr release
  - Example 1.2: “Rolling release” Zephyr downstream
  - Example 1.3: Downstream of a Zephyr release, with module fork

- **Relative path**
  - Example 2.1: Downstream of a Zephyr release with explicit path
– Example 2.2: Downstream with directory of manifest files
– Example 2.3: Continuous Integration overrides

• Mapping with additional configuration
  – Example 3.1: Downstream with name allowlist
  – Example 3.2: Downstream with path allowlist
  – Example 3.3: Downstream with path blocklist
  – Example 3.4: Import into a subdirectory

• Sequence of paths and mappings
  – Example 4.1: Downstream with sequence of manifest files
  – Example 4.2: Import order illustration

A more formal description of how this works is last, after the examples.

Troubleshooting Note If you’re using this feature and find west’s behavior confusing, try resolving your manifest to see the final results after imports are done.

Option 1: Boolean This is the easiest way to use import.

If import is true as a projects attribute, west imports projects from the west.yml file in that project’s root directory. If it’s false or missing, it has no effect. For example, this manifest would import west.yml from the p1 git repository at revision v1.0:

manifest:
  # ...
  projects:
  - name: p1
    revision: v1.0
    import: true  # Import west.yml from p1’s v1.0 git tag
  - name: p2
    import: false  # Nothing is imported from p2.
  - name: p3
    # Nothing is imported from p3 either.

It’s an error to set import to either true or false inside self, like this:

manifest:
  # ...
  self:
  import: true  # Error

Example 1.1: Downstream of a Zephyr release You have a source code repository you want to use with Zephyr v1.14.1 LTS. You want to maintain the whole thing using west. You don’t want to modify any of the mainline repositories.

In other words, the west workspace you want looks like this:
You can do this with the following `my-repo/west.yml`:

```yaml
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v1.14.1
      import: true
```

You can then create the workspace on your computer like this, assuming `my-repo` is hosted at `https://git.example.com/my-repo`:

```bash
west init -m https://git.example.com/my-repo my-downstream
```

```bash
cd my-downstream
west update
```

After `west init`, `my-downstream/my-repo` will be cloned.

After `west update`, all of the projects defined in the zephyr repository's `west.yml` at revision v1.14.1 will be cloned into `my-downstream` as well.

You can add and commit any code to `my-repo` you please at this point, including your own Zephyr applications, drivers, etc. See Application Development.

### Example 1.2: “Rolling release” Zephyr downstream

This is similar to Example 1.1: Downstream of a Zephyr release, except we’ll use `revision: main` for the zephyr repository:

```yaml
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: main
      import: true
```

You can create the workspace in the same way:

```bash
west init -m https://git.example.com/my-repo my-downstream
```

```bash
cd my-downstream
west update
```

This time, whenever you run `west update`, the special `manifest-rev` branch in the zephyr repository will be updated to point at a newly fetched main branch tip from the URL `https://github.com/zephyrproject-rtos/zephyr`.

The contents of `zephyr/west.yml` at the new `manifest-rev` will then be used to import projects from Zephyr. This lets you stay up to date with the latest changes in the Zephyr project. The cost is that

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running `west update` will not produce reproducible results, since the remote main branch can change every time you run it.

It’s also important to understand that west ignores your working tree’s `zephyr/west.yml` entirely when resolving imports. West always uses the contents of imported manifests as they were committed to the latest manifest-rev when importing from a project.

You can only import manifest from the file system if they are in your manifest repository’s working tree. See Example 2.2: Downstream with directory of manifest files for an example.

**Example 1.3: Downstream of a Zephyr release, with module fork**  This manifest is similar to the one in Example 1.1: Downstream of a Zephyr release, except it:

- is a downstream of Zephyr 2.0
- includes a downstream fork of the `modules/hal/nordic` module which was included in that release

```yaml
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: hal_nordic
      remote: my-remote
      revision: my-sha
      path: modules/hal/nordic
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v2.0.0
      import: true

# subset of zephyr/west.yml contents at v2.0.0:
manifest:
  defaults:
    remote: zephyrproject-rtos
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    # ...
    - name: hal_nordic
      path: modules/hal/nordic
      revision: another-sha
```

With this manifest file, the project named `hal_nordic`:

- is cloned from `https://git.example.com/hal_nordic` instead of `https://github.com/zephyrproject-rtos/hal_nordic`.
- is updated to commit `my-sha` by `west update`, instead of the mainline commit `another-sha`

In other words, when your top-level manifest defines a project, like `hal_nordic`, west will ignore any other definition it finds later on while resolving imports.

This does mean you have to copy the path: `modules/hal/nordic` value into `my-repo/west.yml` when defining `hal_nordic` there. The value from `zephyr/west.yml` is ignored entirely. See Resolving Manifests for troubleshooting advice if this gets confusing in practice.

When you run `west update`, west will:
- update zephyr's manifest-rev to point at the v2.0.0 tag
- import zephyr/west.yml at that manifest-rev
- locally check out the v2.0.0 revisions for all zephyr projects except hal_nordic
- update hal_nordic to my-sha instead of another-sha

Option 2: Relative path  The import value can also be a relative path to a manifest file or a directory containing manifest files. The path is relative to the root directory of the projects or self repository the import key appears in.

Here is an example:

```json
manifest:
  projects:
    - name: project-1
      revision: v1.0
      import: west.yml
    - name: project-2
      revision: main
      import: p2-manifests
  self:
    import: submanifests
```

This will import the following:

- the contents of project-1/west.yml at manifest-rev, which points at tag v1.0 after running west update
- any YAML files in the directory tree project-2/p2-manifests at the latest commit in the main branch, as fetched by west update, sorted by file name
- YAML files in submanifests in your manifest repository, as they appear on your file system, sorted by file name

Notice how projects imports get data from Git using manifest-rev, while self imports get data from your file system. This is because as usual, west leaves version control for your manifest repository up to you.

Example 2.1: Downstream of a Zephyr release with explicit path  This is an explicit way to write an equivalent manifest to the one in Example 1.1: Downstream of a Zephyr release.

```json
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: v1.14.1
      import: west.yml
```

The setting import: west.yml means to use the file west.yml inside the zephyr project. This example is contrived, but shows the idea.

This can be useful in practice when the name of the manifest file you want to import is not west.yml.

Example 2.2: Downstream with directory of manifest files  Your Zephyr downstream has a lot of additional repositories. So many, in fact, that you want to split them up into multiple manifest files, but keep track of them all in a single manifest repository, like this:
You want to add all the files in `my-repo/submanifests` to the main manifest file, `my-repo/west.yml`, in addition to projects in `zephyr/west.yml`. You want to track the latest development code in the Zephyr repository’s main branch instead of using a fixed revision.

Here’s how:

```yaml
# my-repo/west.yml:
manifest:
  remotes:
    - name: zephyrproject-rtos
      url-base: https://github.com/zephyrproject-rtos
  projects:
    - name: zephyr
      remote: zephyrproject-rtos
      revision: main
      import: true
  self:
    import: submanifests
```

Manifest files are imported in this order during resolution:

1. `my-repo/submanifests/01-libraries.yml`
2. `my-repo/submanifests/02-vendor-hals.yml`
3. `my-repo/submanifests/03-applications.yml`
4. `my-repo/west.yml`
5. `zephyr/west.yml`

**Note:** The `.yml` file names are prefixed with numbers in this example to make sure they are imported in the specified order.

You can pick arbitrary names. West sorts files in a directory by name before importing.

Notice how the manifests in `submanifests` are imported before `my-repo/west.yml` and `zephyr/west.yml`. In general, an import in the `self` section is processed before the manifest files in `projects` and the main manifest file.

This means projects defined in `my-repo/submanifests` take highest precedence. For example, if `01-libraries.yml` defines `hal_nordic`, the project by the same name in `zephyr/west.yml` is simply ignored. As usual, see Resolving Manifests for troubleshooting advice.

This may seem strange, but it allows you to redefine projects “after the fact”, as we’ll see in the next example.

**Example 2.3: Continuous Integration overrides** Your continuous integration system needs to fetch and test multiple repositories in your west workspace from a developer’s forks instead of your mainline development trees, to see if the changes all work well together.

Starting with Example 2.2: Downstream with directory of manifest files, the CI scripts add a file `00-ci.yml` in `my-repo/submanifests`, with these contents:
# my-repo/submanifests/00-ci.yml:

```yaml
manifest:
  projects:
    - name: a-vendor-hal
      url: https://github.com/a-developer/hal
      revision: a-pull-request-branch
    - name: an-application
      url: https://github.com/a-developer/application
      revision: another-pull-request-branch
```

The CI scripts run `west update` after generating this file in `my-repo/submanifests`. The projects defined in `00-ci.yml` have higher precedence than other definitions in `my-repo/submanifests`, because the name `00-ci.yml` comes before the other file names.

Thus, `west update` always checks out the developer’s branches in the projects named `a-vendor-hal` and `an-application`, even if those same projects are also defined elsewhere.

**Option 3: Mapping**  
The import key can also contain a mapping with the following keys:

- **file**: Optional. The name of the manifest file or directory to import. This defaults to `west.yml` if not present.
- **name-allowlist**: Optional. If present, a name or sequence of project names to include.
- **path-allowlist**: Optional. If present, a path or sequence of project paths to match against. This is a shell-style globbing pattern, currently implemented with `pathlib`. Note that this means case sensitivity is platform specific.
- **name-blocklist**: Optional. Like `name-allowlist`, but contains project names to exclude rather than include.
- **path-blocklist**: Optional. Like `path-allowlist`, but contains project paths to exclude rather than include.
- **path-prefix**: Optional (new in v0.8.0). If given, this will be prepended to the project’s path in the workspace, as well as the paths of any imported projects. This can be used to place these projects in a subdirectory of the workspace.

Allowlists override blocklists if both are given. For example, if a project is blocked by path, then allowed by name, it will still be imported.

**Example 3.1: Downstream with name allowlist**  Here is a pair of manifest files, representing a mainline and a downstream. The downstream doesn’t want to use all the mainline projects, however. We’ll assume the mainline `west.yml` is hosted at `https://git.example.com/mainline/manifest`.

```yaml
# mainline west.yml:
manifest:
  projects:
    - name: mainline-app  # included
      path: examples/app
      url: https://git.example.com/mainline/app
    - name: lib
      path: libraries/lib
      url: https://git.example.com/mainline/lib
    - name: lib2  # included
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2

# downstream west.yml:
```

(continues on next page)
manifest:
  projects:
  - name: mainline
    url: https://git.example.com/mainline/manifest
    import:
      name-allowlist:
      - mainline-app
      - lib2
  - name: downstream-app
    url: https://git.example.com/downstream/app
  - name: lib3
    path: libraries/lib3
    url: https://git.example.com/downstream/lib3

An equivalent manifest in a single file would be:

manifest:
  projects:
  - name: mainline
    url: https://git.example.com/mainline/manifest
  - name: downstream-app
    url: https://git.example.com/downstream/app
  - name: lib3
    path: libraries/lib3
    url: https://git.example.com/downstream/lib3
  - name: mainline-app
    # imported
    path: examples/app
    url: https://git.example.com/mainline/app
  - name: lib2
    # imported
    path: libraries/lib2
    url: https://git.example.com/mainline/lib2

If an allowlist had not been used, the lib project from the mainline manifest would have been imported.

Example 3.2: Downstream with path allowlist Here is an example showing how to allowlist mainline's libraries only, using path-allowlist.

# mainline west.yml:
manifest:
  projects:
  - name: app
    path: examples/app
    url: https://git.example.com/mainline/app
  - name: lib
    path: libraries/lib
    # included
    url: https://git.example.com/mainline/lib
  - name: lib2
    path: libraries/lib2
    # included
    url: https://git.example.com/mainline/lib2

# downstream west.yml:
manifest:
  projects:
  - name: mainline
    url: https://git.example.com/mainline/manifest
    import:
(continues on next page)
path-allowlist: libraries/*
- name: app
  url: https://git.example.com/downstream/app
- name: lib3
  path: libraries/lib3
  url: https://git.example.com/downstream/lib3

An equivalent manifest in a single file would be:

```
manifest:
  projects:
    - name: lib  # imported
      path: libraries/lib
      url: https://git.example.com/mainline/lib
    - name: lib2  # imported
      path: libraries/lib2
      url: https://git.example.com/mainline/lib2
    - name: mainline
      url: https://git.example.com/mainline/manifest
    - name: app
      url: https://git.example.com/downstream/app
    - name: lib3
      path: libraries/lib3
      url: https://git.example.com/downstream/lib3
```

Example 3.3: Downstream with path blocklist  Here's an example showing how to block all vendor HALs from mainline by common path prefix in the workspace, add your own version for the chip you're targeting, and keep everything else.

```
# mainline west.yml:
manifest:
  defaults:
    remote: mainline
  remotes:
    - name: mainline
      url-base: https://git.example.com/mainline
  projects:
    - name: app
    - name: lib
      path: libraries/lib
    - name: lib2
      path: libraries/lib2
    - name: hal_foo
      path: modules/hals/foo  # excluded
    - name: hal_bar
      path: modules/hals/bar  # excluded
    - name: hal_baz
      path: modules/hals/baz  # excluded

# downstream west.yml:
manifest:
  projects:
    - name: mainline
      url: https://git.example.com/mainline/manifest
      import:
```

(continues on next page)
An equivalent manifest in a single file would be:

```
manifest:
  defaults:
    remote: mainline
  remotes:
    - name: mainline
      url-base: https://git.example.com/mainline
  projects:
    - name: app            # imported
    - name: lib            # imported
      path: libraries/lib
    - name: lib2           # imported
      path: libraries/lib2
    - name: mainline
      repo-path: https://git.example.com/mainline/manifest
    - name: hal_foo
      path: modules/hals/foo
      url: https://git.example.com/downstream/hal_foo
```

**Example 3.4: Import into a subdirectory**  You want to import a manifest and its projects, placing everything into a subdirectory of your west workspace.

For example, suppose you want to import this manifest from project `foo`, adding this project and its projects `bar` and `baz` to your workspace:

```
# foo/west.yml:
manifest:
  defaults:
    remote: example
  remotes:
    - name: example
      url-base: https://git.example.com
  projects:
    - name: bar
    - name: baz
```

Instead of importing these into the top level workspace, you want to place all three project repositories in an `external-code` subdirectory, like this:

```
workspace/
  └── external-code/
      └── foo/
      │    └── bar/
      │         └── baz/
```

You can do this using this manifest:

```
manifest:
  projects:
    - name: foo
```

(continues on next page)
An equivalent manifest in a single file would be:

```yaml
# foo/west.yml:
manifest:
  defaults:
    remote: example
  remotes:
    - name: example
      url-base: https://git.example.com
  projects:
    - name: foo
      path: external-code/foo
    - name: bar
      path: external-code/bar
    - name: baz
      path: external-code/baz
```

Option 4: Sequence  The import key can also contain a sequence of files, directories, and mappings.

Example 4.1: Downstream with sequence of manifest files  This example manifest is equivalent to the manifest in Example 2.2: Downstream with directory of manifest files, with a sequence of explicitly named files.

```yaml
# my-repo/west.yml:
manifest:
  projects:
    - name: zephyr
      url: https://github.com/zephyrproject-rtos/zephyr
      import: west.yml
  self:
  import:
    - submanifests/01-libraries.yml
    - submanifests/02-vendor-hals.yml
    - submanifests/03-applications.yml
```

Example 4.2: Import order illustration  This more complicated example shows the order that west imports manifest files:

```yaml
# my-repo/west.yml
manifest:
  # ...
  projects:
    - name: my-library
    - name: my-app
    - name: zephyr
      import: true
    - name: another-manifest-repo
      import: submanifests
  self:
  import:
```
For this example, west resolves imports in this order:

1. the listed files in my-repo/submanifests are first, in the order they occur (e.g. libraries.yml comes before applications.yml, since this is a sequence of files), since the self: import: is always imported first
2. my-repo/west.yml is next (with projects my-library etc. as long as they weren't already defined somewhere in submanifests)
3. zephyr/west.yml is after that, since that's the first import key in the projects list in my-repo/west.yml
4. files in another-manifest-repo/submanifests are last (sorted by file name), since that's the final project import

### Manifest Import Details

This section describes how west resolves a manifest file that uses import a bit more formally.

#### Overview

The import key can appear in a west manifest's projects and self sections. The general case looks like this:

```yaml
# Top-level manifest file.
manifest:
  projects:
    - name: foo
      import: import-1
    - name: bar
      import: import-2
    # ...
    - name: baz
      import: import-N
  self:
    import: self-import
```

Import keys are optional. If any of import-1, ..., import-N are missing, west will not import additional manifest data from that project. If self-import is missing, no additional files in the manifest repository (beyond the top-level file) are imported.

The ultimate outcomes of resolving manifest imports are:

- a projects list, which is produced by combining the projects defined in the top-level file with those defined in imported files
- a set of extension commands, which are drawn from the the west-commands keys in in the top-level file and any imported files
- a group-filter list, which is produced by combining the top-level and any imported filters

Importing is done in this order:

1. Manifests from self-import are imported first.
2. The top-level manifest file's definitions are handled next.
3. Manifests from import-1, ..., import-N, are imported in that order.
When an individual `import` key refers to multiple manifest files, they are processed in this order:

- If the value is a relative path naming a directory (or a map whose file is a directory), the manifest files it contains are processed in lexicographic order – i.e., sorted by file name.
- If the value is a sequence, its elements are recursively imported in the order they appear.

This process recurses if necessary. E.g., if `import-1` produces a manifest file that contains an `import` key, it is resolved recursively using the same rules before its contents are processed further.

**Projects** This section describes how the final `projects` list is created.

Projects are identified by name. If the same name occurs in multiple manifests, the first definition is used, and subsequent definitions are ignored. For example, if `import-1` contains a project named `bar`, that is ignored, because the top-level `west.yml` has already defined a project by that name.

The contents of files named by `import-1` through `import-N` are imported from Git at the latest manifest-rev revisions in their projects. These revisions can be updated to the values `rev-1` through `rev-N` by running `west update`. If any manifest-rev reference is missing or out of date, `west update` also fetches project data from the remote fetch URL and updates the reference.

Also note that all imported manifests, from the root manifest to the repository which defines a project P, must be up to date in order for `west to update P` itself. For example, this means `west update P` would update manifest-rev in the baz project if `bash/west.yml` defines P, as well as updating the manifest-rev branch in the local git clone of P. Confusingly, updating baz may result in the removal of P from `bash/west.yml`, which “should” cause `west update P` to fail with an unrecognized project!

For this reason, it’s not possible to run `west update P` if P is defined in an imported manifest; you must update this project along with all the others with a plain `west update`.

By default, west won’t fetch any project data over the network if a project’s revision is a SHA or tag which is already available locally, so updating the extra projects shouldn’t take too much time unless it’s really needed. See the documentation for the `update.fetch` configuration option for more information.

**Extensions** All extension commands defined using `west-commands` keys discovered while handling imports are available in the resolved manifest.

If an imported manifest file has a `west-commands`: definition in its `self:` section, the extension commands defined there are added to the set of available extensions at the time the manifest is imported. They will thus take precedence over any extension commands with the same names added later on.

**Group filters** The resolved manifest has a `group-filter` value which is the result of concatenating the `group-filter` values in the top-level manifest and any imported manifests.

Manifest files which appear earlier in the import order have higher precedence and are therefore concatenated later into the final `group-filter`.

In other words, let:

- the submanifest resolved from `self-import` have group filter `self-filter`
- the top-level manifest file have group filter `top-filter`
- the submanifests resolved from `import-1` through `import-N` have group filters `filter-1` through `filter-N` respectively

The final resolved `group-filter` value is then `filter1 + filter-2 + ... + filter-N + top-filter + self-filter`, where `+` here refers to list concatenation.

**Important:** The order that filters appear in the above list matters.
The last filter element in the final concatenated list “wins” and determines if the group is enabled or
disabled.

For example, in [-foo] + [+foo], group foo is enabled. However, in [+foo] + [-foo], group foo is
disabled.

For simplicity, west and this documentation may elide concatenated group filter elements which are
redundant using these rules. For example, [+foo] + [-foo] could be written more simply as [-foo],
for the reasons given above. As another example, [-foo] + [+foo] could be written as the empty list
[], since all groups are enabled by default.

Manifest Command

The west manifest command can be used to manipulate manifest files. It takes an action, and action-
specific arguments.

The following sections describe each action and provides a basic signature for simple uses. Run west
manifest --help for full details on all options.

Resolving Manifests  The --resolve action outputs a single manifest file equivalent to your current
manifest and all its imported manifests:

west manifest --resolve [-o outfile]

The main use for this action is to see the “final” manifest contents after performing any imports.

To print detailed information about each imported manifest file and how projects are handled during
manifest resolution, set the maximum verbosity level using -v:

west -v manifest --resolve

Freezing Manifests  The --freeze action outputs a frozen manifest:

west manifest --freeze [-o outfile]

A “frozen” manifest is a manifest file where every project’s revision is a SHA. You can use --freeze to
produce a frozen manifest that’s equivalent to your current manifest file. The -o option specifies an
output file; if not given, standard output is used.

Validating Manifests  The --validate action either succeeds if the current manifest file is valid, or
fails with an error:

west manifest --validate

The error message can help diagnose errors.

Get the manifest path  The --path action prints the path to the top level manifest file:

west manifest --path

The output is something like /path/to/workspace/west.yml. The path format depends on your oper-
ating system.
2.10.8  Configuration

This page documents west's configuration file system, the west config command, and configuration options used by built-in commands. For API documentation on the west.configuration module, see west-apis-configuration.

West Configuration Files

West's configuration file syntax is INI-like; here is an example file:

```ini
[manifest]
path = zephyr

[zephyr]
base = zephyr
```

Above, the manifest section has option path set to zephyr. Another way to say the same thing is that manifest.path is zephyr in this file.

There are three types of configuration file:

1. **System**: Settings in this file affect west's behavior for every user logged in to the computer. Its location depends on the platform:
   - Linux: `/etc/westconfig`
   - macOS: `/usr/local/etc/westconfig`
   - Windows: `%PROGRAMDATA%\west\config`

2. **Global** (per user): Settings in this file affect how west behaves when run by a particular user on the computer.
   - All platforms: the default is `.westconfig` in the user's home directory.
   - Linux note: if the environment variable `XDG_CONFIG_HOME` is set, then `$XDG_CONFIG_HOME/west/config` is used.
   - Windows note: the following environment variables are tested to find the home directory: `%HOME%`, then `%USERPROFILE%`, then a combination of `%HOMEDRIVE%` and `%HOMEPATH%`.

3. **Local**: Settings in this file affect west's behavior for the current west workspace. The file is `.west/config`, relative to the workspace's root directory.

A setting in a file which appears lower down on this list overrides an earlier setting. For example, if color.ui is true in the system's configuration file, but false in the workspace's, then the final value is false. Similarly, settings in the user configuration file override system settings, and so on.

west config

The built-in config command can be used to get and set configuration values. You can pass west config the options --system, --global, or --local to specify which configuration file to use. Only one of these can be used at a time. If none is given, then writes default to --local, and reads show the final value after applying overrides.

Some examples for common uses follow; run west config -h for detailed help, and see Built-in Configuration Options for more details on built-in options.

To set manifest.path to some-other-manifest:

```bash
west config manifest.path some-other-manifest
```
Doing the above means that commands like `west update` will look for the west manifest inside the `some-other-manifest` directory (relative to the workspace root directory) instead of the directory given to `west init`, so be careful!

To read `zephyr.base`, the value which will be used as `ZEPHYR_BASE` if it is unset in the calling environment (also relative to the workspace root):

```
west config zephyr.base
```

You can switch to another zephyr repository without changing `manifest.path` – and thus the behavior of commands like `west update` – using:

```
west config zephyr.base some-other-zephyr
```

This can be useful if you use commands like `git worktree` to create your own zephyr directories, and want commands like `west build` to use them instead of the zephyr repository specified in the manifest. (You can go back to using the directory in the upstream manifest by running `west config zephyr.base zephyr`.)

To set `color.ui` to `false` in the global (user-wide) configuration file, so that west will no longer print colored output for that user when run in any workspace:

```
west config --global color.ui false
```

To undo the above change:

```
west config --global color.ui true
```

**Built-in Configuration Options**

The following table documents configuration options supported by west’s built-in commands. Configuration options supported by Zephyr’s extension commands are documented in the pages for those commands.
<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>color.ui</td>
<td>Boolean. If true (the default), then west output is colorized when stdout is a terminal.</td>
</tr>
<tr>
<td>commands.</td>
<td>Boolean, default true, disables Extensions if false</td>
</tr>
<tr>
<td>allow_extensions</td>
<td>String, default west.yml. Relative path from the manifest repository root directory to the manifest file used by west init and other commands which parse the manifest.</td>
</tr>
<tr>
<td>manifest.file</td>
<td>String, default west.yml. Relative path from the manifest repository root directory to the manifest file used by west init and other commands which parse the manifest.</td>
</tr>
<tr>
<td>manifest.group-filter</td>
<td>String, default empty. A comma-separated list of project groups to enable and disable within the workspace. Prefix enabled groups with + and disabled groups with -. For example, the value &quot;+foo,-bar&quot; enables group foo and disables bar. See Project Groups and Active Projects.</td>
</tr>
<tr>
<td>manifest.path</td>
<td>String, relative path from the west workspace root directory to the manifest repository used by west update and other commands which parse the manifest. Set locally by west init.</td>
</tr>
<tr>
<td>update.fetch</td>
<td>String, one of &quot;smart&quot; (the default behavior starting in v0.6.1) or &quot;always&quot; (the previous behavior). If set to &quot;smart&quot;, the west update command will skip fetching from project remotes when those projects' revisions in the manifest file are SHAs or tags which are already available locally. The &quot;always&quot; behavior is to unconditionally fetch from the remote.</td>
</tr>
<tr>
<td>update.name-cache</td>
<td>String. If non-empty, west update will use its value as the --name-cache option's value if not given on the command line.</td>
</tr>
<tr>
<td>update.narrow</td>
<td>Boolean. If true, west update behaves as if --narrow was given on the command line. The default is false.</td>
</tr>
<tr>
<td>update.path-cache</td>
<td>String. If non-empty, west update will use its value as the --path-cache option's value if not given on the command line.</td>
</tr>
<tr>
<td>update.sync-submodules</td>
<td>Boolean. If true (the default), west update will synchronize Git submodules before updating them.</td>
</tr>
<tr>
<td>zephyr.base</td>
<td>String, default value to set for the ZEPHYR_BASE environment variable while the west command is running. By default, this is set to the path to the manifest project with path zephyr (if there is one) during west init. If the variable is already set, then this setting is ignored unless zephyr.base-prefer is &quot;configfile&quot;.</td>
</tr>
<tr>
<td>zephyr.base-prefer</td>
<td>String, one the values &quot;env&quot; and &quot;configfile&quot;. If set to &quot;env&quot; (the default), setting ZEPHYR_BASE in the calling environment overrides the value of the zephyr.base configuration option. If set to &quot;configfile&quot;, the configuration option wins instead.</td>
</tr>
</tbody>
</table>

### 2.10.9 Extensions

West is “pluggable”: you can add your own commands to west without editing its source code. These are called west extension commands, or just “extensions” for short. Extensions show up in the west --help output in a special section for the project which defines them. This page provides general information on west extension commands, and has a tutorial for writing your own.

Some commands you can run when using west with Zephyr, like the ones used to build, flash, and debug and the ones described here, are extensions. That's why help for them shows up like this in west --help:

```
commands from project at "zephyr":
  completion: display shell completion scripts
  boards: display information about supported boards
  build: compile a Zephyr application
  sign: sign a Zephyr binary for bootloader chain-loading
  flash: flash and run a binary on a board
  debug: flash and interactively debug a Zephyr application
```
Disabling Extension Commands

To disable support for extension commands, set the `commands.allow_extensions` configuration option to `false`. To set this globally for whenever you run `west`, use:

```
west config --global commands.allow_extensions false
```

If you want to, you can then re-enable them in a particular `west` workspace with:

```
west config --local commands.allow_extensions true
```

Note that the files containing extension commands are not imported by `west` unless the commands are explicitly run. See below for details.

Adding a West Extension

There are three steps to adding your own extension:

1. Write the code implementing the command.
2. Add information about it to a `west-commands.yml` file.
3. Make sure the `west-commands.yml` file is referenced in the `west` manifest.

Note that `west` ignores extension commands whose names are the same as a built-in command.

**Step 1: Implement Your Command**  
Create a Python file to contain your command implementation (see the “Meta > Requires” information on the `west` PyPI page for details on the currently supported versions of Python). You can put it in anywhere in any project tracked by your `west` manifest, or the manifest repository itself. This file must contain a subclass of the `west.commands.WestCommand` class; this class will be instantiated and used when your extension is run.

Here is a basic skeleton you can use to get started. It contains a subclass of `WestCommand`, with implementations for all the abstract methods. For more details on the `west` APIs you can use, see `west-apis`.

```python
'''my_west_extension.py
Basic example of a west extension.''

from textwrap import dedent  # just for nicer code indentation
from west.commands import WestCommand  # your extension must subclass this
from west import log  # use this for user output

class MyCommand(WestCommand):

    def __init__(self):
        super().__init__(
            'my-command-name',  # gets stored as self.name
            'one-line help for what my-command-name does',  # self.help
            # self.description:
```

(continues on next page)
A multi-line description of my-command.

You can split this up into multiple paragraphs and they'll get reflowed for you. You can also pass
formatter_class=argparse.RawDescriptionHelpFormatter when calling
parser_adder.add_parser() below if you want to keep your line endings.'''

```python
def do_add_parser(self, parser_adder):
    # This is a bit of boilerplate, which allows you full control over the
    # type of argparse handling you want. The "parser_adder" argument is
    # the return value of an argparse.ArgumentParser.add_subparsers() call.
    parser = parser_adder.add_parser(self.name,
                                      help=self.help,
                                      description=self.description)

    # Add some example options using the standard argparse module API.
    parser.add_argument('--optional', help='an optional argument')
    parser.add_argument('required', help='a required argument')

    return parser  # gets stored as self.parser

def do_run(self, args, unknown_args):
    # This gets called when the user runs the command, e.g.:
    # $ west my-command-name -o FOO BAR
    # --optional is FOO
    # required is BAR
    log.inf('--optional is', args.optional)
    log.inf('required is', args.required)
```

You can ignore the second argument to do_run() (unknown_args above), as WestCommand will reject unknown arguments by default. If you want to be passed a list of unknown arguments instead, add accepts_unknown_args=True to the super().__init__() arguments.

### Step 2: Add or Update Your `west-commands.yml`

You now need to add a `west-commands.yml` file to your project which describes your extension to west.

Here is an example for the above class definition, assuming it’s in `my_west_extension.py` at the project root directory:

```yaml
west-commands:
  - file: my_west_extension.py
    commands:
      - name: my-command-name
        class: MyCommand
        help: one-line help for what my-command-name does
```

The top level of this YAML file is a map with a west-commands key. The key's value is a sequence of "command descriptors". Each command descriptor gives the location of a file implementing west extensions, along with the names of those extensions, and optionally the names of the classes which define them (if not given, the class value defaults to the same thing as name).

Some information in this file is redundant with definitions in the Python code. This is because west won’t import `my_west_extension.py` until the user runs `west my-command-name`, since:

- It allows users to run `west update` with a manifest from an untrusted source, then use other west
commands without your code being imported along the way. Since importing a Python module is shell-equivalent, this provides some peace of mind.

- It’s a small optimization, since your code will only be imported if it is needed.

So, unless your command is explicitly run, west will just load the west-commands.yml file to get the basic information it needs to display information about your extension to the user in west --help output, etc.

If you have multiple extensions, or want to split your extensions across multiple files, your west-commands.yml will look something like this:

```yaml
west-commands:
  - file: my_west_extension.py
    commands:
      - name: my-command-name
        class: MyCommand
        help: one-line help for what my-command-name does
    - file: another_file.py
      commands:
        - name: command2
          help: another cool west extension
        - name: a-third-command
          class: ThirdCommand
          help: a third command in the same file as command2
```

Above:

- `my_west_extension.py` defines extension `my-command-name` with class `MyCommand`
- `another_file.py` defines two extensions:
  1. `command2` with class `command2`
  2. `a-third-command` with class `ThirdCommand`

See the file west-commands-schema.yml in the west repository for a schema describing the contents of a west-commands.yml.

**Step 3: Update Your Manifest**

Finally, you need to specify the location of the west-commands.yml you just edited in your west manifest. If your extension is in a project, add it like this:

```yaml
manifest:
  # [... other contents ...]
  projects:
    - name: your-project
      west-commands: path/to/west-commands.yml
  # [... other projects ...]
```

Where `path/to/west-commands.yml` is relative to the root of the project. Note that the name west-commands.yml, while encouraged, is just a convention; you can name the file something else if you need to.

Alternatively, if your extension is in the manifest repository, just do the same thing in the manifest’s self section, like this:

```yaml
manifest:
  # [... other contents ...]
  self:
    west-commands: path/to/west-commands.yml
```

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That’s it; you can now run `west my-command-name`. Your command’s name, help, and the project which contains its code will now also show up in the `west --help` output. If you share the updated repositories with others, they’ll be able to use it, too.

### 2.10.10 Building, Flashing and Debugging

Zephyr provides several `west extension commands` for building, flashing, and interacting with Zephyr programs running on a board: `build`, `flash`, `debug`, `debugserver` and `attach`.

For information on adding board support for the flashing and debugging commands, see Flash and debug support in the board porting guide.

**Building: `west build`**

**Tip:** Run `west build -h` for a quick overview.

The `build` command helps you build Zephyr applications from source. You can use `west config` to configure its behavior.

Its default behavior tries to “do what you mean”:

- If there is a Zephyr build directory named `build` in your current working directory, it is incrementally re-compiled. The same is true if you run `west build` from a Zephyr build directory.
- Otherwise, if you run `west build` from a Zephyr application's source directory and no build directory is found, a new one is created and the application is compiled in it.

**Basics**  The easiest way to use `west build` is to go to an application’s root directory (i.e. the folder containing the application's `CMakeLists.txt`) and then run:

```
west build -b <BOARD>
```

Where `<BOARD>` is the name of the board you want to build for. This is exactly the same name you would supply to CMake if you were to invoke it with: `cmake -DBOARD=<BOARD>`.

**Tip:** You can use the `west boards` command to list all supported boards.

A build directory named `build` will be created, and the application will be compiled there after `west build` runs CMake to create a build system in that directory. If `west build` finds an existing build directory, the application is incrementally re-compiled there without re-running CMake. You can force CMake to run again with `--cmake`.

You don’t need to use the `--board` option if you’ve already got an existing build directory; `west build` can figure out the board from the CMake cache. For new builds, the `--board` option, `BOARD` environment variable, or `build.board` configuration option are checked (in that order).

**Sysbuild (multi-domain builds)**  `Sysbuild (System build)` can be used to create a multi-domain build system combining multiple images for a single or multiple boards.

Use `--sysbuild` to select the `Sysbuild (System build)` build infrastructure with `west build` to build multiple domains.

More detailed information regarding the use of sysbuild can be found in the `Sysbuild (System build)` guide.
Tip: The build.sysbuild configuration option can be enabled to tell west build to default build using sysbuild. --no-sysbuild can be used to disable sysbuild for a specific build.

west build will build all domains through the top-level build folder of the domains specified by sysbuild. A single domain from a multi-domain project can be built by using --domain argument.

Examples Here are some west build usage examples, grouped by area.

Forcing CMake to Run Again To force a CMake re-run, use the --cmake (or -c) option:

```bash
west build -c
```

Setting a Default Board To configure west build to build for the reel_board by default:

```bash
west config build.board reel_board
```

(You can use any other board supported by Zephyr here; it doesn’t have to be reel_board.)

Setting Source and Build Directories To set the application source directory explicitly, give its path as a positional argument:

```bash
west build -b <BOARD> path/to/source/directory
```

To set the build directory explicitly, use --build-dir (or -d):

```bash
west build -b <BOARD> --build-dir path/to/build/directory
```

To change the default build directory from build, use the build.dir-fmt configuration option. This lets you name build directories using format strings, like this:

```bash
west config build.dir-fmt "build/{board}/{app}"
```

With the above, running west build -b reel_board samples/hello_world will use build directory build/reel_board/hello_world. See Configuration Options for more details on this option.

Setting the Build System Target To specify the build system target to run, use --target (or -t).

For example, on host platforms with QEMU, you can use the run target to build and run the hello_world sample for the emulated qemu_x86 board in one command:

```bash
west build -b qemu_x86 -t run samples/hello_world
```

As another example, to use -t to list all build system targets:

```bash
west build -t help
```

As a final example, to use -t to run the pristine target, which deletes all the files in the build directory:

```bash
west build -t pristine
```
**Pristine Builds**  A *pristine* build directory is essentially a new build directory. All byproducts from previous builds have been removed.

To force `west build` make the build directory pristine before re-running CMake to generate a build system, use the `--pristine=always` (or `-p=always`) option.

Giving `--pristine` or `-p` without a value has the same effect as giving it the value `always`. For example, these commands are equivalent:

```
west build -p reel_board samples/hello_world
west build -p=always -b reel_board samples/hello_world
```

By default, `west build` applies a heuristic to detect if the build directory needs to be made pristine. This is the same as using `--pristine=auto`.

**Tip:** You can run `west config build.pristine always` to always do a pristine build, or `west config build.pristine never` to disable the heuristic. See the `west build` Configuration Options for details.

**Verbose Builds**  To print the CMake and compiler commands run by `west build`, use the global `west` verbosity option, `-v`:

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

**One-Time CMake Arguments**  To pass additional arguments to the CMake invocation performed by `west build`, pass them after a `--` at the end of the command line.

**Important:** Passing additional CMake arguments like this forces `west build` to re-run CMake, even if a build system has already been generated.

After using `--` once to generate the build directory, use `west build -d <build-dir>` on subsequent runs to do incremental builds.

For example, to use the Unix Makefiles CMake generator instead of Ninja (which `west build` uses by default), run:

```
w west build -b reel_board -- -G'Unix Makefiles'
```

To use Unix Makefiles and set `CMAKE_VERBOSE_MAKEFILE` to ON:

```
w west build -b reel_board -- -G'Unix Makefiles' -DCMAKE_VERBOSE_MAKEFILE=ON
```

Notice how the `--` only appears once, even though multiple CMake arguments are given. All command-line arguments to `west build` after a `--` are passed to CMake.

To set `DTC_OVERLAY_FILE` to enable-modem.overlay, using that file as a devicetree overlay:

```
w west build -b reel_board -- -DDTC_OVERLAY_FILE=enable-modem.overlay
```

To merge the `file.conf` Kconfig fragment into your build's `.config`:

```
w west build -- -DOVERLAY_CONFIG=file.conf
```

**Permanent CMake Arguments**  The previous section describes how to add CMake arguments for a single `west build` command. If you want to save CMake arguments for `west build` to use every time it generates a new build system instead, you should use the `build.cmake-args` configuration option.
Whenever `west build` runs CMake to generate a build system, it splits this option's value according to shell rules and includes the results in the `cmake` command line.

Remember that, by default, `west build` tries to avoid generating a new build system if one is present in your build directory. Therefore, you need to either delete any existing build directories or do a pristine build after setting `build.cmake-args` to make sure it will take effect.

For example, to always enable `CMAKE_EXPORT_COMPILE_COMMANDS`, you can run:

```bash
west config build.cmake-args -- -DCMAKE_EXPORT_COMPILE_COMMANDS=ON
```

(The extra `--` is used to force the rest of the command to be treated as a positional argument. Without it, `west config` would treat the `-DVAR=VAL` syntax as a use of its `-D` option.)

To enable `CMAKE_VERBOSE_MAKEFILE`, so CMake always produces a verbose build system:

```bash
west config build.cmake-args -- -DCMAKE_VERBOSE_MAKEFILE=ON
```

To save more than one argument in `build.cmake-args`, use a single string whose value can be split into distinct arguments (`west build` uses the Python function `shlex.split()` internally to split the value).

For example, to enable both `CMAKE_EXPORT_COMPILE_COMMANDS` and `CMAKE_VERBOSE_MAKEFILE`:

```bash
west config build.cmake-args -- "-DCMAKE_EXPORT_COMPILE_COMMANDS=ON -DCMAKE_VERBOSE_MAKEFILE=ON"
```

If you want to save your CMake arguments in a separate file instead, you can combine CMake's `-C <initial-cache>` option with `build.cmake-args`. For instance, another way to set the options used in the previous example is to create a file named `~/my-cache.cmake` with the following contents:

```bash
set(CMAKE_EXPORT_COMPILE_COMMANDS ON CACHE BOOL "")
set(CMAKE_VERBOSE_MAKEFILE ON CACHE BOOL "")
```

Then run:

```bash
west config build.cmake-args "-C ~/my-cache.cmake"
```

See the `cmake(1)` manual page and the `set()` command documentation for more details.

**Build tool arguments** Use `-o` to pass options to the underlying build tool.

This works with both `ninja` (the default) and `make` based build systems.

For example, to pass `-dexplain` to `ninja`:

```bash
west build -o=-dexplain
```

As another example, to pass `--keep-going` to `make`:

```bash
west build -o=--keep-going
```

Note that using `-o=--foo` instead of `-o --foo` is required to prevent `--foo` from being treated as a `west build` option.

**Build parallelism** By default, `ninja` uses all of your cores to build, while `make` uses only one. You can control this explicitly with the `-j` option supported by both tools.

For example, to build with 4 cores:

```bash
west build -o=-j4
```

The `-o` option is described further in the previous section.
Build a single domain  In a multi-domain build with hello_world and MCUboot, you can use --domain hello_world to only build this domain:

```sh
west build --sysbuild --domain hello_world
```

The --domain argument can be combined with the --target argument to build the specific target for the target, for example:

```sh
west build --sysbuild --domain hello_world --target help
```

Configuration Options  You can configure west build using these options.

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>build.board</td>
<td>String. If given, this the board used by west build when --board is not given and BOARD is unset in the environment.</td>
</tr>
<tr>
<td>build.board_warn</td>
<td>Boolean, default true. If false, disables warnings when west build can't figure out the target board.</td>
</tr>
<tr>
<td>build.cmake-args</td>
<td>String. If present, the value will be split according to shell rules and passed to CMake whenever a new build system is generated. See Permanent CMake Arguments.</td>
</tr>
</tbody>
</table>
| build.dir-fmt   | String, default build. The build folder format string, used by west whenever it needs to create or locate a build folder. The currently available arguments are:  
  - `board`: The board name  
  - `source_dir`: The relative path from the current working directory to the source directory. If the current working directory is inside the source directory this will be set to an empty string.  
  - `app`: The name of the source directory. |
| build.generator | String, default Ninja. The CMake Generator to use to create a build system. (To set a generator for a single build, see the above example) |
| build.guess-dir | String, instructs west whether to try to guess what build folder to use when build.dir-fmt is in use and not enough information is available to resolve the build folder name. Can take these values:  
  - `never` (default): Never try to guess, bail out instead and require the user to provide a build folder with -d.  
  - `runners`: Try to guess the folder when using any of the ‘runner’ commands. These are typically all commands that invoke an external tool, such as flash and debug. |
| build.pristine  | String. Controls the way in which west build may clean the build folder before building. Can take the following values:  
  - `never` (default): Never automatically make the build folder pristine.  
  - `auto`: west build will automatically make the build folder pristine before building, if a build system is present and the build would fail otherwise (e.g. the user has specified a different board or application from the one previously used to make the build directory).  
  - `always`: Always make the build folder pristine before building, if a build system is present. |
| build.sysbuild  | Boolean, default false. If true, build application using the sysbuild infrastructure. |
Flashing: `west flash`

**Tip:** Run `west flash -h` for additional help.

**Basics**  From a Zephyr build directory, re-build the binary and flash it to your board:

```bash
west flash
```

Without options, the behavior is the same as `ninja flash` (or `make flash`, etc.).

To specify the build directory, use `--build-dir` (or `-d`):

```bash
west flash --build-dir path/to/build/directory
```

If you don't specify the build directory, `west flash` searches for one in `build`, then the current working directory. If you set the `build.dir-fmt` configuration option (see Setting Source and Build Directories), `west flash` searches there instead of `build`.

**Choosing a Runner**  If your board's Zephyr integration supports flashing with multiple programs, you can specify which one to use using the `--runner` (or `--r`) option. For example, if West flashes your board with `nrfjprog` by default, but it also supports JLink, you can override the default with:

```bash
west flash --runner jlink
```

You can override the default flash runner at build time by using the `BOARD_FLASH_RUNNER` CMake variable, and the debug runner with `BOARD_DEBUG_RUNNER`.

For example:

```sh
# Set the default runner to "jlink", overriding the board's usual default.
west build [...] -- -DBOARD_FLASH_RUNNER=jlink
```

See One-Time CMake Arguments and Permanent CMake Arguments for more information on setting CMake arguments.

See Flash and debug runners below for more information on the runner library used by West. The list of runners which support flashing can be obtained with `west flash -H`; if run from a build directory or with `--build-dir`, this will print additional information on available runners for your board.

**Configuration Overrides**  The CMake cache contains default values West uses while flashing, such as where the board directory is on the file system, the path to the zephyr binaries to flash in several formats, and more. You can override any of this configuration at runtime with additional options.

For example, to override the HEX file containing the Zephyr image to flash (assuming your runner expects a HEX file), but keep other flash configuration at default values:

```bash
west flash --hex-file path/to/some/other.hex
```

The `west flash -h` output includes a complete list of overrides supported by all runners.

**Runner-Specific Overrides**  Each runner may support additional options related to flashing. For example, some runners support an `--erase` flag, which mass-erases the flash storage on your board before flashing the Zephyr image.

To view all of the available options for the runners your board supports, as well as their usage information, use `--context` (or `-H`):
west flash --context

**Important:** Note the capital H in the short option name. This re-runs the build in order to ensure the information displayed is up to date!

When running West outside of a build directory, `west flash -H` just prints a list of runners. You can use `west flash -H -r <runner-name>` to print usage information for options supported by that runner.

For example, to print usage information about the jlink runner:

```
west flash -H -r jlink
```

**Multi-domain flashing**  When a `Sysbuild (multi-domain builds)` folder is detected, then `west flash` will flash all domains in the order defined by sysbuild.

It is possible to flash the image from a single domain in a multi-domain project by using `--domain`.

For example, in a multi-domain build with hello_world and MCUboot, you can use the `--domain` hello_world domain to only flash only the image from this domain:

```
west flash --domain hello_world
```

**Debugging:** `west debug, west debugserver`

**Tip:** Run `west debug -h` or `west debugserver -h` for additional help.

**Basics**  From a Zephyr build directory, to attach a debugger to your board and open up a debug console (e.g. a GDB session):

```
west debug
```

To attach a debugger to your board and open up a local network port you can connect a debugger to (e.g. an IDE debugger):

```
west debugserver
```

Without options, the behavior is the same as `ninja debug` and `ninja debugserver` (or `make debug`, etc.).

To specify the build directory, use `--build-dir` (or `-d`):

```
west debug --build-dir path/to/build/directory
west debugserver --build-dir path/to/build/directory
```

If you don't specify the build directory, these commands search for one in `build`, then the current working directory. If you set the `build.dir-fmt` configuration option (see Setting Source and Build Directories), `west debug` searches there instead of `build`.

**Choosing a Runner**  If your board's Zephyr integration supports debugging with multiple programs, you can specify which one to use using the `--runner` (or `-r`) option. For example, if West debugs your board with `pyocd-gdbserver` by default, but it also supports JLink, you can override the default with:
west debug --runner jlink
west debugserver --runner jlink

See Flash and debug runners below for more information on the runner library used by West. The list of runners which support debugging can be obtained with west debug -H; if run from a build directory or with --build-dir, this will print additional information on available runners for your board.

Configuration Overrides  The CMake cache contains default values West uses for debugging, such as where the board directory is on the file system, the path to the zephyr binaries containing symbol tables, and more. You can override any of this configuration at runtime with additional options.

For example, to override the ELF file containing the Zephyr binary and symbol tables (assuming your runner expects an ELF file), but keep other debug configuration at default values:

west debug --elf-file path/to/some/other.elf
west debugserver --elf-file path/to/some/other.elf

The west debug -h output includes a complete list of overrides supported by all runners.

Runner-Specific Overrides  Each runner may support additional options related to debugging. For example, some runners support flags which allow you to set the network ports used by debug servers.

To view all of the available options for the runners your board supports, as well as their usage information, use --context (or -H):

west debug --context

(The command west debugserver --context will print the same output.)

Important:  Note the capital H in the short option name. This re-runs the build in order to ensure the information displayed is up to date!

When running West outside of a build directory, west debug -H just prints a list of runners. You can use west debug -H -r <runner-name> to print usage information for options supported by that runner.

For example, to print usage information about the jlink runner:

west debug -H -r jlink

Multi-domain debugging  west debug can only debug a single domain at a time. When a Sysbuild (multi-domain builds) folder is detected, west debug will debug the default domain specified by sysbuild.

The default domain will be the application given as the source directory. See the following example:

west build --sysbuild path/to/source/directory

For example, when building hello_world with MCUboot using sysbuild, hello_world becomes the default domain:

west build --sysbuild samples/hello_world

So to debug hello_world you can do:

west debug

or:
If you wish to debug MCUboot, you must explicitly specify MCUboot as the domain to debug:

west debug --domain mcuboot

Flash and debug runners

The flash and debug commands use Python wrappers around various Flash & Debug Host Tools. These wrappers are all defined in a Python library at scripts/west_commands/runners. Each wrapper is called a runner. Runners can flash and/or debug Zephyr programs.

The central abstraction within this library is ZephyrBinaryRunner, an abstract class which represents runners. The set of available runners is determined by the imported subclasses of ZephyrBinaryRunner. ZephyrBinaryRunner is available in the runners.core module; individual runner implementations are in other submodules, such as runners.nrfjprog, runners.openocd, etc.

Hacking

This section documents the runners.core module used by the flash and debug commands. This is the core abstraction used to implement support for these features.

Warning: These APIs are provided for reference, but they are more “shared code” used to implement multiple extension commands than a stable API.

Developers can add support for new ways to flash and debug Zephyr programs by implementing additional runners. To get this support into upstream Zephyr, the runner should be added into a new or existing runners module, and imported from runners/__init__.py.

Note: The test cases in scripts/west_commands/tests add unit test coverage for the runners package and individual runner classes.

Please try to add tests when adding new runners. Note that if your changes break existing test cases, CI testing on upstream pull requests will fail.

Zephyr binary runner core interfaces

This provides the core ZephyrBinaryRunner class meant for public use, as well as some other helpers for concrete runner classes.

```python
class runners.core.BuildConfiguration(build_dir: str)
    # This helper class provides access to build-time configuration.
    # Configuration options can be read as if the object were a dict, either object['CONFIG_FOO'] or object.get('CONFIG_FOO').
    # Kconfig configuration values are available (parsed from .config).
    def getboolean(option)
        # If a boolean option is explicitly set to y or n, returns its value. Otherwise, falls back to False.
```

2.10. West (Zephyr's meta-tool)
exception runners.core.MissingProgram(program)

    FileNotFoundError subclass for missing program dependencies.

    No significant changes from the parent FileNotFoundError; this is useful for explicitly signaling that
    the file in question is a program that some class requires to proceed.

    The filename attribute contains the missing program.

class runners.core.NetworkPortHelper

    Helper class for dealing with local IP network ports.

get_unused_ports(starting_from)

    Find unused network ports, starting at given values.

    starting_from is an iterable of ports the caller would like to use.

    The return value is an iterable of ports, in the same order, using the given values if they were
    unused, or the next sequentially available unused port otherwise.

    Ports may be bound between this call's check and actual usage, so callers still need to handle
    errors involving returned ports.

class runners.core.RunnerCaps(commands: Set[str] = {'attach', 'debug', 'debugserver', 'flash'},

dev_id: bool = False,
flash_addr: bool = False,
erase: bool = False,
tool_opt: bool = False)

    This class represents a runner class's capabilities.

    Each capability is represented as an attribute with the same name. Flag attributes are True or False.

    Available capabilities:

    • commands: set of supported commands; default is {'flash', 'debug', 'debugserver', 'attach'}.

    • dev_id: whether the runner supports device identifiers, in the form of an -i, –dev-id option.
      This is useful when the user has multiple debuggers connected to a single computer, in order
      to select which one will be used with the command provided.

    • flash_addr: whether the runner supports flashing to an arbitrary address. Default is False. If
      true, the runner must honor the –dt-flash option.

    • erase: whether the runner supports an –erase option, which does a mass-erase of the entire
      addressable flash on the target before flashing. On multi-core SoCs, this may only erase
      portions of flash specific the actual target core. (This option can be useful for things like
      clearing out old settings values or other subsystem state that may affect the behavior of the
      zephyr image. It is also sometimes needed by SoCs which have flash-like areas that can't be
      sector erased by the underlying tool before flashing; UICR on nRF SoCs is one example.)

    • tool_opt: whether the runner supports a –tool-opt (-O) option, which can be given multiple
      times and is passed on to the underlying tool that the runner wraps.

class runners.core.RunnerConfig(build_dir: str,

board_dir: str,
elf_file: Optional[str],
hex_file: Optional[str],
bin_file: Optional[str],
gdb: Optional[str] = None,
openocd: Optional[str] = None,
openocd_search: List[str] = [])

    Runner execution-time configuration.

    This is a common object shared by all runners. Individual runners can register specific configuration
    options using their do_add_parser() hooks.

    bin_file: Optional[str]
        Alias for field number 4

    board_dir: str
        Alias for field number 1

    build_dir: str
        Alias for field number 0
elf_file: Optional[str]
   Alias for field number 2

gdb: Optional[str]
   Alias for field number 5

hex_file: Optional[str]
   Alias for field number 3

openocd: Optional[str]
   Alias for field number 6

openocd_search: List[str]
   Alias for field number 7

class runners.core.ZephyrBinaryRunner(cfg: RunnerConfig)
   Abstract superclass for binary runners (flashers, debuggers).

   Note: this class's API has changed relatively rarely since it as added, but it is not considered a
   stable Zephyr API, and may change without notice.

   With some exceptions, boards supported by Zephyr must provide generic means to be flashed (have
   a Zephyr firmware binary permanently installed on the device for running) and debugged (have a
   breakpoint debugger and program loader on a host workstation attached to a running target).

   This is supported by four top-level commands managed by the Zephyr build system:

   • ‘flash’: flash a previously configured binary to the board, start execution on the target, then
     return.

   • ‘debug’: connect to the board via a debugging protocol, program the flash, then drop the user
     into a debugger interface with symbol tables loaded from the current binary, and block until it
     exits.

   • ‘debugserver’: connect via a board-specific debugging protocol, then reset and halt the target.
     Ensure the user is now able to connect to a debug server with symbol tables loaded from the
     binary.

   • ‘attach’: connect to the board via a debugging protocol, then drop the user into a debugger
     interface with symbol tables loaded from the current binary, and block until it exits. Unlike
     ‘debug’, this command does not program the flash.

   This class provides an API for these commands. Every subclass is called a ‘runner’ for short. Each
   runner has a name (like ‘pyocd’), and declares commands it can handle (like ‘flash’). Boards (like
   ‘nrf52dk_nrf52832’) declare which runner(s) are compatible with them to the Zephyr build system,
   along with information on how to configure the runner to work with the board.

   The build system will then place enough information in the build directory to create and use
   runners with this class's create() method, which provides a command line argument parsing API.
   You can also create runners by instantiating subclasses directly.

   In order to define your own runner, you need to:

   1. Define a ZephyrBinaryRunner subclass, and implement its abstract methods. You may need to
      override capabilities().

   2. Make sure the Python module defining your runner class is imported, e.g. by editing this
      package's __init__.py (otherwise, get_runners() won't work).

   3. Give your runner's name to the Zephyr build system in your board's board.cmake.

   Additional advice:

   • If you need to import any non-standard-library modules, make sure to catch ImportError and
     defer complaints about it to a RuntimeError if one is missing. This avoids affecting users that
     don't require your runner, while still making it clear what went wrong to users that do require
     it that don't have the necessary modules installed.
• If you need to ask the user something (e.g. using input()), do it in your create() classmethod, not do_run(). That ensures your __init__() really has everything it needs to call do_run(), and also avoids calling input() when not instantiating within a command line application.

• Use self.logger to log messages using the standard library's logging API; your logger is named “runner.<your-runner-name()>”

For command-line invocation from the Zephyr build system, runners define their own argparse-based interface through the common add_parser() (and runner-specific do_add_parser() it delegates to), and provide a way to create instances of themselves from a RunnerConfig and parsed runner-specific arguments via create().

Runners use a variety of host tools and configuration values, the user interface to which is abstracted by this class. Each runner subclass should take any values it needs to execute one of these commands in its constructor. The actual command execution is handled in the run() method.

classmethod add_parser(parser)
    Adds a sub-command parser for this runner.

    The given object, parser, is a sub-command parser from the argparse module. For more details, refer to the documentation for argparse.ArgumentParser.add_subparsers().

    The lone common optional argument is:
    • –dt-flash (if the runner capabilities includes flash_addr)

    Runner-specific options are added through the do_add_parser() hook.

property build_conf: BuildConfiguration
    Get a BuildConfiguration for the build directory.

call(cmd: List[str], **kwargs) \rightarrow int
    Subclass subprocess.call() wrapper.

    Subclasses should use this method to run command in a subprocess and get its return code, rather than using subprocess directly, to keep accurate debug logs.

classmethod capabilities() \rightarrow RunnerCaps
    Returns a RunnerCaps representing this runner's capabilities.

    This implementation returns the default capabilities.

    Subclasses should override appropriately if needed.

cfg
    RunnerConfig for this instance.

check_call(cmd: List[str], **kwargs)
    Subclass subprocess.check_call() wrapper.

    Subclasses should use this method to run command in a subprocess and check that it executed correctly, rather than using subprocess directly, to keep accurate debug logs.

check_output(cmd: List[str], **kwargs) \rightarrow bytes
    Subclass subprocess.check_output() wrapper.

    Subclasses should use this method to run command in a subprocess and check that it executed correctly, rather than using subprocess directly, to keep accurate debug logs.

classmethod create(cfg: RunnerConfig, args: Namespace) \rightarrow ZephyrBinaryRunner
    Create an instance from command-line arguments.

    • cfg: runner configuration (pass to superclass __init__)
    • args: arguments parsed from execution environment, as specified by add_parser().
classmethod dev_id_help() → str
    Get the ArgParse help text for the --dev-id option.

abstract classmethod do_add_parser(parser)
    Hook for adding runner-specific options.

abstract classmethod do_create(cfg: RunnerConfig, args: Namespace) → ZephyrBinaryRunner
    Hook for instance creation from command line arguments.

abstract do_run(command: str, **kwargs)
    Concrete runner; run() delegates to this. Implement in subclasses.
    In case of an unsupported command, raise a ValueError.

ensure_output(output_type: str) → None
    Ensure self.cfg has a particular output artifact.
    For example, ensure_output('bin') ensures that self.cfg.bin_file refers to an existing file. Errors out if it's missing or undefined.

    Parameters
        output_type -- string naming the output type

static flash_address_from_build_conf(build_conf: BuildConfiguration)
    If CONFIG_HAS_FLASH_LOAD_OFFSET is n in build_conf, return the CONFIG_FLASH_BASE_ADDRESS value. Otherwise, return CONFIG_FLASH_BASE_ADDRESS + CONFIG_FLASH_LOAD_OFFSET.

static get_flash_address(args: Namespace, build_conf: BuildConfiguration, default: int = 0) → int
    Helper method for extracting a flash address.
    If args.dt_flash is true, returns the address obtained from ZephyrBinaryRunner.flash_address_from_build_conf(build_conf).
    Otherwise (when args.dt_flash is False), the default value is returned.

static get_runners() → List[Type[ZephyrBinaryRunner]]
    Get a list of all currently defined runner classes.

logger
    logging.Logger for this instance.

abstract classmethod name() → str
    Return this runner's user-visible name.
    When choosing a name, pick something short and lowercase, based on the name of the tool (like opencld, jlink, etc.) or the target architecture/board (like xtensa etc.).

popen_ignore_int(cmd: List[str], **kwargs) → Popen
    Spawn a child command, ensuring it ignores SIGINT.
    The returned subprocess.Popen object must be manually terminated.

static require(program: str) → str
    Require that a program is installed before proceeding.

    Parameters
        program -- name of the program that is required, or path to a program binary.

    If program is an absolute path to an existing program binary, this call succeeds. Otherwise, try to find the program by name on the system PATH.
    If the program can be found, its path is returned. Otherwise, raises MissingProgram.
run(command: str, **kwargs)
    Runs command (‘flash’, ‘debug’, ‘debugserver’, ‘attach’).
    This is the main entry point to this runner.

run_client(client)
    Run a client that handles SIGINT.

run_server_and_client(server, client)
    Run a server that ignores SIGINT, and a client that handles it.
    This routine portably:
    • creates a Popen object for the server command which ignores SIGINT
    • runs client in a subprocess while temporarily ignoring SIGINT
    • cleans up the server after the client exits.
    It’s useful to e.g. open a GDB server and client.

property thread_info_enabled: bool
    Returns True if self.build_conf has CONFIG_DEBUG_THREAD_INFO enabled.

classmethod tool_opt_help() → str
    Get the ArgParse help text for the –tool-opt option.

Doing it By Hand

If you prefer not to use West to flash or debug your board, simply inspect the build directory for the
binaries output by the build system. These will be named something like zephyr/zephyr.elf, zephyr/
zephyr.hex, etc., depending on your board’s build system integration. These binaries may be flashed
to a board using alternative tools of your choice, or used for debugging as needed, e.g. as a source of
symbol tables.

By default, these West commands rebuild binaries before flashing and debugging. This can of course
also be accomplished using the usual targets provided by Zephyr’s build system (in fact, that’s how these
commands do it).

2.10.11 Signing Binaries

The west sign extension command can be used to sign a Zephyr application binary for consumption by
a bootloader using an external tool. Run west sign -h for command line help.

MCUboot / imgtool

The Zephyr build system has special support for signing binaries for use with the MCUboot bootloader
using the imgtool program provided by its developers. You can both build and sign this type of application
binary in one step by setting some Kconfig options. If you do, west flash will use the signed binaries.
If you use this feature, you don’t need to run west sign yourself; the build system will do it for you.

Here is an example workflow, which builds and flashes MCUboot, as well as the hello_world application
for chain-loading by MCUboot. Run these commands from the zephyrproject workspace you created
in the Getting Started Guide.

west build -b YOUR_BOARD bootloader/mcuboot/boot/zephyr -d build-mcuboot
west build -b YOUR_BOARD zephyr/samples/hello_world -d build-hello-signed -- \
    -DCONFIG_BOOTLOADER_MCUBOOT=y \ 
    -DCONFIG_MCUBOOT_SIGNATURE_KEY_FILE="bootloader/mcuboot/root-rsa-2048.pem"

(continues on next page)
west flash -d build-mcuboot
west flash -d build-hello-signed

Notes on the above commands:

- YOUR_BOARD should be changed to match your board
- The CONFIG_MCUBOOT_SIGNATURE_KEY_FILE value is the insecure default provided and used by by MCUboot for development and testing
- You can change the hello_world application directory to any other application that can be loaded by MCUboot, such as the smp_svr_sample

For more information on these and other related configuration options, see:

- CONFIG_BOOTLOADER_MCUBOOT: build the application for loading by MCUboot
- CONFIG_MCUBOOT_SIGNATURE_KEY_FILE: the key file to use with west sign. If you have your own key, change this appropriately
- CONFIG_MCUBOOT_EXTRA_IMGTOOL_ARGS: optional additional command line arguments for imgtool
- CONFIG_MCUBOOT_GENERATE_CONFIRMED_IMAGE: also generate a confirmed image, which may be more useful for flashing in production environments than the OTA-able default image
- On Windows, if you get “Access denied” issues, the recommended fix is to run pip3 install imgtool, then retry with a pristine build directory.

If your west flash runner uses an image format supported by imgtool, you should see something like this on your device's serial console when you run west flash -d build-mcuboot:

*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
[00:00:00.469] <inf> mcuboot: Starting bootloader
[00:00:00.116] <inf> mcuboot: Primary image: magic=unset, swap_type=0x1, copy_
→ done=0x3, image_ok=0x3
[00:00:00.213] <inf> mcuboot: Boot source: none
[00:00:00.374] <err> mcuboot: Failed reading image headers; Image=0
[00:00:00.437] <err> mcuboot: Unable to find bootable image

Then, you should see something like this when you run west flash -d build-hello-signed:

*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
[00:00:00.469] <inf> mcuboot: Starting bootloader
[00:00:00.116] <inf> mcuboot: Primary image: magic=unset, swap_type=0x1, copy_
→ done=0x3, image_ok=0x3
[00:00:00.213] <inf> mcuboot: Boot source: none
[00:00:00.374] <err> mcuboot: Swap type: none
[00:00:00.437] <err> mcuboot: Bootloader chainload address offset: 0xc000
[00:00:00.500] <err> mcuboot: Jumping to the first image slot
*** Booting Zephyr OS build zephyr-v2.3.0-2310-gcebac69c8ae1 ***
Hello World! nrf52840dk_nrf52840

Whether west flash supports this feature depends on your runner. The nrfjprog and pyocd runners work with the above flow. If your runner does not support this flow and you would like it to, please send a patch or file an issue for adding support.

### 2.10.12 Additional Zephyr extension commands

This page documents miscellaneous Zephyr Extensions.
Listing boards: west boards

The `boards` command can be used to list the boards that are supported by Zephyr without having to resort to additional sources of information.

It can be run by typing:

```
w west boards
```

This command lists all supported boards in a default format. If you prefer to specify the display format yourself you can use the `--format` (or `-f`) flag:

```
w west boards -f "\{arch\}:\{name\}"
```

Additional help about the formatting options can be found by running:

```
w west boards -h
```

Shell completion scripts: west completion

The `completion` extension command outputs shell completion scripts that can then be used directly to enable shell completion for the supported shells.

It currently supports the following shells:

- bash
- zsh

Additional instructions are available in the command’s help:

```
w west help completion
```

Installing CMake packages: west zephyr-export

This command registers the current Zephyr installation as a CMake config package in the CMake user package registry.

In Windows, the CMake user package registry is found in `HKEY_CURRENT_USER\Software\Kitware\CMake\Packages`.

In Linux and MacOS, the CMake user package registry is found in `~/.cmake/packages`.

You may run this command when setting up a Zephyr workspace. If you do, application CMakeLists.txt files that are outside of your workspace will be able to find the Zephyr repository with the following:

```
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
```

See `share/zephyr-package/cmake` for details.

Software bill of materials: west spdx

This command generates SPDX 2.2 tag-value documents, creating relationships from source files to the corresponding generated build files. SPDX-License-Identifier comments in source files are scanned and filled into the SPDX documents.

To use this command:

1. Pre-populate a build directory `BUILD_DIR` like this:
west spdx --init -d BUILD_DIR

This step ensures the build directory contains CMake metadata required for SPDX document generation.

2. Build your application using this pre-created build directory, like so:
   west build -d BUILD_DIR [...]

3. Generate SPDX documents using this build directory:
   west spdx -d BUILD_DIR

This generates the following SPDX bill-of-materials (BOM) documents in BUILD_DIR/spdx/:

- app.spdx: BOM for the application source files used for the build
- zephyr.spdx: BOM for the specific Zephyr source code files used for the build
- build.spdx: BOM for the built output files

Each file in the bill-of-materials is scanned, so that its hashes (SHA256 and SHA1) can be recorded, along with any detected licenses if an `SPDX-License-Identifier` comment appears in the file.

SPDX Relationships are created to indicate dependencies between CMake build targets, build targets that are linked together, and source files that are compiled to generate the built library files.

west spdx accepts these additional options:

- `-n PREFIX`: a prefix for the Document Namespaces that will be included in the generated SPDX documents. See SPDX specification clause 6 for details. If `-n` is omitted, a default namespace will be generated according to the default format described in section 2.5 using a random UUID.
- `-s SPDX_DIR`: specifies an alternate directory where the SPDX documents should be written instead of BUILD_DIR/spdx/.
- `--analyze-includes`: in addition to recording the compiled source code files (e.g. `.c`, `.S`) in the bills-of-materials, also attempt to determine the specific header files that are included for each `.c` file.

   This takes longer, as it performs a dry run using the C compiler for each `.c` file using the same arguments that were passed to it for the actual build.

- `--include-sdk`: with `--analyze-includes`, also create a fourth SPDX document, sdk.spdx, which lists header files included from the SDK.

Working with binary blobs: west blobs

The `blobs` command allows users to interact with binary blobs declared in one or more modules via their module.yml file.

The `blobs` command has three sub-commands, used to list, fetch or clean (i.e. delete) the binary blobs themselves.

You can list binary blobs while specifying the format of the output:

west blobs list -f '{module}: {type} {path}'

For the full set of variables available in `-f/--format` run west blobs -h.

Fetching blobs works in a similar manner:

west blobs fetch
Note that, as described in the modules section, fetched blobs are stored in a `zephyr/blobs/` folder relative to the root of the corresponding module repository.

As does deleting them:

```
west blobs clean
```

Additionally the tool allows you to specify the modules you want to list, fetch or clean blobs for by typing the module names as a command-line parameter.

### 2.10.13 History and Motivation

West was added to the Zephyr project to fulfill two fundamental requirements:

- The ability to work with multiple Git repositories
- The ability to provide an extensible and user-friendly command-line interface for basic Zephyr workflows

During the development of west, a set of Design Constraints were identified to avoid the common pitfalls of tools of this kind.

#### Requirements

Although the motivation behind splitting the Zephyr codebase into multiple repositories is outside of the scope of this page, the fundamental requirements, along with a clear justification of the choice not to use existing tools and instead develop a new one, do belong here.

The basic requirements are:

- **R1**: Keep externally maintained code in separately maintained repositories outside of the main zephyr repository, without requiring users to manually clone each of the external repositories
- **R2**: Provide a tool that both Zephyr users and distributors can make use of to benefit from and extend
- **R3**: Allow users and downstream distributions to override or remove repositories without having to make changes to the zephyr repository
- **R4**: Support both continuous tracking and commit-based (bisectable) project updating

#### Rationale for a custom tool

Some of west’s features are similar to those provided by Git Submodules and Google’s repo.

Existing tools were considered during west’s initial design and development. None were found suitable for Zephyr’s requirements. In particular, these were examined in detail:

- Google repo
  - Does not cleanly support using zephyr as the manifest repository (R4)
  - Python 2 only
  - Does not play well with Windows
  - Assumes Gerrit is used for code review
- Git submodules
  - Does not fully support R1, since the externally maintained repositories would still need to be inside the main zephyr Git tree
  - Does not support R3, since downstream copies would need to either delete or replace submodule definitions
– Does not support continuous tracking of the latest HEAD in external repositories (R4)
– Requires hardcoding of the paths/locations of the external repositories

**Multiple Git Repositories**

Zephyr intends to provide all required building blocks needed to deploy complex IoT applications. This in turn means that the Zephyr project is much more than an RTOS kernel, and is instead a collection of components that work together. In this context, there are a few reasons to work with multiple Git repositories in a standardized manner within the project:

• Clean separation of Zephyr original code and imported projects and libraries
• Avoidance of license incompatibilities between original and imported code
• Reduction in size and scope of the core Zephyr codebase, with additional repositories containing optional components instead of being imported directly into the tree
• Safety and security certifications
• Enforcement of modularization of the components
• Out-of-tree development based on subsets of the supported boards and SoCs

See Basics for information on how west workspaces manage multiple git repositories.

**Design Constraints**

West is:

• **Optional**: it is always possible to drop back to “raw” command-line tools, i.e. use Zephyr without using west (although west itself might need to be installed and accessible to the build system). It may not always be convenient to do so, however. (If all of west’s features were already conveniently available, there would be no reason to develop it.)

• **Compatible with CMake**: building, flashing and debugging, and emulator support will always remain compatible with direct use of CMake.

• **Cross-platform**: West is written in Python 3, and works on all platforms supported by Zephyr.

• **Usable as a Library**: whenever possible, west features are implemented as libraries that can be used standalone in other programs, along with separate command line interfaces that wrap them. West itself is a Python package named west; its libraries are implemented as subpackages.

• **Conservative about features**: no features will be accepted without strong and compelling motivation.

• **Clearly specified**: West’s behavior in cases where it wraps other commands is clearly specified and documented. This enables interoperability with third party tools, and means Zephyr developers can always find out what is happening “under the hood” when using west.

See Zephyr issue #6205 and for more details and discussion.

### 2.10.14 Moving to West

To convert a “pre-west” Zephyr setup on your computer to west, follow these steps. If you are starting from scratch, use the Getting Started Guide instead. See Troubleshooting West for advice on common issues.

1. Install west.
   
   On Linux:
pip3 install --user -U west

On Windows and macOS:

pip3 install -U west

For details, see *Installing west*.

2. Move your zephyr repository to a new zephyrproject parent directory, and change directory there.

On Linux and macOS:

```bash
mkdir zephyrproject
mv zephyr zephyrproject
cd zephyrproject
```

On Windows cmd.exe:

```bash
mkdir zephyrproject
move zephyr zephyrproject
chdir zephyrproject
```

The name `zephyrproject` is recommended, but you can choose any name with no spaces anywhere in the path.

3. Create a west workspace using the zephyr repository as a local manifest repository:

```
west init -l zephyr
```

This creates `zephyrproject/.west`, marking the root of your workspace, and does some other setup. It will not change the contents of the zephyr repository in any way.

4. Clone the rest of the repositories used by zephyr:

```
w west update
```

Make sure to run this command whenever you pull zephyr. Otherwise, your local repositories will get out of sync. (Run west list for current information on these repositories.)

You are done: zephyrproject is now set up to use west.

### 2.10.15 Using Zephyr without west

This page provides information on using Zephyr without west. This is not recommended for beginners due to the extra effort involved. In particular, you will have to do work “by hand” to replace these features:

- cloning the additional source code repositories used by Zephyr in addition to the main zephyr repository, and keeping them up to date
- specifying the locations of these repositories to the Zephyr build system
- flashing and debugging without understanding detailed usage of the relevant host tools

**Note:** If you have previously installed west and want to stop using it, uninstall it first:

```
ip3 uninstall west
```

Otherwise, Zephyr’s build system will find it and may try to use it.
Getting the Source

In addition to downloading the zephyr source code repository itself, you will need to manually clone the additional projects listed in the west manifest file inside that repository.

```
mkdir zephyrproject
cd zephyrproject
git clone https://github.com/zephyrproject-rtos/zephyr
# clone additional repositories listed in zephyr/west.yml,
# and check out the specified revisions as well.
```

As you pull changes in the zephyr repository, you will also need to maintain those additional repositories, adding new ones as necessary and keeping existing ones up to date at the latest revisions.

Building applications

You can build a Zephyr application using CMake and Ninja (or make) directly without west installed if you specify any modules manually.

```
cmake -Bbuild -GNinja -DZEPHYR_MODULES=module1;module2;... samples/hello_world
ninja -Cbuild
```

When building with west installed, the Zephyr build system will use it to set `ZEPHYR_MODULES`.

If you don't have west installed and your application does not need any of these repositories, the build will still work.

If you don't have west installed and your application does need one of these repositories, you must set `ZEPHYR_MODULES` yourself as shown above.

See [Modules (External projects)](https://zephyr-project.org/docs/users/build-system/modules) for more details.

Similarly, if your application requires binary blobs and you are not using west, you will need to download and place those blobs in the right places instead of using `west` blobs. See [Binary Blobs](https://zephyr-project.org/docs/users/build-system/binary-blobs) for more details.

Flashing and Debugging

Running build system targets like `ninja flash`, `ninja debug`, etc. is just a call to the corresponding west command. For example, `ninja flash` calls west `flash`. If you don't have west installed on your system, running those targets will fail. You can of course still flash and debug using any Flash & Debug Host Tools which work for your board (and which those west commands wrap).

If you want to use these build system targets but do not want to install west on your system using `pip`, it is possible to do so by manually creating a west workspace:

```
# cd into zephyrproject if not already there
git clone https://github.com/zephyrproject-rtos/west .west/west
```

Then create a file `.west/config` with the following contents:

```
[manifest]
path = zephyr

[zephyr]
base = zephyr
```

---

1 Note that west `build` invokes ninja, among other tools. There's no recursive invocation of either west or ninja involved by default, however, as west `build` does not invoke `ninja flash`, `debug`, etc. The one exception is if you specifically run one of these build system targets with a command line like `west build -t flash`. In that case, west is run twice: once for `west build`, and in a subprocess, again for `west flash`. Even in this case, `ninja` is only run once, as `ninja flash`. This is because these build system targets depend on an up to date build of the Zephyr application, so it's compiled before `west flash` is run.
After that, and in order for `ninja` to be able to invoke `west` to flash and debug, you must specify the west directory. This can be done by setting the environment variable `WEST_DIR` to point to `zephyrproject/`. Run `west/west` before running CMake to set up a build directory.

For details on west's Python APIs, see `west-apis`.

## 2.11 Testing

### 2.11.1 Test Framework

The Zephyr Test Framework (Ztest) provides a simple testing framework intended to be used during development. It provides basic assertion macros and a generic test structure.

The framework can be used in two ways, either as a generic framework for integration testing, or for unit testing specific modules.

To enable the latest APIs of Ztest simply set `CONFIG_ZTEST_NEW_API=y`. The legacy APIs will soon be deprecated and eventually removed.

### Creating a test suite

Using Ztest to create a test suite is as easy as calling the `ZTEST_SUITE`. The macro accepts the following arguments:

- **suite_name** - The name of the suite. This name must be unique within a single binary.
- **ztest_suite_predicate_t** - An optional predicate function to allow choosing when the test will run. The predicate will get a pointer to the global state passed in through `ztest_run_all()` and should return a boolean to decide if the suite should run.
- **ztest_suite_setup_t** - An optional setup function which returns a test fixture. This will be called and run once per test suite run.
- **ztest_suite_before_t** - An optional before function which will run before every single test in this suite.
- **ztest_suite_after_t** - An optional after function which will run after every single test in this suite.
- **ztest_suite_teardown_t** - An optional teardown function which will run at the end of all the tests in the suite.

Below is an example of a test suite using a predicate:

```c
#include <zephyr/ztest.h>
#include "test_state.h"

static bool predicate(const void *global_state)
{
  return ((const struct test_state*)global_state)->x == 5;
}

ZTEST_SUITE(alternating_suite, predicate, NULL, NULL, NULL, NULL);
```

### Adding tests to a suite

There are 4 macros used to add a test to a suite, they are:

- **`ZTEST` (suite_name, test_name)** - Which can be used to add a test by `test_name` to a given suite by `suite_name`. 
• **ZTEST_USER** (suite_name, test_name) - Which behaves the same as **ZTEST**, only that when **CONFIG_USERSPACE** is enabled, then the test will be run in a userspace thread.

• **ZTEST_F** (suite_name, test_name) - Which behaves the same as **ZTEST**, only that the test function will already include a variable named fixture with the type <suite_name>_fixture.

• **ZTEST_USER_F** (suite_name, test_name) - Which combines the fixture feature of **ZTEST_F** with the userspace threading for the test.

**Test fixtures** Test fixtures can be used to help simplify repeated test setup operations. In many cases, tests in the same suite will require some initial setup followed by some form of reset between each test. This is achieved via fixtures in the following way:

```c
#include <zephyr/ztest.h>

struct my_suite_fixture {
    size_t max_size;
    size_t size;
    uint8_t buff[1];
};

static void *my_suite_setup(void)
{
    /* Allocate the fixture with 256 byte buffer */
    struct my_suite_fixture *fixture = k_malloc(sizeof(struct my_suite_fixture) + 255);
    zassert_not_null(fixture, NULL);
    fixture->max_size = 256;
    return fixture;
}

static void my_suite_before(void *f)
{
    struct my_suite_fixture *fixture = (struct my_suite_fixture *)f;
    memset(fixture->buff, 0, fixture->max_size);
    fixture->size = 0;
}

static void my_suite_teardown(void *f)
{
    k_free(f);
}

ZTEST_SUITE(my_suite, NULL, my_suite_setup, my_suite_before, NULL, my_suite_teardown);

ZTEST_F(my_suite, test_feature_x)
{
    zassert_equal(0, fixture->size);
    zassert_equal(256, fixture->max_size);
}
```

**Advanced features**

**Test result expectations** Some tests were made to be broken. In cases where the test is expected to fail or skip due to the nature of the code, it’s possible to annotate the test as such. For example:
#include <zephyr/ztest.h>

ZTEST_SUITE(my_suite, NULL, NULL, NULL, NULL, NULL);

ZTEST_EXPECT_FAIL(my_suite, test_fail)
ZTEST(my_suite, test_fail)
{
    /** This will fail the test */
    zassert_true(false, NULL);
}

ZTEST_EXPECT_SKIP(my_suite, test_fail)
ZTEST(my_suite, test_skip)
{
    /** This will skip the test */
    zassert_true(false, NULL);
}

In this example, the above tests should be marked as failed and skipped respectively. Instead, Ztest will mark both as passed due to the expectation.

Test rules Test rules are a way to run the same logic for every test and every suite. There are a lot of cases where you might want to reset some state for every test in the binary (regardless of which suite is currently running). As an example, this could be to reset mocks, reset emulators, flush the UART, etc.

#include <zephyr/fff.h>
#include <zephyr/ztest.h>
#include "test_mocks.h"

DEFINE_FFF_GLOBALS;

DEFINE_FAKE_VOID_FUN(my_weak_func);

static void fff_reset_rule_before(const struct ztest_unit_test *test, void __attribute__((unused)) *fixture)
{
    ARG_UNUSED(test);
    ARG_UNUSED(fixture);

    RESET_FAKE(my_weak_func);
}

ZTEST_RULE(fff_reset_rule, fff_reset_rule_before, NULL);

A custom test_main While the Ztest framework provides a default test_main() function, it's possible that some applications will want to provide custom behavior. This is particularly true if there's some global state that the tests depend on and that state either cannot be replicated or is difficult to replicate without starting the process over. For example, one such state could be a power sequence. Assuming there's a board with several steps in the power-on sequence a test suite can be written using the predicate to control when it would run. In that case, the test_main() function can be written as following:

#include <zephyr/ztest.h>

(continues on next page)
```c
#include "my_test.h"

void test_main(void)
{
    struct power_sequence_state state;

    /* Only suites that use a predicate checking for phase == PWR_PHASE_0 will run. */
    state.phase = PWR_PHASE_0;
    ztest_run_all(&state);

    /* Only suites that use a predicate checking for phase == PWR_PHASE_1 will run. */
    state.phase = PWR_PHASE_1;
    ztest_run_all(&state);

    /* Only suites that use a predicate checking for phase == PWR_PHASE_2 will run. */
    state.phase = PWR_PHASE_2;
    ztest_run_all(&state);

    /* Check that all the suites in this binary ran at least once. */
    ztest_verify_all_test_suites_ran();
}
```

**Quick start - Integration testing**

A simple working base is located at `samples/subsys/testsuite/integration`. Just copy the files to `tests/` and edit them for your needs. The test will then be automatically built and run by the twister script. If you are testing the `bar` component of `foo`, you should copy the sample folder to `tests/foo/bar`. It can then be tested with:

```
./scripts/twister -s tests/foo/bar/test-identifier
```

In the example above `tests/foo/bar` signifies the path to the test and the `test-identifier` references a test defined in the `testcase.yaml` file.

To run all tests defined in a test project, run:

```
./scripts/twister -T tests/foo/bar/
```

The sample contains the following files:

CMakeLists.txt

```makefile
# SPDX-License-Identifier: Apache-2.0

cmake_minimum_required(VERSION 3.20.0)
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
project(integration)

FILE(GLOB app_sources src/*.c)
target_sources(app PRIVATE ${app_sources})
```

testcase.yaml

```yaml
tests:
    # section.subsection
    sample.testing.ztest:
        build_only: true
```

(continues on next page)
Listing Tests

Skipping Tests

A test case project may consist of multiple sub-tests or smaller tests that either can be testing functionality or APIs. Functions implementing a test should follow the guidelines below:

- Test cases function names should be prefix with `test_`
- Test cases should be documented using doxygen
- Test function names should be unique within the section or component being tested

An example can be seen below:

```c
/**
 * @brief Test Asserts
 *
 * This test verifies the zassert_true macro.
 */
ZTEST(framework_tests, test_assert)
{
   zassert_true(1, "1 was false");
   zassert_false(0, "0 was true");
   zassert_is_null(NULL, "NULL was not NULL");
   zassert_not_null("foo", "\"foo\" was NULL");
   zassert_equal(1, 1, "1 was not equal to 1");
   zassert_equal_ptr(NULL, NULL, "NULL was not equal to NULL");
}```
Zephyr Project Documentation, Release 3.2.99

(continued from previous page)

*/
ZTEST(my_suite, test_assert)
{
    zassert_true(1, "1 was false");
}

Listing Tests  Tests (test projects) in the Zephyr tree consist of many test cases that run as part of a project and test similar functionality, for example an API or a feature. The twister script can parse the test cases in all test projects or a subset of them, and can generate reports on a granular level, i.e. if cases have passed or failed or if they were blocked or skipped.

Twister parses the source files looking for test case names, so you can list all kernel test cases, for example, by entering:

twister --list-tests -T tests/kernel

Skipping Tests  Special- or architecture-specific tests cannot run on all platforms and architectures, however we still want to count those and report them as being skipped. Because the test inventory and the list of tests is extracted from the code, adding conditionals inside the test suite is sub-optimal. Tests that need to be skipped for a certain platform or feature need to explicitly report a skip using ztest_test_skip() or Z_TEST_SKIP_IFDEF. If the test runs, it needs to report either a pass or fail. For example:

```c
#ifdef CONFIG_TEST1
ZTEST(common, test_test1)
{
    zassert_true(1, "true");
}
#else
ZTEST(common, test_test1)
{
    ztest_test_skip();
}
#endif
ZTEST(common, test_test2)
{
    Z_TEST_SKIP_IFDEF(CONFIG_BUGxxxxx);
    zassert_equal(1, 0, NULL);
}

ZTEST_SUITE(common, NULL, NULL, NULL, NULL, NULL);
```

Quick start - Unit testing

Ztest can be used for unit testing. This means that rather than including the entire Zephyr OS for testing a single function, you can focus the testing efforts into the specific module in question. This will speed up testing since only the module will have to be compiled in, and the tested functions will be called directly.

Since you won’t be including basic kernel data structures that most code depends on, you have to provide function stubs in the test. Ztest provides some helpers for mocking functions, as demonstrated below.
In a unit test, mock objects can simulate the behavior of complex real objects and are used to decide whether a test failed or passed by verifying whether an interaction with an object occurred, and if required, to assert the order of that interaction.

**Best practices for declaring the test suite** `twister` and other validation tools need to obtain the list of subcases that a Zephyr `test` test image will expose.

### Rationale

This all is for the purpose of traceability. It’s not enough to have only a semaphore test project. We also need to show that we have testpoints for all APIs and functionality, and we trace back to documentation of the API, and functional requirements.

The idea is that test reports show results for every sub-testcase as passed, failed, blocked, or skipped. Reporting on only the high-level test project level, particularly when tests do too many things, is too vague.

**Other questions:**

- Why not pre-scan with CPP and then parse? or post scan the ELF file?
  
  If C pre-processing or building fails because of any issue, then we won’t be able to tell the subcases.

- Why not declare them in the YAML testcase description?
  
  A separate testcase description file would be harder to maintain than just keeping the information in the test source files themselves – only one file to update when changes are made eliminates duplication.

### Stress test framework

Zephyr stress test framework (Ztress) provides an environment for executing user functions in multiple priority contexts. It can be used to validate that code is resilient to preemptions. The framework tracks the number of executions and preemptions for each context. Execution can have various completion conditions like timeout, number of executions or number of preemptions.

The framework is setting up the environment by creating the requested number of threads (each on different priority), optionally starting a timer. For each context, a user function (different for each context) is called and then the context sleeps for a randomized amount of system ticks. The framework is tracking CPU load and adjusts sleeping periods to achieve higher CPU load. In order to increase the probability of preemptions, the system clock frequency should be relatively high. The default 100 Hz on QEMU x86 is much too low and it is recommended to increase it to 100 kHz.

The stress test environment is setup and executed using `ZTRESS_EXECUTE` which accepts a variable number of arguments. Each argument is a context that is specified by `ZTRESS_TIMER` or `ZTRESS_THREAD` macros. Contexts are specified in priority descending order. Each context specifies completion conditions by providing the minimum number of executions and preemptions. When all conditions are met and the execution has completed, an execution report is printed and the macro returns. Note that while the test is executing, a progress report is periodically printed.

Execution can be prematurely completed by specifying a test timeout (`ztress_set_timeout()`) or an explicit abort (`ztress_abort()`).

User function parameters contains an execution counter and a flag indicating if it is the last execution.

The example below presents how to setup and run 3 contexts (one of which is `k_timer` interrupt handler context). Completion criteria is set to at least 10000 executions of each context and 1000 preemptions of the lowest priority context. Additionally, the timeout is configured to complete after 10 seconds if those conditions are not met. The last argument of each context is the initial sleep time which will be adjusted throughout the test to achieve the highest CPU load.
Zephyr Project Documentation, Release 3.2.99

ztress_set_timeout(K_MSEC(10000));
ZTRESS_EXECUTE(ZTRESS_TIMER(foo_0, user_data_0, 10000, Z_TIMEOUT_TICKS(20)),
  ZTRESS_THREAD(foo_1, user_data_1, 10000, 0, Z_TIMEOUT_
  →TICKS(20)),
  ZTRESS_THREAD(foo_2, user_data_2, 10000, 1000, Z_TIMEOUT_
  →TICKS(20)));

Configuration  Static configuration of Ztress contains:
  • ZTRESS_MAX_THREADS - number of supported threads.
  • ZTRESS_STACK_SIZE - Stack size of created threads.
  • ZTRESS_REPORT_PROGRESS_MS - Test progress report interval.

API reference

Running tests

group ztest_test
  This module eases the testing process by providing helpful macros and other testing structures.

Defines

ZTEST(suite, fn)
  Create and register a new unit test.
  Calling this macro will create a new unit test and attach it to the declared suite. The suite
does not need to be defined in the same compilation unit.

  Parameters
  • suite – The name of the test suite to attach this test
  • fn – The test function to call.

ZTEST_USER(suite, fn)
  Define a test function that should run as a user thread.
  This macro behaves exactly the same as ZTEST, but calls the test function in user space if
CONFIG_USERSPACE was enabled.

  Parameters
  • suite – The name of the test suite to attach this test
  • fn – The test function to call.

ZTEST_F(suite, fn)
  Define a test function.
  This macro behaves exactly the same as ZTEST(), but the function takes an argument for the
fixture of type struct suite##_fixture* named this.

  Parameters
  • suite – The name of the test suite to attach this test
  • fn – The test function to call.
ZTEST_USER_F(suite, fn)
Define a test function that should run as a user thread.
If CONFIG_USERSPACE is not enabled, this is functionally identical to ZTEST_F(). The test
function takes a single fixture argument of type struct suite##_fixture* named this.

Parameters
• suite – The name of the test suite to attach this test
• fn – The test function to call.

ZTEST_RULE(name, before_each_fn, after_each_fn)
Define a test rule that will run before/after each unit test.
Functions defined here will run before/after each unit test for every test suite. Along with the
callback, the test functions are provided a pointer to the test being run, and the data. This
provides a mechanism for tests to perform custom operations depending on the specific test
or the data (for example logging may use the test's name).
Ordering:
• Test rule's before function will run before the suite's before function. This is done to
  allow the test suite's customization to take precedence over the rule which is applied to
  all suites.
• Test rule's after function is not guaranteed to run in any particular order.

Parameters
• name – The name for the test rule (must be unique within the compilation unit)
• before_each_fn – The callback function (ztest_rule_cb) to call before each test
  (may be NULL)
• after_each_fn – The callback function (ztest_rule_cb) to call after each test
  (may be NULL)

ztest_run_test_suite(suite)
Run the specified test suite.

Parameters
• suite – Test suite to run.

Typedefs

typedef void (*ztest_rule_cb)(const struct ztest_unit_test *test, void *data)
Test rule callback function signature.
The function signature that can be used to register a test rule's before/after callback. This
provides access to the test and the fixture data (if provided).

Param test
  Pointer to the unit test in context

Param data
  Pointer to the test's fixture data (may be NULL)

Functions
void ztest_test_fail(void)
    Fail the currently running test.
    This is the function called from failed assertions and the like. You probably don't need to call
    it yourself.

void ztest_test_pass(void)
    Pass the currently running test.
    Normally a test passes just by returning without an assertion failure. However, if
    the success case for your test involves a fatal fault, you can call this function from
    k_sys_fatal_error_handler to indicate that the test passed before aborting the thread.

void ztest_test_skip(void)
    Skip the current test.

void ztest_skip_failed_assumption(void)

void ztest_simple_1cpu_before(void *data)
    A 'before' function to use in test suites that just need to start 1cpu.
    Ignores data, and calls z_test_1cpu_start()

    Parameters
    • data – The test suite's data

void ztest_simple_1cpu_after(void *data)
    A 'after' function to use in test suites that just need to stop 1cpu.
    Ignores data, and calls z_test_1cpu_stop()

    Parameters
    • data – The test suite's data

struct ztest_test_rule

struct ztest_arch_api
    #include <ztest_test_new.h> Structure for architecture specific APIs.

**Assertions** These macros will instantly fail the test if the related assertion fails. When an assertion
fails, it will print the current file, line and function, alongside a reason for the failure and an optional
message. If the config option: `CONFIG_ZTEST_ASSERT_VERBOSE` is 0, the assertions will only print the
file and line numbers, reducing the binary size of the test.

Example output for a failed macro from `zassert_equal(buf->ref, 2, "Invalid refcount")`:

Assertion failed at main.c:62: test_get_single_buffer: Invalid refcount (buf->ref not
    equal to 2)
Aborted at unit test function

**group ztest_assert**

This module provides assertions when using Ztest.

**Defines**

`zassert(cond, default_msg, ...)`

`zassume(cond, default_msg, ...)`

2.11. Testing
zassert_unreachable(...)  
Assert that this function call won’t be reached.

Parameters
  • ... – Optional message and variables to print if the assertion fails

zassert_true(cond, ...)
Assert that \texttt{cond} is true.

Parameters
  • \texttt{cond} – Condition to check
  • ... – Optional message and variables to print if the assertion fails

zassert_false(cond, ...)
Assert that \texttt{cond} is false.

Parameters
  • \texttt{cond} – Condition to check
  • ... – Optional message and variables to print if the assertion fails

zassert_ok(cond, ...)
Assert that \texttt{cond} is 0 (success)

Parameters
  • \texttt{cond} – Condition to check
  • ... – Optional message and variables to print if the assertion fails

zassert_is_null(ptr, ...)
Assert that \texttt{ptr} is NULL.

Parameters
  • \texttt{ptr} – Pointer to compare
  • ... – Optional message and variables to print if the assertion fails

zassert_not_null(ptr, ...)
Assert that \texttt{ptr} is not NULL.

Parameters
  • \texttt{ptr} – Pointer to compare
  • ... – Optional message and variables to print if the assertion fails

zassert_equal(a, b, ...)
Assert that \texttt{a} equals \texttt{b}.

\texttt{a} and \texttt{b} won’t be converted and will be compared directly.

Parameters
  • \texttt{a} – Value to compare
  • \texttt{b} – Value to compare
  • ... – Optional message and variables to print if the assertion fails

zassert_not_equal(a, b, ...)
Assert that \texttt{a} does not equal \texttt{b}.

\texttt{a} and \texttt{b} won’t be converted and will be compared directly.

Parameters
• a – Value to compare
• b – Value to compare
• ... – Optional message and variables to print if the assertion fails

\texttt{zassert\_equal\_ptr(a, b, ...)}

Assert that \( a \) equals \( b \).

\( a \) and \( b \) will be converted to \texttt{void *} before comparing.

\textbf{Parameters}

• a – Value to compare
• b – Value to compare
• ... – Optional message and variables to print if the assertion fails

\texttt{zassert\_within(a, b, d, ...)}

Assert that \( a \) is within \( b \) with delta \( d \).

\textbf{Parameters}

• a – Value to compare
• b – Value to compare
• d – Delta
• ... – Optional message and variables to print if the assertion fails

\texttt{zassert\_between\_inclusive(a, l, u, ...)}

Assert that \( a \) is greater than or equal to \( l \) and less than or equal to \( u \).

\textbf{Parameters}

• a – Value to compare
• l – Lower limit
• u – Upper limit
• ... – Optional message and variables to print if the assertion fails

\texttt{zassert\_mem\_equal(...)}

Assert that 2 memory buffers have the same contents.

This macro calls the final memory comparison assertion macro. Using double expansion allows providing some arguments by macros that would expand to more than one values (ANSI-C99 defines that all the macro arguments have to be expanded before macro call).

\textbf{Parameters}

• ... – Arguments, see \texttt{zassert\_mem\_equal\_} for real arguments accepted.

\texttt{zassert\_mem\_equal\_}(buf, exp, size, ...)

Internal assert that 2 memory buffers have the same contents.

\textbf{Note:} This is internal macro, to be used as a second expansion. See \texttt{zassert\_mem\_equal}. 

\textbf{Parameters}

• buf – Buffer to compare
• exp – Buffer with expected contents
• size – Size of buffers
• ... – Optional message and variables to print if the assertion fails
**Assumptions**  These macros will instantly skip the test or suite if the related assumption fails. When an assumption fails, it will print the current file, line, and function, alongside a reason for the failure and an optional message. If the config option: \texttt{CONFIG_ZTEST_ASSUME_VERBOSE} is 0, the assumptions will only print the file and line numbers, reducing the binary size of the test.

Example output for a failed macro from \texttt{zassume_equal(buf->ref, 2, "Invalid refcount")}:

```
group ztest_assume
  This module provides assumptions when using Ztest.

Defines

\texttt{zassume_true(cond, ...)}
  Assume that \texttt{cond} is true.
  If the assumption fails, the test will be marked as “skipped”.

  \textbf{Parameters}
  \begin{itemize}
    \item \texttt{cond} – Condition to check
    \item \ldots – Optional message and variables to print if the assumption fails
  \end{itemize}

\texttt{zassume_false(cond, ...)}
  Assume that \texttt{cond} is false.
  If the assumption fails, the test will be marked as “skipped”.

  \textbf{Parameters}
  \begin{itemize}
    \item \texttt{cond} – Condition to check
    \item \ldots – Optional message and variables to print if the assumption fails
  \end{itemize}

\texttt{zassume_ok(cond, ...)}
  Assume that \texttt{cond} is 0 (success)
  If the assumption fails, the test will be marked as “skipped”.

  \textbf{Parameters}
  \begin{itemize}
    \item \texttt{cond} – Condition to check
    \item \ldots – Optional message and variables to print if the assumption fails
  \end{itemize}

\texttt{zassume_is_null(ptr, ...)}
  Assume that \texttt{ptr} is NULL.
  If the assumption fails, the test will be marked as “skipped”.

  \textbf{Parameters}
  \begin{itemize}
    \item \texttt{ptr} – Pointer to compare
    \item \ldots – Optional message and variables to print if the assumption fails
  \end{itemize}

\texttt{zassume_not_null(ptr, ...)}
  Assume that \texttt{ptr} is not NULL.
  If the assumption fails, the test will be marked as “skipped”.

  \textbf{Parameters}
  \begin{itemize}
    \item \texttt{ptr} – Pointer to compare
    \item \ldots – Optional message and variables to print if the assumption fails
  \end{itemize}
```
**zassume_equal(a, b, ...)**  
Assume that \( a \) equals \( b \).  
\( a \) and \( b \) won’t be converted and will be compared directly. If the assumption fails, the test will be marked as “skipped”.  

**Parameters**  
- \( a \) – Value to compare  
- \( b \) – Value to compare  
- \( ... \) – Optional message and variables to print if the assumption fails

**zassume_not_equal(a, b, ...)**  
Assume that \( a \) does not equal \( b \).  
\( a \) and \( b \) won’t be converted and will be compared directly. If the assumption fails, the test will be marked as “skipped”.  

**Parameters**  
- \( a \) – Value to compare  
- \( b \) – Value to compare  
- \( ... \) – Optional message and variables to print if the assumption fails

**zassume_equal_ptr(a, b, ...)**  
Assume that \( a \) equals \( b \).  
\( a \) and \( b \) will be converted to \texttt{void *} before comparing. If the assumption fails, the test will be marked as “skipped”.  

**Parameters**  
- \( a \) – Value to compare  
- \( b \) – Value to compare  
- \( ... \) – Optional message and variables to print if the assumption fails

**zassume_within(a, b, d, ...)**  
Assume that \( a \) is within \( b \) with delta \( d \).  
If the assumption fails, the test will be marked as “skipped”.  

**Parameters**  
- \( a \) – Value to compare  
- \( b \) – Value to compare  
- \( d \) – Delta  
- \( ... \) – Optional message and variables to print if the assumption fails

**zassume_between_inclusive(a, l, u, ...)**  
Assume that \( a \) is greater than or equal to \( l \) and less than or equal to \( u \).  
If the assumption fails, the test will be marked as “skipped”.  

**Parameters**  
- \( a \) – Value to compare  
- \( l \) – Lower limit  
- \( u \) – Upper limit  
- \( ... \) – Optional message and variables to print if the assumption fails
zassume_mem_equal(...)  
Assume that 2 memory buffers have the same contents.

This macro calls the final memory comparison assumption macro. Using double expansion allows providing some arguments by macros that would expand to more than one values (ANSI-C99 defines that all the macro arguments have to be expanded before macro call).

Parameters

• ... – Arguments, see \texttt{zassume\_mem\_equal\_\_} for real arguments accepted.

\texttt{zassume\_mem\_equal\_\_}(buf, exp, size, ...)

Internal assume that 2 memory buffers have the same contents.

If the assumption fails, the test will be marked as “skipped”.

Note: This is internal macro, to be used as a second expansion. See \texttt{zassume\_mem\_equal}.

Parameters

• buf – Buffer to compare
• exp – Buffer with expected contents
• size – Size of buffers
• ... – Optional message and variables to print if the assumption fails

Mocking via FFF  
Zephyr has integrated with FFF for mocking. See \texttt{FFF} for documentation. To use it, use the following in your source:

\texttt{#include <zephyr/fff.h>}

Zephyr provides several FFF-based fake drivers which can be used as either stubs or mocks. Fake driver instances are configured via \textit{Devicetree} and \textit{Configuration System (Kconfig)}. See the following devicetree bindings for more information:

• \texttt{zephyr,\_fake\_can}
• \texttt{zephyr,\_fake\_eeprom}

Customizing Test Output

The way output is presented when running tests can be customized. An example can be found in \texttt{tests/ztest/custom\_output}.

Customization is enabled by setting \texttt{CONFIG\_ZTEST\_TC\_UTIL\_USER\_OVERRIDE} to “y” and adding a file \texttt{tc\_util\_user\_override.h} with your overrides.

Add the line \texttt{zephyr\_include\_directories(my\_folder)} to your project's \texttt{CMakeLists.txt} to let Zephyr find your header file during builds.

See the file \texttt{subsys\_testsuite\_include\_tc\_util.h} to see which macros and/or defines can be overridden. These will be surrounded by blocks such as:

\texttt{#ifndef SOMETHING
#define SOMETHING <default implementation>
#endif /* SOMETHING */}
Shuffling Test Sequence

By default the tests are sorted and run in alphanumerical order. Test cases may be dependent on this sequence. Enable `ZTEST_SHUFFLE` to randomize the order. The output from the test will display the seed for failed tests. For native posix builds you can provide the seed as an argument to twister with `--seed`.

Static configuration of `ZTEST_SHUFFLE` contains:

- `ZTEST_SHUFFLE_SUITE_REPEAT_COUNT` - Number of iterations the test suite will run.
- `ZTEST_SHUFFLE_TEST_REPEAT_COUNT` - Number of iterations the test will run.

Test Selection

For POSIX enabled builds with `ZTEST_NEW_API` use command line arguments to list or select tests to run. The test argument expects a comma separated list of `suite::test`. You can substitute the test name with an `*` to run all tests within a suite.

For example

```
$ zephyr.exe -list
$ zephyr.exe -test="fixture_tests::test_fixture_pointer,framework_tests::test_assert_mem_equal"
$ zephyr.exe -test="framework_tests::*"
```

### 2.11.2 Test Runner (Twister)

This script scans for the set of unit test applications in the git repository and attempts to execute them. By default, it tries to build each test case on boards marked as default in the board definition file.

The default options will build the majority of the tests on a defined set of boards and will run in an emulated environment if available for the architecture or configuration being tested.

In normal use, twister runs a limited set of kernel tests (inside an emulator). Because of its limited test execution coverage, twister cannot guarantee local changes will succeed in the full build environment, but it does sufficient testing by building samples and tests for different boards and different configurations to help keep the complete code tree buildable.

When using (at least) one `--v` option, twister's console output shows for every test how the test is run (qemu, native_posix, etc.) or whether the binary was just built. There are a few reasons why twister only builds a test and doesn’t run it:

- The test is marked as `build_only: true` in its `.yaml` configuration file.
- The test configuration has defined a harness but you don’t have it or haven’t set it up.
- The target device is not connected and not available for flashing.
- You or some higher level automation invoked twister with `--build-only`.

To run the script in the local tree, follow the steps below:

**Linux**

```
$ source zephyr-env.sh
$ ./scripts/twister
```

**Windows**

```
zephyr-env.cmd
python ./scripts\twister
```
If you have a system with a large number of cores and plenty of free storage space, you can build and run all possible tests using the following options:

**Linux**

```
$ ./scripts/twister --all --enable-slow
```

**Windows**

```
python .\scripts\twister --all --enable-slow
```

This will build for all available boards and run all applicable tests in a simulated (for example QEMU) environment.

If you want to run tests on one or more specific platforms, you can use the `--platform` option, it is a platform filter for testing, with this option, test suites will only be built/run on the platforms specified. This option also supports different revisions of one same board, you can use `--platform board@revision` to test on a specific revision.

The list of command line options supported by twister can be viewed using:

**Linux**

```
$ ./scripts/twister --help
```

**Windows**

```
python .\scripts\twister --help
```

### Board Configuration

To build tests for a specific board and to execute some of the tests on real hardware or in an emulation environment such as QEMU a board configuration file is required which is generic enough to be used for other tasks that require a board inventory with details about the board and its configuration that is only available during build time otherwise.

The board metadata file is located in the board directory and is structured using the YAML markup language. The example below shows a board with a data required for best test coverage for this specific board:

```yaml
identifier: frdm_k64f
name: NXP FRDM-K64F
type: mcu
arch: arm
toolchain:
  - zephyr
  - gnuarmemb
  - xtools
supported:
  - arduino_gpio
  - arduino_i2c
  - netif:eth
  - adc
  - i2c
  - nvs
  - spi
  - gpio
  - usb_device
  - watchdog
  - can
```

(continues on next page)
- pwm

**testing:**

default: true

**identifier:**

A string that matches how the board is defined in the build system. This same string is used when building, for example when calling `west build` or `cmake`:

```sh
# with west
west build -b reel_board
# with cmake
cmake -DBOARD=reel_board ..
```

**name:**

The actual name of the board as it appears in marketing material.

**type:**

Type of the board or configuration, currently we support 2 types: mcu, qemu

**arch:**

Architecture of the board

**toolchain:**

The list of supported toolchains that can build this board. This should match one of the values used for 'ZEPHYR_TOOLCHAIN_VARIANT' when building on the command line

**ram:**

Available RAM on the board (specified in KB). This is used to match testcase requirements. If not specified we default to 128KB.

**flash:**

Available FLASH on the board (specified in KB). This is used to match testcase requirements. If not specified we default to 512KB.

**supported:**

A list of features this board supports. This can be specified as a single word feature or as a variant of a feature class. For example:

```sh
supported:
  - pci
```

This indicates the board does support PCI. You can make a testcase build or run only on such boards, or:

```sh
supported:
  - netif:eth
  - sensor:bmi16
```

A testcase can both depend on ‘eth’ to only test ethernet or on ‘netif’ to run on any board with a networking interface.

**testing:**

testing relating keywords to provide best coverage for the features of this board.

**default:** [True|False]:

This is a default board, it will tested with the highest priority and is covered when invoking the simplified twister without any additional arguments.

**ignore_tags:**

Do not attempt to build (and therefore run) tests marked with this list of tags.

**only_tags:**

Only execute tests with this list of tags on a specific platform.
Test Cases

Test cases are detected by the presence of a ‘testcase.yaml’ or a ‘sample.yaml’ files in the application’s project directory. This file may contain one or more entries in the test section each identifying a test scenario.

The name of each testcase needs to be unique in the context of the overall testsuite and has to follow basic rules:

1. The format of the test identifier shall be a string without any spaces or special characters (allowed characters: alphanumeric and [_=]) consisting of multiple sections delimited with a dot (.)
2. Each test identifier shall start with a section followed by a subsection separated by a dot. For example, a test that covers semaphores in the kernel shall start with kernel.semaphore.
3. All test identifiers within a testcase.yaml file need to be unique. For example a testcase.yaml file covering semaphores in the kernel can have:
   - kernel.semaphore: For general semaphore tests
   - kernel.semaphore.stress: Stress testing semaphores in the kernel.
4. Depending on the nature of the test, an identifier can consist of at least two sections:
   - Ztest tests: The individual testcases in the ztest testsuite will be concatenated to identifier in the testcase.yaml file generating unique identifiers for every testcase in the suite.
   - Standalone tests and samples: This type of test should at least have 3 sections in the test identifier in the testcase.yaml (or sample.yaml) file. The last section of the name shall signify the test itself.

Test cases are written using the YAML syntax and share the same structure as samples. The following is an example test with a few options that are explained in this document.

```yaml
tests:
  bluetooth.gatt:
    build_only: true
    platform_allow: qemu_cortex_m3 qemu_x86
    tags: bluetooth
  bluetooth.gatt.br:
    build_only: true
    extra_args: CONF_FILE="prj_br.conf"
    filter: not CONFIG_DEBUG
    platform_exclude: up_squared
    platform_allow: qemu_cortex_m3 qemu_x86
    tags: bluetooth

A sample with tests will have the same structure with additional information related to the sample and what is being demonstrated:

```yaml
sample:
  name: hello world
  description: Hello World sample, the simplest Zephyr application
  tests:
    sample.basic.hello_world:
      build_only: true
      tags: tests
      min_ram: 16
    sample.basic.hello_world.singlethread:
      build_only: true
      extra_args: CONF_FILE=prj_single.conf
      filter: not CONFIG_BT
```
The full canonical name for each test case is:

<path to test case>/<test entry>

Each test block in the testcase meta data can define the following key/value pairs:

**tags: <list of tags>** *(required)*
A set of string tags for the testcase. Usually pertains to functional domains but can be anything. Command line invocations of this script can filter the set of tests to run based on tag.

**skip: <True|False>** *(default False)*
skip testcase unconditionally. This can be used for broken tests.

**slow: <True|False>** *(default False)*
Don't run this test case unless --enable-slow was passed in on the command line. Intended for time-consuming test cases that are only run under certain circumstances, like daily builds. These test cases are still compiled.

**extra_args: <list of extra arguments>*
Extra arguments to pass to Make when building or running the test case.

**extra_configs: <list of extra configurations>*
Extra configuration options to be merged with a master prj.conf when building or running the test case. For example:

```plaintext
common:
  tags: drivers adc
tests:
  test:
    depends_on: adc
test_async:
  extra_configs:
    - CONFIG_ADC_ASYNC=y
```

**build_only: <True|False>** *(default False)*
If true, don’t try to run the test even if the selected platform supports it.

**build_on_all: <True|False>** *(default False)*
If true, attempt to build test on all available platforms.

**depends_on: <list of features>*
A board or platform can announce what features it supports, this option will enable the test only those platforms that provide this feature.

**min_ram: <integer>*
minimum amount of RAM in KB needed for this test to build and run. This is compared with information provided by the board metadata.

**min_flash: <integer>*
minimum amount of ROM in KB needed for this test to build and run. This is compared with information provided by the board metadata.

**timeout: <number of seconds>*
Length of time to run test in QEMU before automatically killing it. Default to 60 seconds.

**arch_allow: <list of arches, such as x86, arm, arc>*
Set of architectures that this test case should only be run for.

**arch_exclude: <list of arches, such as x86, arm, arc>*
Set of architectures that this test case should not run on.
platform_allow: <list of platforms>
Set of platforms that this test case should only be run for. Do not use this option to limit testing or building in CI due to time or resource constraints, this option should only be used if the test or sample can only be run on the allowed platform and nothing else.

integration_platforms: <YML list of platforms/boards>
This option limits the scope to the listed platforms when twister is invoked with the –integration option. Use this instead of platform_allow if the goal is to limit scope due to timing or resource constraints.

platform_exclude: <list of platforms>
Set of platforms that this test case should not run on.

extra_sections: <list of extra binary sections>
When computing sizes, twister will report errors if it finds extra, unexpected sections in the Zephyr binary unless they are named here. They will not be included in the size calculation.

dev_timeout: <positive integer> (default None)
Set a limit on the time that each test case is allowed to run. If the test case takes longer than this amount of time to run, it will be timed out. This is used for device testing cases that may take a long time to run. Setting this value to None will disable the timeout.

device_start: <device start >
Run this before the test case starts. Useful for initializing hardware or setting up environments.

device_stop: <device stop >
Run this after the test case stops. Useful for cleaning up or shutting down hardware.

deviceroot: <deviceroot>
Set the root directory for the test case. Used to determine the location of test case files.

devicename: <devicename>
Set the name of the device for this test case. Used to identify the device in test case output.

devicetype: <devicetype>
Set the type of the device for this test case. Used to identify the device type in test case output.

devicememory: <devicememory>
Set the memory configuration for this test case. Used to identify the device memory in test case output.

devicecheck: <devicecheck>
Set the device check configuration for this test case. Used to identify the device check in test case output.

devicemodule: <devicemodule>
Set the device module configuration for this test case. Used to identify the device module in test case output.

devicemodulecheck: <devicemodulecheck>
Set the device module check configuration for this test case. Used to identify the device module check in test case output.

devicemoduleversion: <devicemoduleversion>
Set the device module version configuration for this test case. Used to identify the device module version in test case output.

devicemodulebuild: <devicemodulebuild>
Set the device module build configuration for this test case. Used to identify the device module build in test case output.

devicemodulecheckbuild: <devicemodulecheckbuild>
Set the device module check build configuration for this test case. Used to identify the device module check build in test case output.

The following options are currently supported:

type: <one_line|multi_line> (required)
Depends on the regex string to be matched

record: <recording options>

regex: <expression> (required)
Any string that the particular test case prints to record test results.

regex: <expression> (required)
Any string that the particular test case prints to confirm test runs as expected.

ordered: <True|False> (default False)
Check the regular expression strings in orderly or randomly fashion

repeat: <integer>
Number of times to validate the repeated regex expression

fixture: <expression>
Specify a test case dependency on an external device(e.g., sensor), and identify setups that fulfill this dependency. It depends on specific test setup and board selection logic to pick the particular board(s) out of multiple boards that fulfill the dependency in an automation setup based on “fixture” keyword. Some sample fixture names are i2c_hts221, i2c_bme280, i2c_FRAM, ble_fw and gpio_loop.

Only one fixture can be defined per testcase.

pytest_root: <pytest directory> (default pytest)
Specify a pytest directory which need to execute when test case begin to running, default pytest directory name is pytest, after pytest finished, twister will check if this case pass or fail according the pytest report.
pytest_args: <list of arguments> (default empty)
  Specify a list of additional arguments to pass to pytest.

The following is an example yaml file with a few harness_config options.

```yaml
sample:
  name: HTS221 Temperature and Humidity Monitor
common:
  tags: sensor
  harness: console
  harness_config:
    type: multi_line
    ordered: false
    regex:
      - "Temperature:(.*)C"
      - "Relative Humidity:(.*)%"
  fixture: i2c_hts221
tests:
  test:
    tags: sensors
    depends_on: i2c
```

The following is an example yaml file with pytest harness_config options, default pytest_root name "pytest" will be used if pytest_root not specified. please refer the example in samples/subsys/testsuite/pytest/.

```yaml
tests:
  pytest.example:
    harness: pytest
    harness_config:
      pytest_root: [pytest directory name]
```

filter: <expression>
  Filter whether the testcase should be run by evaluating an expression against an environment containing the following values:

```yaml
{ ARCH : <architecture>,
  PLATFORM : <platform>,
  <all CONFIG_* key/value pairs in the test's generated defconfig>,
  *<env>: any environment variable available
}
```

The grammar for the expression language is as follows:

expression ::= expression “and” expression

expression “or” expression

“not” expression

“(” expression “)”

symbol “==” constant

symbol “!”=” constant

symbol “<” number

symbol “>” number

symbol “>=” number

symbol “<=” number

symbol “in” list

symbol “:” string

symbol
list ::= "[" list_contents "]"

list_contents ::= constant

list_contents "," constant

constant ::= number

string

For the case where expression ::= symbol, it evaluates to true if the symbol is defined to a non-empty string.

Operator precedence, starting from lowest to highest:

- or (left associative) and (left associative) not (right associative)
- all comparison operators
- (non-associative)

arch_allow, arch_exclude, platform_allow, platform_exclude are all syntactic sugar for these expressions. For instance

arch_exclude = x86 arc

Is the same as:

filter = not ARCH in ["x86", "arc"]

The ‘:’ operator compiles the string argument as a regular expression, and then returns a true value only if the symbol’s value in the environment matches. For example, if CONFIG_SOC="stm32f107xc" then

filter = CONFIG_SOC : "stm.*"

Would match it.

The set of test cases that actually run depends on directives in the testcase filed and options passed in on the command line. If there is any confusion, running with -v or examining the discard report (twister_discard.csv) can help show why particular test cases were skipped.

Metrics (such as pass/fail state and binary size) for the last code release are stored in scripts/release/twister_last_release.csv. To update this, pass the --all --release options.

To load arguments from a file, write ‘+’ before the file name, e.g., +file_name. File content must be one or more valid arguments separated by line break instead of white spaces.

Most everyday users will run with no arguments.

Running in Integration Mode

This mode is used in continuous integration (CI) and other automated environments used to give developers fast feedback on changes. The mode can be activated using the --integration option of twister and narrows down the scope of builds and tests if applicable to platforms defined under the integration keyword in the testcase definition file (testcase.yaml and sample.yaml).

Running Tests on Hardware

Beside being able to run tests in QEMU and other simulated environments, twister supports running most of the tests on real devices and produces reports for each run with detailed FAIL/PASS results.
Executing tests on a single device  To use this feature on a single connected device, run twister with the following new options:

**Linux**

```
scripts/twister --device-testing --device-serial /dev/ttyACM0
--device-serial-baud 115200 -p frdm_k64f -T tests/kernel
```

**Windows**

```
python .\scripts\twister --device-testing --device-serial COM1
--device-serial-baud 115200 -p frdm_k64f -T tests/kernel
```

The `--device-serial` option denotes the serial device the board is connected to. This needs to be accessible by the user running twister. You can run this on only one board at a time, specified using the `--platform` option.

The `--device-serial-baud` option is only needed if your device does not run at 115200 baud.

To support devices without a physical serial port, use the `--device-serial-pty` option. In this cases, log messages are captured for example using a script. In this case you can run twister with the following options:

**Linux**

```
scripts/twister --device-testing --device-serial-pty "script.py"
-p intel_adsp_cavs25 -T tests/kernel
```

**Windows**

**Note:** Not supported on Windows OS

The script is user-defined and handles delivering the messages which can be used by twister to determine the test execution status.

Executing tests on multiple devices  To build and execute tests on multiple devices connected to the host PC, a hardware map needs to be created with all connected devices and their details such as the serial device, baud and their IDs if available. Run the following command to produce the hardware map:

**Linux**

```
./scripts/twister --generate-hardware-map map.yml
```

**Windows**

```
python .\scripts\twister --generate-hardware-map map.yml
```

The generated hardware map file (map.yml) will have the list of connected devices, for example:

**Linux**

```
- connected: true
  id: OSHW000032254e4500128002ab98002784d1000097969900
  platform: unknown
  product: DAPLink CMSIS-DAP
  runner: pyocd
  serial: /dev/cu.usbmodem14614202
- connected: true
  id: 000683759358
  platform: unknown
```
(continues on next page)
product: J-Link
runner: unknown
serial: /dev/cu.usbmodem0006837593581

Windows

- connected: true
  id: 000683759358
  platform: unknown
  product: unknown
  runner: unknown
  serial: COM1
- connected: true
  id: 000683759358
  platform: unknown
  product: unknown
  runner: unknown
  serial: COM2

Any options marked as 'unknown' need to be changed and set with the correct values, in the above example the platform names, the products and the runners need to be replaced with the correct values corresponding to the connected hardware. In this example we are using a reel_board and an nrf52840dk_nrf52840:

Linux

- connected: true
  id: 000683759358
  platform: reel_board
  product: DAPLink CMSIS-DAP
  runner: pyocd
  serial: /dev/cu.usbmodem146114202
  baud: 9600
- connected: true
  id: 000683759358
  platform: nrf52840dk_nrf52840
  product: J-Link
  runner: nrfjprog
  serial: /dev/cu.usbmodem0006837593581
  baud: 9600

Windows

- connected: true
  id: 000683759358
  platform: reel_board
  product: DAPLink CMSIS-DAP
  runner: pyocd
  serial: COM1
  baud: 9600
- connected: true
  id: 000683759358
  platform: nrf52840dk_nrf52840
  product: J-Link
  runner: nrfjprog
  serial: COM2
  baud: 9600
The baud entry is only needed if not running at 115200.

If the map file already exists, then new entries are added and existing entries will be updated. This way you can use one single master hardware map and update it for every run to get the correct serial devices and status of the devices.

With the hardware map ready, you can run any tests by pointing to the map

**Linux**

```
./scripts/twister --device-testing --hardware-map map.yml -T samples/hello_world/
```

**Windows**

```
python ./scripts/twister --device-testing --hardware-map map.yml -T samples\hello_world
```

The above command will result in twister building tests for the platforms defined in the hardware map and subsequently flashing and running the tests on those platforms.

---

**Note:** Currently only boards with support for both pyocd and nrfjprog are supported with the hardware map features. Boards that require other runners to flash the Zephyr binary are still work in progress.

---

Serial PTY support using `--device-serial-pty` can also be used in the hardware map:

```
- connected: true
  id: None
  platform: intel_adsp_cavs18
  product: None
  runner: intel_adsp
  serial_pty: path/to/script.py
  runner_params:
    - --remote-host=remote_host_ip_addr
    - --key=/path/to/key.pem
- connected: true
  id: None
  platform: intel_adsp_cavs25
  product: None
  runner: intel_adsp
  serial_pty: path/to/script.py
  runner_params:
    - --remote-host=remote_host_ip_addr
    - --key=/path/to/key.pem
```

The runner_params field indicates the parameters you want to pass to the west runner. For some boards the west runner needs some extra parameters to work. It is equivalent to following west and twister commands.

**Linux**

```
west flash --remote-host remote_host_ip_addr --key /path/to/key.pem
twister -p intel_adsp_cavs18 --device-testing --device-serial-pty script.py
 --west-flash="--remote-host=remote_host_ip_addr,--key=/path/to/key.pem"
```

**Windows**

**Note:** Not supported on Windows OS
**Note:** For serial PTY, the “--generate-hardware-map” option cannot scan it out and generate a correct hardware map automatically. You have to edit it manually according to above example. This is because the serial port of the PTY is not fixed and being allocated in the system at runtime.

**Fixtures** Some tests require additional setup or special wiring specific to the test. Running the tests without this setup or test fixture may fail. A testcase can specify the fixture it needs which can then be matched with hardware capability of a board and the fixtures it supports via the command line or using the hardware map file.

Fixtures are defined in the hardware map file as a list:

```plaintext
- connected: true
  fixtures:
    - gpio_loopback
      id: 0240000026334e450015400f5e0e00b4eb1000097969900
      platform: frdm_k64f
      product: DAPLink CMSIS-DAP
      runner: pyocd
      serial: /dev/ttyACM9
```

When running `twister` with `--device-testing`, the configured fixture in the hardware map file will be matched to testcases requesting the same fixtures and these test will be executed on the boards that provide this fixture.

Fixtures can also be provided via `twister` command option `--fixture`, this option can be used multiple times and all given fixtures will be appended as a list. And the given fixtures will be assigned to all boards, this means that all boards set by current `twister` command can run those testcases which request the same fixtures.

**Notes** It may be useful to annotate board descriptions in the hardware map file with additional information. Use the “notes” keyword to do this. For example:

```plaintext
- connected: false
  fixtures:
    - gpio_loopback
      id: 000683290670
      notes: An nrf5340dk_nrf5340 is detected as an nrf52840dk_nrf52840 with no serial port, and three serial ports with an unknown platform. The board id of the serial ports is not the same as the board id of the development kit. If you want to regenerate this file you will need to update serial to reference the third port, and platform to nrf5340dk_nrf5340_cpuapp or another supported board target.
      platform: nrf52840dk_nrf52840
      product: J-Link
      runner: jlink
      serial: null
```

**Overriding Board Identifier** When (re-)generated the hardware map file will contain an “id” keyword that serves as the argument to `--board-id` when flashing. In some cases the detected ID is not the correct one to use, for example when using an external J-Link probe. The “probe_id” keyword overrides the “id” keyword for this purpose. For example:

```plaintext
- connected: false
  id: 022900000059ebc6000000000000000000000000000000000000000
```

(continues on next page)
Quarantine Twister allows using user-defined yaml files defining the list of tests to be put under quarantine. Such tests will be skipped and marked accordingly in the output reports. This feature is especially useful when running larger test suits, where a failure of one test can affect the execution of other tests (e.g. putting the physical board in a corrupted state).

To use the quarantine feature one has to add the argument 

```bash
--quarantine-list
(PATH_TO_QUARANTINE_YAML)
```

to a twister call. The current status of tests on the quarantine list can also be verified by adding 

```bash
--quarantine-verify
```

to the above argument. This will make twister skip all tests which are not on the given list.

A quarantine yaml has to be a sequence of dictionaries. Each dictionary has to have “scenarios” and “platforms” entries listing combinations of scenarios and platforms to put under quarantine. In addition, an optional entry “comment” can be used, where some more details can be given (e.g. link to a reported issue). These comments will also be added to the output reports.

An example of entries in a quarantine yaml:

```yaml
- scenarios:
  - sample.basic.helloworld
  platforms:
    - all
  comment: "Link to the issue: https://github.com/zephyrproject-rtos/zephyr/pull/33287"

- scenarios:
  - kernel.common
  - kernel.common.misra
  - kernel.common.nano64
  platforms:
    - qemu_cortex_m3
    - native_posix
```

Running in Tests in Random Order

Enable ZTEST framework’s CONFIG_ZTEST_SHUFFLE config option to run your tests in random order. This can be beneficial for identifying dependencies between test cases. For native_posix platforms, you can provide the seed to the random number generator by providing 

```bash
-seed=value
```

as an argument to twister. See Shuffling Test Sequence for more details.

### 2.11.3 Generating coverage reports

With Zephyr, you can generate code coverage reports to analyze which parts of the code are covered by a given test or application.

You can do this in two ways:

- In a real embedded target or QEMU, using Zephyr’s gcov integration
- Directly in your host computer, by compiling your application targeting the POSIX architecture
Test coverage reports in embedded devices or QEMU

**Overview** GCC GCOV is a test coverage program used together with the GCC compiler to analyze and create test coverage reports for your programs, helping you create more efficient, faster running code and discovering untested code paths.

In Zephyr, gcov collects coverage profiling data in RAM (and not to a file system) while your application is running. Support for gcov collection and reporting is limited by available RAM size and so is currently enabled only for QEMU emulation of embedded targets.

**Details** There are 2 parts to enable this feature. The first is to enable the coverage for the device and the second to enable in the test application. As explained earlier the code coverage with gcov is a function of RAM available. Therefore ensure that the device has enough RAM when enabling the coverage for it. For example a small device like frdm_k64f can run a simple test application but the more complex test cases which consume more RAM will crash when coverage is enabled.

To enable the device for coverage, select `CONFIG_HAS_COVERAGE_SUPPORT` in the Kconfig.board file.

To report the coverage for the particular test application set `CONFIG_COVERAGE`.

**Steps to generate code coverage reports** These steps will produce an HTML coverage report for a single application.

1. Build the code with `CONFIG_COVERAGE=y`.
   ```bash
   west build -b mps2_an385 -- -DCONFIG_COVERAGE=y -DCONFIG_COVERAGE_DUMP=y
   ```
2. Capture the emulator output into a log file. You may need to terminate the emulator with Ctrl-A X for this to complete after the coverage dump has been printed:
   ```bash
   ninja -Cbuild run | tee log.log
   or
   ninja -Cbuild run | tee log.log
   ```
3. Generate the gcov .gcda and .gcno files from the log file that was saved:
   ```bash
   $ python3 scripts/gen_gcov_files.py -i log.log
   ```
4. Find the gcov binary placed in the SDK. You will need to pass the path to the gcov binary for the appropriate architecture when you later invoke gcovr:
   ```bash
   $ find $ZEPHYR_SDK_INSTALL_DIR -iregex ".*gcov"
   ```
5. Create an output directory for the reports:
   ```bash
   $ mkdir -p gcov_report
   ```
6. Run gcovr to get the reports:
   ```bash
   $ gcovr -r $ZEPHYR_BASE . --html --o gcov_report/coverage.html --html-details --gcov-executable <gcov_path_in_SDK>
   ```

**Coverage reports using the POSIX architecture**

When compiling for the POSIX architecture, you utilize your host native tooling to build a native executable which contains your application, the Zephyr OS, and some basic HW emulation.
That means you can use the same tools you would while developing any other desktop application.

To build your application with gcc's gcov, simply set CONFIG_COVERAGE before compiling it. When you run your application, gcov coverage data will be dumped into the respective gcda and gcno files. You may postprocess these with your preferred tools. For example:

```
west build -b native_posix samples/hello_world -- -DCONFIG_COVERAGE=y

$ ./build/zephyr/zephyr.exe
# Press Ctrl+C to exit
lcov --capture --directory ./ --output-file lcov.info -q --rc lcov_branch_coverage=1
genhtml lcov.info --output-directory lcov_html -q --ignore-errors source --branch--coverage --highlight --legend
```

**Note:** You need a recent version of lcov (at least 1.14) with support for intermediate text format. Such packages exist in recent Linux distributions. Alternatively, you can use gcovr (at least version 4.2).

**Coverage reports using Twister**

Zephyr's `twister script` can automatically generate a coverage report from the tests which were executed. You just need to invoke it with the `--coverage` command line option.

For example, you may invoke:

```
$ twister --coverage -p qemu_x86 -T tests/kernel
```

or:

```
$ twister --coverage -p native_posix -T tests/bluetooth
```

which will produce `twister-out/coverage/index.html` with the report.

The process differs for unit tests, which are built with the host toolchain and require a different board:

```
$ twister --coverage -p unit_testing -T tests/unit
```

which produces a report in the same location as non-unit testing.

### 2.11.4 Sparse support

Sparse is a static code analysis tool. Apart from performing common code analysis tasks it also supports an `address_space` attribute, which allows introduction of distinct address spaces in C code with subsequent verification that pointers to different address spaces do not get confused. Additionally it supports a `force` attribute which should be used to cast pointers between different address spaces. At the moment Zephyr introduces a single custom address space `__cache` used to identify pointers from the cached address range on the Xtensa architecture. This helps identify cases where cached and uncached addresses are confused.

**Running with sparse**

To run a sparse verification build `west build` should be called with a `-DSPARSE=y` parameter, e.g.

```
wester build -d hello -b intel_adsp_cavs25 zephyr/samples/hello_world -- -DSPARSE=y
```
2.11.5 ZTest Deprecated APIs

Ztest is currently being migrated to a new API, this documentation provides information about the deprecated APIs which will eventually be removed. See Test Framework for the new API. Similarly, ZTest's mocking framework is also deprecated (see Mocking via FFF).

Quick start - Unit testing

Ztest can be used for unit testing. This means that rather than including the entire Zephyr OS for testing a single function, you can focus the testing efforts into the specific module in question. This will speed up testing since only the module will have to be compiled in, and the tested functions will be called directly.

Since you won't be including basic kernel data structures that most code depends on, you have to provide function stubs in the test. Ztest provides some helpers for mocking functions, as demonstrated below.

In a unit test, mock objects can simulate the behavior of complex real objects and are used to decide whether a test failed or passed by verifying whether an interaction with an object occurred, and if required, to assert the order of that interaction.

Best practices for declaring the test suite  

Twister and other validation tools need to obtain the list of subcases that a Zephyr ztest test image will expose.

Rationale

This all is for the purpose of traceability. It's not enough to have only a semaphore test project. We also need to show that we have testpoints for all APIs and functionality, and we trace back to documentation of the API, and functional requirements.

The idea is that test reports show results for every sub-testcase as passed, failed, blocked, or skipped. Reporting on only the high-level test project level, particularly when tests do too many things, is too vague.

There exist two alternatives to writing tests. The first, and more verbose, approach is to directly declare and run the test suites. Here is a generic template for a test showing the expected use of ztest_test_suite():

```c
#define CONFIG_WHATEVER /* Conditionally skip test_sometest3 */
void test_sometest3(void)
{
    ztest_test_skip();
}
else
void test_sometest4(void);
...

void test_main(void)
{
    ztest_test_suite(common,
                     ztest_unit_test(test_sometest1),
                     ztest_unit_test(test_sometest2),
                     ...
    
(continues on next page)```
ztest_unit_test(test_sometest3),
    ztest_unit_test(test_sometest4)
);  
ztest_run_test_suite(common);
}

Alternatively, it is possible to split tests across multiple files using ztest_register_test_suite() which bypasses the need for extern:

```c
#include <zephyr/ztest.h>

void test_sometest1(void) {
    zassert_true(1, "true");
}

ztest_register_test_suite(common, NULL,
                           ztest_unit_test(test_sometest1)
                          );
```

The above sample simple registers the test suite and uses a NULL pragma function (more on that later). It is important to note that the test suite isn't directly run in this file. Instead two alternatives exist for running the suite. First, if to do nothing. A default test_main function is provided by ztest. This is the preferred approach if the test doesn't involve a state and doesn't require use of the pragma.

In cases of an integration test it is possible that some general state needs to be set between test suites. This can be thought of as a state diagram in which test_main simply goes through various actions that modify the board's state and different test suites need to run. This is achieved in the following:

```c
#include <zephyr/ztest.h>

struct state {
    bool is_hibernating;
    bool is_usb_connected;
}

static bool pragma_always(const void *state) {
    return true;
}

static bool pragma_not_hibernating_not_connected(const void *s) {
    struct state *state = s;
    return !state->is_hibernating && !state->is_usb_connected;
}

static bool pragma_usb_connected(const void *s) {
    return ((struct state *)s)->is_usb_connected;
}

ztest_register_test_suite(baseline, pragma_always,
                         ztest_unit_test(test_case0));
ztest_register_test_suite(before_usb, pragma_not_hibernating_not_connected,
                          ztest_unit_test(test_case1),
                          ztest_unit_test(test_case2));
ztest_register_test_suite(with_usb, pragma_usb_connected,
                          (continues on next page)
ztest_unit_test(test_case3),
ztest_unit_test(test_case4));

void test_main(void)
{
    struct state state;

    /* Should run `baseline` test suite only. */
    ztest_run_registered_test_suites(&state);

    /* Simulate power on and update state. */
    emulate_power_on();
    /* Should run `baseline` and `before_usb` test suites. */
    ztest_run_registered_test_suites(&state);

    /* Simulate plugging in a USB device. */
    emulate_plugging_in_usb();
    /* Should run `baseline` and `with_usb` test suites. */
    ztest_run_registered_test_suites(&state);

    /* Verify that all the registered test suites actually ran. */
    ztest_verify_all_registered_test_suites_ran();
}

For twister to parse source files and create a list of subcases, the declarations of ztest_test_suite() and ztest_register_test_suite() must follow a few rules:

- one declaration per line
- conditional execution by using ztest_test_skip()

What to avoid:

- packing multiple testcases in one source file

void test_main(void)
{
    #ifdef TEST_feature1
    ztest_test_suite(feature1,
    ztest_unit_test(test_1a),
    ztest_unit_test(test_1b),
    ztest_unit_test(test_1c)
    );
    ztest_run_test_suite(feature1);
    #endif

    #ifdef TEST_feature2
    ztest_test_suite(feature2,
    ztest_unit_test(test_2a),
    ztest_unit_test(test_2b)
    );
    ztest_run_test_suite(feature2);
    #endif

    • Do not use #if

    ztest_test_suite(common,
    ztest_unit_test(test_sometest1),

• Do not add comments on lines with a call to ztest_unit_test():

```c
ztest_test_suite(common,
    ztest_unit_test(test_sometest1),
    ztest_unit_test(test_sometest2) /* will fail */,
    /* will fail! */ ztest_unit_test(test_sometest3),
    ztest_unit_test(test_sometest4),
...}
```

• Do not define multiple definitions of unit / user unit test case per line

```c
ztest_test_suite(common,
    ztest_unit_test(test_sometest1), ztest_unit_test(test_sometest2),
    ztest_unit_test(test_sometest3),
    ztest_unit_test(test_sometest4),
...}
```

Other questions:

• Why not pre-scan with CPP and then parse? or post scan the ELF file?
  If C pre-processing or building fails because of any issue, then we won’t be able to tell the subcases.

• Why not declare them in the YAML testcase description?
  A separate testcase description file would be harder to maintain than just keeping the information
  in the test source files themselves – only one file to update when changes are made eliminates
  duplication.

Mocking

These functions allow abstracting callbacks and related functions and controlling them from specific
tests. You can enable the mocking framework by setting CONFIG_ZTEST_MOCKING to “y” in the configu-
ration file of the test. The amount of concurrent return values and expected parameters is limited by
CONFIG_ZTEST_PARAMETER_COUNT.

Here is an example for configuring the function expect_two_parameters to expect the values \(a=2\) and \(b=3\), and telling returns_int to return 5:

```c
#include <zephyr/ztest.h>

static void expect_two_parameters(int a, int b)
{
    ztest_check_expected_value(a);
    ztest_check_expected_value(b);
}

static void parameter_tests(void)
{
    ztest_expect_value(expect_two_parameters, a, 2);
}
group ztest_mock

This module provides simple mocking functions for unit testing. These need CONFIG_ZTEST_MOCKING=y.

**Defines**

ztest_expect_value(func, param, value)

Tell function *func* to expect the value *value* for *param*. When using ztest_check_expected_value(), tell that the value of *param* should be *value*. The value will internally be stored as an uintptr_t.

**Parameters**

- func – Function in question
- param – Parameter for which the value should be set
- value – Value for *param*

ztest_check_expected_value(param)

If *param* doesn’t match the value set by ztest_expect_value(), fail the test.

This will first check that does *param* have a value to be expected, and then checks whether the value of the parameter is equal to the expected value. If either of these checks fail, the current test will fail. This must be called from the called function.

**Parameters**

- param – Parameter to check

ztest_expect_data(func, param, data)

Tell function *func* to expect the data *data* for *param*.  

2.11. Testing
When using `ztest_check_expected_data()`, the data pointed to by `param` should be same `data` in this function. Only data pointer is stored by this function, so it must still be valid when `ztest_check_expected_data` is called.

**Parameters**

- `func` – Function in question
- `param` – Parameter for which the data should be set
- `data` – pointer for the data for parameter `param`

```c
ztest_check_expected_data(param, length)
```

If data pointed by `param` don’t match the data set by `ztest_expect_data()`, fail the test.

This will first check that `param` is expected to be null or non-null and then check whether the data pointed by parameter is equal to expected data. If either of these checks fail, the current test will fail. This must be called from the called function.

**Parameters**

- `param` – Parameter to check
- `length` – Length of the data to compare

```c
ztest_return_data(func, param, data)
```

Tell function `func` to return the data `data` for `param`.

When using `ztest_return_data()`, the data pointed to by `param` should be same `data` in this function. Only data pointer is stored by this function, so it must still be valid when `ztest_copy_return_data` is called.

**Parameters**

- `func` – Function in question
- `param` – Parameter for which the data should be set
- `data` – pointer for the data for parameter `param`

```c
ztest_copy_return_data(param, length)
```

Copy the data set by `ztest_return_data` to the memory pointed by `param`.

This will first check that `param` is not null and then copy the data. This must be called from the called function.

**Parameters**

- `param` – Parameter to return data for
- `length` – Length of the data to return

```c
ztest_returns_value(func, value)
```

Tell `func` that it should return `value`.

**Parameters**

- `func` – Function that should return `value`
- `value` – Value to return from `func`

```c
ztest_get_return_value()
```

Get the return value for current function.

The return value must have been set previously with `ztest_returns_value()`. If no return value exists, the current test will fail.

**Returns**

The value the current function should return
ztest_get_return_value_ptr()

Get the return value as a pointer for current function.

The return value must have been set previously with `ztest_returns_value()`. If no return value exists, the current test will fail.

**Returns**

The value the current function should return as a `void *`

## 2.12 Toolchains

Guides on how to set up toolchains for Zephyr development.

### 2.12.1 Zephyr SDK

The Zephyr Software Development Kit (SDK) contains toolchains for each of Zephyr's supported architectures. It also includes additional host tools, such as custom QEMU and OpenOCD.

Use of the Zephyr SDK is highly recommended and may even be required under certain conditions (for example, running tests in QEMU for some architectures).

**Supported architectures**

The Zephyr SDK supports the following target architectures:

- ARC (32-bit and 64-bit; ARCv1, ARCv2, ARCv3)
- ARM (32-bit and 64-bit; ARMv6, ARMv7, ARMv8; A/R/M Profiles)
- MIPS (32-bit and 64-bit)
- Nios II
- RISC-V (32-bit and 64-bit; RV32I, RV32E, RV64I)
- x86 (32-bit and 64-bit)
- Xtensa

**Installation bundle and variables**

The Zephyr SDK bundle supports all major operating systems (Linux, macOS and Windows) and is delivered as a compressed file. The installation consists of extracting the file and running the included setup script. Additional OS-specific instructions are described in the sections below.

If no toolchain is selected, the build system looks for Zephyr SDK and uses the toolchain from there. You can enforce this by setting the environment variable `ZEPHYR_TOOLCHAIN_VARIANT` to `zephyr`.

If you install the Zephyr SDK outside any of the default locations (listed in the operating system specific instructions below) and you want automatic discovery of the Zephyr SDK, then you must register the Zephyr SDK in the CMake package registry by running the setup script. If you decide not to register the Zephyr SDK in the CMake registry, then the `ZEPHYR_SDK_INSTALL_DIR` can be used to point to the Zephyr SDK installation directory.

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

- `/company/tools/zephyr-sdk-0.13.2`
- `/company/tools/zephyr-sdk-a.b.c`
This allows the Zephyr build system to choose the correct version of the SDK, while allowing multiple Zephyr SDKs to be grouped together at a specific path.

Install Zephyr SDK on Linux

1. Download and verify the latest Zephyr SDK bundle:

```
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/zephyr-sdk-0.15.2_linux-x86_64.tar.gz
wget -O - https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/SHA-256.sum | sha256sum --check --ignore-missing
```

You can change 0.15.2 to another version if needed; the Zephyr SDK Releases page contains all available SDK releases.

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

2. Extract the Zephyr SDK bundle archive:

```
cd <sdk download directory>
tar xvf zephyr-sdk-0.15.2_linux-x86_64.tar.gz
```

3. Run the Zephyr SDK bundle setup script:

```
./setup.sh
```

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

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

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

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

The Zephyr SDK bundle archive contains the zephyr-sdk-0.15.2 directory and, when extracted under `$HOME`, the resulting installation path will be `$HOME/zephyr-sdk-0.15.2`.

Install Zephyr SDK on macOS

1. Download and verify the latest Zephyr SDK bundle:

```
cd ~
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/zephyr-sdk-0.15.2_macos-x86_64.tar.gz
```

(continues on next page)
If your host architecture is 64-bit ARM (Apple Silicon, also known as M1), replace x86_64 with aarch64 in order to download the 64-bit ARM macOS SDK.

2. Extract the Zephyr SDK bundle archive:

```
tar xvf zephyr-sdk-0.15.2_macos-x86_64.tar.gz
```

_Note:_ It is recommended to extract the Zephyr SDK bundle at one of the following default locations:

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

The Zephyr SDK bundle archive contains the `zephyr-sdk-0.15.2` directory and, when extracted under $HOME, the resulting installation path will be $HOME/zephyr-sdk-0.15.2.

3. Run the Zephyr SDK bundle setup script:

```
cd zephyr-sdk-0.15.2
./setup.sh
```

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

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

### Install Zephyr SDK on Windows

1. Open a cmd.exe window by pressing the Windows key typing “cmd.exe”.

2. Download the latest Zephyr SDK bundle:

```
cd %HOMEPATH%
wget https://github.com/zephyrproject-rtos/sdk-ng/releases/download/v0.15.2/zephyr-sdk-0.15.2_windows-x86_64.zip
```

3. Extract the Zephyr SDK bundle archive:

```
unzip zephyr-sdk-0.15.2_windows-x86_64.zip
```

_Note:_ It is recommended to extract the Zephyr SDK bundle at one of the following default locations:

- %HOMEPATH%
- %PROGRAMFILES%
The Zephyr SDK bundle archive contains the `zephyr-sdk-0.15.2` directory and, when extracted under `%HOMEPATH%`, the resulting installation path will be `%HOMEPATH%\zephyr-sdk-0.15.2`.

4. Run the Zephyr SDK bundle setup script:

```bash
cd zephyr-sdk-0.15.2
setup.cmd
```

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

### 2.12.2 Arm Compiler 6

1. Download and install a development suite containing the Arm Compiler 6 for your operating system.

2. **Set these environment variables:**
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `armclang`.
   - Set `ARMCLANG_TOOLCHAIN_PATH` to the toolchain installation directory.

3. The Arm Compiler 6 needs the `ARMLMD_LICENSE_FILE` environment variable to point to your license file or server. For example:

   ```bash
   # Linux, macOS, license file:
   export ARMLMD_LICENSE_FILE=/<path>/license_armds.dat
   # Linux, macOS, license server:
   export ARMLMD_LICENSE_FILE=8224@myserver
   
   # Windows, license file:
   set ARMLMD_LICENSE_FILE=c:\<path>\license_armds.dat
   # Windows, license server:
   set ARMLMD_LICENSE_FILE=8224@myserver
   ```

1. If the Arm Compiler 6 was installed as part of an Arm Development Studio, then you must set the `ARM_PRODUCT_DEF` to point to the product definition file: See also: Product and toolkit configuration. For example if the Arm Development Studio is installed in: `/opt/armds-2020-1` with a Gold license, then set `ARM_PRODUCT_DEF` to point to `/opt/armds-2020-1/gold.elmap`.

**Note:** The Arm Compiler 6 uses `armlink` for linking. This is incompatible with Zephyr's linker script template, which works with GNU ld. Zephyr's Arm Compiler 6 support Zephyr's CMake linker script generator, which supports generating scatter files. Basic scatter file support is in place, but there are still areas covered in ld templates which are not fully supported by the CMake linker script generator.

Some Zephyr subsystems or modules may also contain C or assembly code that relies on GNU intrinsics and have not yet been updated to work fully with `armclang`. 

---

Chapter 2. Developing with Zephyr
2.12.3 Cadence Tensilica Xtensa C/C++ Compiler (XCC)

1. Obtain Tensilica Software Development Toolkit targeting the specific SoC on hand. This usually contains two parts:
   - The Xtensa Xplorer which contains the necessary executables and libraries.
   - A SoC-specific add-on to be installed on top of Xtensa Xplorer.
     - This add-on allows the compiler to generate code for the SoC on hand.
2. Install Xtensa Xplorer and then the SoC add-on.
   - Follow the instruction from Cadence on how to install the SDK.
   - Depending on the SDK, there are two set of compilers:
     - GCC-based compiler: xt-xcc and its friends.
     - Clang-based compiler: xt-clang and its friends.
3. Make sure you have obtained a license to use the SDK, or has access to a remote licensing server.
4. Set these environment variables:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xcc` or `xcc-clang`.
   - Set `XTENSA_TOOLCHAIN_PATH` to the toolchain installation directory.
   - Set `XTENSA_CORE` to the SoC ID where application is being targeting.
   - Set `TOOLCHAIN_VER` to the Xtensa SDK version.
5. For example, assuming the SDK is installed in `/opt/xtensa`, and using the SDK for application development on `intel_adsp_cavs15`, setup the environment using:

   ```
   # Linux
   export ZEPHYR_TOOLCHAIN_VARIANT=xcc
   export XTENSA_TOOLCHAIN_PATH=/opt/xtensa/XtDevTools/install/tools/
   export XTENSA_CORE=X6H3SUE_RI_2018_0
   export TOOLCHAIN_VER=RI-2018.0-linux
   ```
6. To use Clang-based compiler:
   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xcc-clang`.
   - Note that the Clang-based compiler may contain an old LLVM bug which results in the following error:

     ```
     /tmp/file.s: Assembler messages:
     /tmp/file.s:20: Error: file number 1 already allocated
     clang-3.9: error: Xtensa-as command failed with exit code 1
     ```

     If this happens, set `XCC_NO_G_FLAG` to 1.
     - For example:

     ```
     # Linux
     export XCC_NO_G_FLAG=1
     ```
   - Also note that setting `XCC_USE_CLANG` to 1 and `ZEPHYR_TOOLCHAIN_VARIANT` to `xcc` is deprecated. Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xcc-clang` instead.

2.12.4 DesignWare ARC MetaWare Development Toolkit (MWDT)

1. You need to have ARC MWDT installed on your host.
2. *Set these environment variables:*
   - Set `$ZEPHYR_TOOLCHAIN_VARIANT` to `arcmwdr`.
   - Set `$ARCMWDT_TOOLCHAIN_PATH` to the toolchain installation directory. MWDT installation provides $METAWARE_ROOT$ so simply set `$ARCMWDT_TOOLCHAIN_PATH` to `$METAWARE_ROOT/..` (Linux) or `%METAWARE_ROOT%\..` (Windows)

3. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the `$ARCMWDT_TOOLCHAIN_PATH` values may be different on your system):

   ```bash
   # Linux:
   $ echo $ZEPHYR_TOOLCHAIN_VARIANT
   arcmwdr
   $ echo $ARCMWDT_TOOLCHAIN_PATH
   /home/you/ARC/MWDT_2019.12/
   
   # Windows:
   > echo %ZEPHYR_TOOLCHAIN_VARIANT%
   arcmwdr
   > echo %ARCMWDT_TOOLCHAIN_PATH%
   C:\ARC\MWDT_2019.12\   
   
   2.12.5 GNU Arm Embedded

1. Download and install a GNU Arm Embedded build for your operating system and extract it on your file system.

   **Note:** On Windows, we'll assume for this guide that you install into the directory `C:\gnu_arm_embedded`. You can also choose the default installation path used by the ARM GCC installer, in which case you will need to adjust the path accordingly in the guide below.

   **Warning:** On macOS Catalina or later you might need to change a security policy for the toolchain to be able to run from the terminal.

2. *Set these environment variables:*
   - Set `$ZEPHYR_TOOLCHAIN_VARIANT` to `gnuarmemb`.
   - Set `$GNUARMEMB_TOOLCHAIN_PATH` to the toolchain installation directory.

3. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the `GNUARMEMB_TOOLCHAIN_PATH` values may be different on your system):

   ```bash
   # Linux, macOS:
   $ echo $ZEPHYR_TOOLCHAIN_VARIANT
   gnuarmemb
   $ echo $GNUARMEMB_TOOLCHAIN_PATH
   /home/you/Downloads/gnu_arm_embedded
   
   # Windows:
   > echo %ZEPHYR_TOOLCHAIN_VARIANT%
   gnuarmemb
   > echo %GNUARMEMB_TOOLCHAIN_PATH%
   C:\gnu_arm_embedded
   ```
2.12.6 Intel oneAPI Toolkit

1. Download Intel oneAPI Base Toolkit

2. Assuming the toolkit is installed in `/opt/intel/oneApi`, set environment using:

   ```
   # Linux, macOS:
   export ONEAPI_TOOLCHAIN_PATH=/opt/intel/oneapi
   source $ONEAPI_TOOLCHAIN_PATH/compiler/latest/env/vars.sh
   
   # Windows:
   > set ONEAPI_TOOLCHAIN_PATH=C:\Users\Intel\oneapi
   ```

   To setup the complete oneApi environment, use:

   ```
   source /opt/intel/oneapi/setvars.sh
   ```

   The above will also change the python environment to the one used by the toolchain and might conflict with what Zephyr uses.

3. Set `ZEPHYR_TOOLCHAIN_VARIANT` to `oneApi`.

2.12.7 Crosstool-NG

You can build toolchains from source code using crosstool-NG.

1. Follow the steps on the crosstool-NG website to prepare your host.

2. Follow the Zephyr SDK with Crosstool NG instructions to build your toolchain. Repeat as necessary to build toolchains for multiple target architectures.

   You will need to clone the `sdk-ng` repo and run the following command:

   ```
   ./go.sh <arch>
   ```

   **Note:** Currently, only i586 and Arm toolchain builds are verified.

3. Set these environment variables:

   - Set `ZEPHYR_TOOLCHAIN_VARIANT` to `xtools`.
   - Set `XTOOLSC_TOOLCHAIN_PATH` to the toolchain build directory.

4. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the `XTOOLSC_TOOLCHAIN_PATH` values may be different on your system):

   ```
   # Linux, macOS:
   $ echo $ZEPHYR_TOOLCHAIN_VARIANT
   xtools
   ```
2.12.8 Host Toolchains

In some specific configurations, like when building for non-MCU x86 targets on a Linux host, you may be able to re-use the native development tools provided by your operating system.

To use your host gcc, set the ZEPHYR_TOOLCHAIN_VARIANT environment variable to host. To use clang, set ZEPHYR_TOOLCHAIN_VARIANT to llvm.

2.12.9 Other Cross Compilers

This toolchain variant is borrowed from the Linux kernel build system's mechanism of using a CROSS_COMPILE environment variable to set up a GNU-based cross toolchain.

Examples of such “other cross compilers” are cross toolchains that your Linux distribution packaged, that you compiled on your own, or that you downloaded from the net. Unlike toolchains specifically listed in Toolchains, the Zephyr build system may not have been tested with them, and doesn’t officially support them. (Nonetheless, the toolchain set-up mechanism itself is supported.)

Follow these steps to use one of these toolchains.

1. **Install a cross compiler suitable for your host and target systems.**

   For example, you might install the gcc-arm-none-eabi package on Debian-based Linux systems, or arm-none-eabi-newlib on Fedora or Red Hat:

   ```bash
   # On Debian or Ubuntu
   sudo apt-get install gcc-arm-none-eabi
   # On Fedora or Red Hat
   sudo dnf install arm-none-eabi-newlib
   ```

2. **Set these environment variables:**

   - Set ZEPHYR_TOOLCHAIN_VARIANT to cross-compile.
   - Set CROSS_COMPILE to the common path prefix which your toolchain's binaries have, e.g. the path to the directory containing the compiler binaries plus the target triplet and trailing dash.

3. To check that you have set these variables correctly in your current environment, follow these example shell sessions (the CROSS_COMPILE value may be different on your system):

   ```bash
   # Linux, macOS:
   $ echo $ZEPHYR_TOOLCHAIN_VARIANT
   cross-compile
   $ echo $CROSS_COMPILE
   /usr/bin/arm-none-eabi-
   ```

   You can also set CROSS_COMPILE as a CMake variable.

When using this option, all of your toolchain binaries must reside in the same directory and have a common file name prefix. The CROSS_COMPILE variable is set to the directory concatenated with the file name prefix. In the Debian example above, the gcc-arm-none-eabi package installs binaries such as arm-none-eabi-gcc and arm-none-eabi-ld in directory /usr/bin/, so the common prefix is /usr/bin/arm-none-eabi- (including the trailing dash, -). If your toolchain is installed in /opt/mytoolchain/bin with binary names based on target triplet myarch-none-elf, CROSS_COMPILE would be set to /opt/mytoolchain/bin/myarch-none-elf-.
2.12.10 Custom CMake Toolchains

To use a custom toolchain defined in an external CMake file, set these environment variables:

- Set ZEPHYR_TOOLCHAIN_VARIANT to your toolchain's name
- Set TOOLCHAIN_ROOT to the path to the directory containing your toolchain's CMake configuration files.

Zephyr will then include the toolchain cmake files located in the TOOLCHAIN_ROOT directory:

- cmake/toolchain/<toolchain name>/generic.cmake: configures the toolchain for "generic" use, which mostly means running the C preprocessor on the generated Devicetree file.
- cmake/toolchain/<toolchain name>/target.cmake: configures the toolchain for "target" use, i.e. building Zephyr and your application's source code.

Here <toolchain name> is the same as the name provided in ZEPHYR_TOOLCHAIN_VARIANT. See the zephyr files cmake/modules/FindHostTools.cmake and cmake/modules/FindTargetTools.cmake for more details on what your generic.cmake and target.cmake files should contain.

You can also set ZEPHYR_TOOLCHAIN_VARIANT and TOOLCHAIN_ROOT as CMake variables when generating a build system for a Zephyr application, like so:

```
west build ... -- -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=...
```

```
cmake -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=...
```

If you do this, -C <initial-cache> cmake option may useful. If you save your ZEPHYR_TOOLCHAIN_VARIANT, TOOLCHAIN_ROOT, and other settings in a file named my-toolchain.cmake, you can then invoke cmake as cmake -C my-toolchain.cmake ... to save typing.

Zephyr includes include/toolchain.h which again includes a toolchain specific header based on the compiler identifier, such as __llvm__ or __GNUC__. Some custom compilers identify themselves as the compiler on which they are based, for example llvm which then gets the toolchain/llvm.h included. This included file may though not be right for the custom toolchain. In order to solve this, and thus to get the include/other.h included instead, add the set(TOOLCHAIN_USE_CUSTOM 1) cmake line to the generic.cmake and/or target.cmake files located under <TOOLCHAIN_ROOT>/cmake/toolchain/<toolchain name>/.

When TOOLCHAIN_USE_CUSTOM is set, the other.h must be available out-of-tree and it must include the correct header for the custom toolchain. A good location for the other.h header file, would be a directory under the directory specified in TOOLCHAIN_ROOT as include/toolchain. To get the toolchain header included in zephyr's build, the USERINCLUDE can be set to point to the include directory, as shown here:

```
west build -- -DZEPHYR_TOOLCHAIN_VARIANT=... -DTOOLCHAIN_ROOT=... -DUSERINCLUDE=...
```

2.13 Tools and IDEs

2.13.1 Coccinelle

Coccinelle is a tool for pattern matching and text transformation that has many uses in kernel development, including the application of complex, tree-wide patches and detection of problematic programming patterns.

**Note:** Linux and macOS development environments are supported, but not Windows.
Getting Coccinelle

The semantic patches included in the kernel use features and options which are provided by Coccinelle version 1.0.0-rc11 and above. Using earlier versions will fail as the option names used by the Coccinelle files and `coccicheck` have been updated.

Coccinelle is available through the package manager of many distributions, e.g.:

- Debian
- Fedora
- Ubuntu
- OpenSUSE
- Arch Linux
- NetBSD
- FreeBSD

Some distribution packages are obsolete and it is recommended to use the latest version released from the Coccinelle homepage at http://coccinelle.lip6.fr/

Or from Github at:
https://github.com/coccinelle/coccinelle

Once you have it, run the following commands:

```
./autogen
./configure
make
```

as a regular user, and install it with:

```
sudo make install
```

More detailed installation instructions to build from source can be found at:

https://github.com/coccinelle/coccinelle/blob/master/install.txt

Supplemental documentation

For Semantic Patch Language (SmPL) grammar documentation refer to:

https://coccinelle.gitlabpages.inria.fr/website/documentation.html

Using Coccinelle on Zephyr

coccicheck checker is the front-end to the Coccinelle infrastructure and has various modes:

Four basic modes are defined: `patch`, `report`, `context`, and `org`. The mode to use is specified by setting `--mode=<mode>` or `-m=<mode>`.

- `patch` proposes a fix, when possible.
- `report` generates a list in the following format: `file:line:column-column: message`
- `context` highlights lines of interest and their context in a diff-like style. Lines of interest are indicated with `-`.
- `org` generates a report in the Org mode format of Emacs.
Note that not all semantic patches implement all modes. For easy use of Coccinelle, the default mode is `report`.

Two other modes provide some common combinations of these modes.

- `chain` tries the previous modes in the order above until one succeeds.
- `rep+ctxt` runs successively the report mode and the context mode. It should be used with the `C` option (described later) which checks the code on a file basis.

### Examples

To make a report for every semantic patch, run the following command:

```
./scripts/coccischeck --mode=report
```

To produce patches, run:

```
./scripts/coccischeck --mode=patch
```

The `coccischeck` target applies every semantic patch available in the sub-directories of `scripts/coccinelle` to the entire source code tree.

For each semantic patch, a commit message is proposed. It gives a description of the problem being checked by the semantic patch, and includes a reference to Coccinelle.

As any static code analyzer, Coccinelle produces false positives. Thus, reports must be carefully checked, and patches reviewed.

**To enable verbose messages set** `--verbose=1` option, for example:

```
./scripts/coccischeck --mode=report --verbose=1
```

### Coccinelle parallelization

By default, `coccischeck` tries to run as parallel as possible. To change the parallelism, set the `--jobs=<number>` option. For example, to run across 4 CPUs:

```
./scripts/coccischeck --mode=report --jobs=4
```

As of Coccinelle 1.0.2 Coccinelle uses Ocaml parmap for parallelization, if support for this is detected you will benefit from parmap parallelization.

When parmap is enabled `coccischeck` will enable dynamic load balancing by using `--chunksize 1` argument, this ensures we keep feeding threads with work one by one, so that we avoid the situation where most work gets done by only a few threads. With dynamic load balancing, if a thread finishes early we keep feeding it more work.

When parmap is enabled, if an error occurs in Coccinelle, this error value is propagated back, the return value of the `coccischeck` command captures this return value.

### Using Coccinelle with a single semantic patch

The option `--cocci` can be used to check a single semantic patch. In that case, the variable must be initialized with the name of the semantic patch to apply.

For instance:

```
./scripts/coccischeck --mode=report --cocci=<example.cocci>
```

or:
Controlling which files are processed by Coccinelle

By default the entire source tree is checked.

To apply Coccinelle to a specific directory, pass the path of specific directory as an argument.

For example, to check `drivers/usb/` one may write:

```
./scripts/coccicheck --mode=patch drivers/usb/
```

The report mode is the default. You can select another one with the `--mode=<mode>` option explained above.

Debugging Coccinelle SmPL patches

Using coccicheck is best as it provides in the spatch command line include options matching the options used when we compile the kernel. You can learn what these options are by using verbose option, you could then manually run Coccinelle with debug options added.

Alternatively you can debug running Coccinelle against SmPL patches by asking for stderr to be redirected to stderr, by default stderr is redirected to /dev/null, if you’d like to capture stderr you can specify the `--debug=file.err` option to coccicheck. For instance:

```
rm -f cocci.err
./scripts/coccicheck --mode=patch --debug=cocci.err
cat cocci.err
```

Debugging support is only supported when using Coccinelle >= 1.0.2.

Additional Flags

Additional flags can be passed to spatch through the SPFLAGS variable. This works as Coccinelle respects the last flags given to it when options are in conflict.

```
./scripts/coccicheck --sp-flag="--use-glimpse"
```

Coccinelle supports idutils as well but requires coccinelle >= 1.0.6. When no ID file is specified coccinelle assumes your ID database file is in the file .id-utils.index on the top level of the kernel, coccinelle carries a script scripts/idutils_index.sh which creates the database with:

```
mkid -i C --output .id-utils.index
```

If you have another database filename you can also just symlink with this name.

```
./scripts/coccicheck --sp-flag="--use-idutils"
```

Alternatively you can specify the database filename explicitly, for instance:

```
./scripts/coccicheck --sp-flag="--use-idutils /full-path/to/ID"
```

Sometimes coccinelle doesn’t recognize or parse complex macro variables due to insufficient definition. Therefore, to make it parsable we explicitly provide the prototype of the complex macro using the `--macro-file-builtins <headerfile.h>` flag.

The `<headerfile.h>` should contain the complete prototype of the complex macro from which spatch engine can extract the type information required during transformation.
For example:

`Z_SYSCALL_HANDLER` is not recognized by coccinelle. Therefore, we put its prototype in a header file, say for example `mymacros.h`.

```bash
$ cat mymacros.h
#define Z_SYSCALL_HANDLER int xxx
```

Now we pass the header file `mymacros.h` during transformation:

```bash
./scripts/coccicheck --sp-flag="---macro-file-builtins mymacros.h"
```

See `spatch --help` to learn more about spatch options.

Note that the `--use-glimpse` and `--use-idutils` options require external tools for indexing the code. None of them is thus active by default. However, by indexing the code with one of these tools, and according to the cocci file used, spatch could proceed the entire code base more quickly.

### SmPL patch specific options

SmPL patches can have their own requirements for options passed to Coccinelle. SmPL patch specific options can be provided by providing them at the top of the SmPL patch, for instance:

```bash
// Options: --no-includes --include-headers
```

### Proposing new semantic patches

New semantic patches can be proposed and submitted by kernel developers. For sake of clarity, they should be organized in the sub-directories of `scripts/coccinelle/`.

The cocci script should have the following properties:

- The script **must** have report mode.
- The first few lines should state the purpose of the script using /// comments. Usually, this message would be used as the commit log when proposing a patch based on the script.

**Example**

```bash
/// Use ARRAY_SIZE instead of dividing sizeof array with sizeof an element
```

- A more detailed information about the script with exceptional cases or false positives (if any) can be listed using //# comments.

**Example**

```bash
//# This makes an effort to find cases where ARRAY_SIZE can be used such as
//# where there is a division of sizeof the array by the sizeof its first
//# element or by any indexed element or the element type. It replaces the
//# division of the two sizeofs by ARRAY_SIZE.
```

- Confidence: It is a property defined to specify the accuracy level of the script. It can be either High, Moderate or Low depending upon the number of false positives observed.

**Example**

```bash
// Confidence: High
```

- Virtual rules: These are required to support the various modes framed in the script. The virtual rule specified in the script should have the corresponding mode handling rule.
Example

virtual context

@depends on context@
type T;
T[] E;
@@
( *
  (sizeof(E)/sizeof(*E))
  |
  (sizeof(E)/sizeof(E[...]))
  |
  (sizeof(E)/sizeof(T))
 )

Detailed description of the report mode

report generates a list in the following format:

file:line:column-column: message

Example  Running:

./scripts/coccicheck --mode=report --cocci=scripts/coccinelle/array_size.cocci

will execute the following part of the SmPL script:

<smpl>
@r depends on (org | report)@
type T;
T[] E;
position p;
@@
( (sizeof(E)@p /sizeof(*E))
  |
  (sizeof(E)@p /sizeof(E[...]))
  |
  (sizeof(E)@p /sizeof(T))
 )
@script:python depends on report@
p << r.p;
@@
msg="WARNING: Use ARRAY_SIZE"
coccilib.report.print_report(p[0], msg)
</smpl>

This SmPL excerpt generates entries on the standard output, as illustrated below:

ext/hal/nxp/mcux/drivers/lpc/fsl_wwdt.c:66:49-50: WARNING: Use ARRAY_SIZE
ext/hal/nxp/mcux/drivers/lpc/fsl_ctimer.c:74:53-54: WARNING: Use ARRAY_SIZE
ext/hal/nxp/mcux/drivers/imx/fsl_dcp.c:944:45-46: WARNING: Use ARRAY_SIZE
Detailed description of the **patch mode**

When the patch mode is available, it proposes a fix for each problem identified.

**Example** Running:

```
./scripts/coccicheck --mode=patch --cocci=scripts/coccinelle/misc/array_size.cocci
```

will execute the following part of the SmPL script:

```smpl
@depends on patch@

@type T;
T[] E;
@@

( - (sizeof(E)/sizeof(*E))
  + ARRAY_SIZE(E)
  |
  - (sizeof(E)/sizeof(E[...]))
  + ARRAY_SIZE(E)
  |
  - (sizeof(E)/sizeof(T))
  + ARRAY_SIZE(E)
 )

</smpl>
```

This SmPL excerpt generates patch hunks on the standard output, as illustrated below:

```
diff -u -p a/ext/lib/encoding/tinycbor/src/cborvalidation.c b/ext/lib/encoding/ ˓→tinycbor/src/cborvalidation.c
--- a/ext/lib/encoding/tinycbor/src/cborvalidation.c
+++ b/ext/lib/encoding/tinycbor/src/cborvalidation.c
@@ -325,7 +325,7 @@ static inline CborError validate_number(  static inline CborError validate_tag(CborValue *it, CborTag tag, int flags, int recursionLeft)
 {
   CborType type = cbor_value_get_type(it);
   - const size_t knownTagCount = sizeof(knownTagData) / sizeof(knownTagData[0]);
+   const size_t knownTagCount = ARRAY_SIZE(knownTagData);
   const struct KnownTagData *tagData = knownTagData;
   const struct KnownTagData * const knownTagDataEnd = knownTagData + knownTagCount;
```

**Detailed description of the **context mode**

context highlights lines of interest and their context in a diff-like style.

**Note:** The diff-like output generated is NOT an applicable patch. The intent of the context mode is to highlight the important lines (annotated with minus, -) and gives some surrounding context lines around. This output can be used with the diff mode of Emacs to review the code.

**Example** Running:
will execute the following part of the SmPL script:

```smpl
@depends on context@
type T;
T[] E;
@@
  (* (sizeof(E)/sizeof(*E))
   | * (sizeof(E)/sizeof(E[...]))
   | * (sizeof(E)/sizeof(T))
)
</smpl>
```

This SmPL excerpt generates diff hunks on the standard output, as illustrated below:

```
diff -u -p ext/lib/encoding/tinycbor/src/cborvalidation.c /tmp/nothing/ext/lib/
  encoding/tinycbor/src/cborvalidation.c
--- ext/lib/encoding/tinycbor/src/cborvalidation.c
+++ /tmp/nothing/ext/lib/encoding/tinycbor/src/cborvalidation.c
@@ -325,7 +325,6 @@ static inline CborError validate_number(
  static inline CborError validate_tag(CborValue *it, CborTag tag, int flags, int recursionLeft)
  {
    CborType type = cbor_value_get_type(it);
-   const size_t knownTagCount = sizeof(knownTagData) / sizeof(knownTagData[0]);
-   const struct KnownTagData *tagData = knownTagData;
-   const struct KnownTagData * const knownTagDataEnd = knownTagData + knownTagCount;
    ```

**Detailed description of the `org` mode**

`org` generates a report in the Org mode format of Emacs.

**Example**  Running:

```
./scripts/coccicide --mode=org --cocci=scripts/coccinelle/misc/array_size.cocci
```

will execute the following part of the SmPL script:

```smpl
@r depends on (org || report)@
type T;
T[] E;
positional p;
@@
  (@sizeof(E)%p /sizeof(*E))
  | (@sizeof(E)%p /sizeof(E[...]))
```

(continues on next page)
This SmPL excerpt generates Org entries on the standard output, as illustrated below:

```plaintext
* TODO [[view:ext/lib/encoding/tinycbor/src/cborvalidation.c::face=ovl-→face1::linb=328::colb=52::cole=53][WARNING should use ARRAY_SIZE]]
```

Coccinelle Mailing List

Subscribe to the coccinelle mailing list:

- [https://systeme.lip6.fr/mailman/listinfo/cocci](https://systeme.lip6.fr/mailman/listinfo/cocci)

Archives:

- [https://lore.kernel.org/cocci/](https://lore.kernel.org/cocci/)
- [https://systeme.lip6.fr/pipermail/cocci/](https://systeme.lip6.fr/pipermail/cocci/)

### 2.13.2 Using with PlatformIO

[PlatormIO logo]

- **What is PlatformIO?**
- **Installation**
- **Configuration**
- **Tutorials**
- **Project Examples**
- **Next Steps**

**What is PlatformIO?**

PlatformIO is a cross-platform embedded development environment with Zephyr support maintained by its developers.
Since Zephyr support within PlatformIO is not maintained by the Zephyr Project, please report any issues with PlatformIO directly to its developers in the official PlatformIO repositories.

A detailed overview of the PlatformIO ecosystem and its philosophy can be found in the official PlatformIO documentation.

Installation

- **PlatformIO IDE** is a toolset for embedded C/C++ development available on Windows, macOS and Linux platforms
- **PlatformIO Core (CLI)** is a command-line tool that consists of multi-platform build system, platform and library managers and other integration components. It can be used with a variety of code development environments and allows integration with cloud platforms and web services

Configuration

Please go through the official PlatformIO configuration guide for Zephyr project.

Tutorials

- Zephyr and Nordic nRF52-DK: debugging, unit testing, project analysis
- Developing Zephyr RTOS embedded applications on PlatformIO and simulating on Antmicro Renode

Project Examples

Please check the official examples for various development platforms

Next Steps

Here are some useful links for exploring the PlatformIO ecosystem:

- Try other platforms that support Zephyr project
- Learn more about integrations with other IDEs/Text Editors
- Get help from PlatformIO community
Chapter 3

Kernel

3.1 Kernel Services

The Zephyr kernel lies at the heart of every Zephyr application. It provides a low footprint, high performance, multi-threaded execution environment with a rich set of available features. The rest of the Zephyr ecosystem, including device drivers, networking stack, and application-specific code, uses the kernel’s features to create a complete application.

The configurable nature of the kernel allows you to incorporate only those features needed by your application, making it ideal for systems with limited amounts of memory (as little as 2 KB!) or with simple multi-threading requirements (such as a set of interrupt handlers and a single background task). Examples of such systems include: embedded sensor hubs, environmental sensors, simple LED wearable, and store inventory tags.

Applications requiring more memory (50 to 900 KB), multiple communication devices (like Wi-Fi and Bluetooth Low Energy), and complex multi-threading, can also be developed using the Zephyr kernel. Examples of such systems include: fitness wearables, smart watches, and IoT wireless gateways.

3.1.1 Scheduling, Interrupts, and Synchronization

These pages cover basic kernel services related to thread scheduling and synchronization.

 Threads

Note: There is also limited support for using Operation without Threads.

- Lifecycle
  - Thread Creation
  - Thread Termination
  - Thread Aborting
  - Thread Suspension
- Thread States
- Thread Stack objects
  - Kernel-only Stacks
This section describes kernel services for creating, scheduling, and deleting independently executable threads of instructions.

A thread is a kernel object that is used for application processing that is too lengthy or too complex to be performed by an ISR.

Any number of threads can be defined by an application (limited only by available RAM). Each thread is referenced by a thread id that is assigned when the thread is spawned.

A thread has the following key properties:

- A stack area, which is a region of memory used for the thread’s stack. The size of the stack area can be tailored to conform to the actual needs of the thread’s processing. Special macros exist to create and work with stack memory regions.
- A thread control block for private kernel bookkeeping of the thread’s metadata. This is an instance of type k_thread.
- An entry point function, which is invoked when the thread is started. Up to 3 argument values can be passed to this function.
- A scheduling priority, which instructs the kernel’s scheduler how to allocate CPU time to the thread. (See Scheduling.)
- A set of thread options, which allow the thread to receive special treatment by the kernel under specific circumstances. (See Thread Options.)
- A start delay, which specifies how long the kernel should wait before starting the thread.
- An execution mode, which can either be supervisor or user mode. By default, threads run in supervisor mode and allow access to privileged CPU instructions, the entire memory address space, and peripherals. User mode threads have a reduced set of privileges. This depends on the CONFIG_USERSPACE option. See User Mode.

Lifecycle

Thread Creation A thread must be created before it can be used. The kernel initializes the thread control block as well as one end of the stack portion. The remainder of the thread’s stack is typically left uninitialized.
Specifying a start delay of \texttt{K\_NO\_WAIT} instructs the kernel to start thread execution immediately. Alternatively, the kernel can be instructed to delay execution of the thread by specifying a timeout value – for example, to allow device hardware used by the thread to become available.

The kernel allows a delayed start to be canceled before the thread begins executing. A cancellation request has no effect if the thread has already started. A thread whose delayed start was successfully canceled must be re-spawned before it can be used.

**Thread Termination**  Once a thread is started it typically executes forever. However, a thread may synchronously end its execution by returning from its entry point function. This is known as \textbf{termination}.

A thread that terminates is responsible for releasing any shared resources it may own (such as mutexes and dynamically allocated memory) prior to returning, since the kernel does not reclaim them automatically.

In some cases a thread may want to sleep until another thread terminates. This can be accomplished with the \texttt{k\_thread\_join()} API. This will block the calling thread until either the timeout expires, the target thread self-exits, or the target thread aborts (either due to a \texttt{k\_thread\_abort()} call or triggering a fatal error).

Once a thread has terminated, the kernel guarantees that no use will be made of the thread struct. The memory of such a struct can then be re-used for any purpose, including spawning a new thread. Note that the thread must be fully terminated, which presents race conditions where a thread’s own logic signals completion which is seen by another thread before the kernel processing is complete. Under normal circumstances, application code should use \texttt{k\_thread\_join()} or \texttt{k\_thread\_abort()} to synchronize on thread termination state and not rely on signaling from within application logic.

**Thread Aborting**  A thread may asynchronously end its execution by \textbf{aborting}. The kernel automatically aborts a thread if the thread triggers a fatal error condition, such as dereferencing a null pointer.

A thread can also be aborted by another thread (or by itself) by calling \texttt{k\_thread\_abort()}. However, it is typically preferable to signal a thread to terminate itself gracefully, rather than aborting it.

As with thread termination, the kernel does not reclaim shared resources owned by an aborted thread.

**Note:** The kernel does not currently make any claims regarding an application’s ability to respawn a thread that aborts.

**Thread Suspension**  A thread can be prevented from executing for an indefinite period of time if it becomes \textbf{suspended}. The function \texttt{k\_thread\_suspend()} can be used to suspend any thread, including the calling thread. Suspending a thread that is already suspended has no additional effect.

Once suspended, a thread cannot be scheduled until another thread calls \texttt{k\_thread\_resume()} to remove the suspension.

**Note:** A thread can prevent itself from executing for a specified period of time using \texttt{k\_sleep()}. However, this is different from suspending a thread since a sleeping thread becomes executable automatically when the time limit is reached.

**Thread States**  A thread that has no factors that prevent its execution is deemed to be \textbf{ready}, and is eligible to be selected as the current thread.

A thread that has one or more factors that prevent its execution is deemed to be \textbf{unready}, and cannot be selected as the current thread.

The following factors make a thread unready:
• The thread has not been started.
• The thread is waiting for a kernel object to complete an operation. (For example, the thread is taking a semaphore that is unavailable.)
• The thread is waiting for a timeout to occur.
• The thread has been suspended.
• The thread has terminated or aborted.

Note: Although the diagram above may appear to suggest that both Ready and Running are distinct thread states, that is not the correct interpretation. Ready is a thread state, and Running is a schedule state that only applies to Ready threads.

Thread Stack objects Every thread requires its own stack buffer for the CPU to push context. Depending on configuration, there are several constraints that must be met:

• There may need to be additional memory reserved for memory management structures
• If guard-based stack overflow detection is enabled, a small write-protected memory management region must immediately precede the stack buffer to catch overflows.
• If userspace is enabled, a separate fixed-size privilege elevation stack must be reserved to serve as a private kernel stack for handling system calls.
• If userspace is enabled, the thread’s stack buffer must be appropriately sized and aligned such that a memory protection region may be programmed to exactly fit.

The alignment constraints can be quite restrictive, for example some MPUs require their regions to be of some power of two in size, and aligned to its own size.

Because of this, portable code can’t simply pass an arbitrary character buffer to k_thread_create(). Special macros exist to instantiate stacks, prefixed with K_KERNEL_STACK and K_THREAD_STACK.

Kernel-only Stacks If it is known that a thread will never run in user mode, or the stack is being used for special contexts like handling interrupts, it is best to define stacks using the K_KERNEL_STACK macros.
These stacks save memory because an MPU region will never need to be programmed to cover the stack buffer itself, and the kernel will not need to reserve additional room for the privilege elevation stack, or memory management data structures which only pertain to user mode threads.

Attempts from user mode to use stacks declared in this way will result in a fatal error for the caller.

If CONFIG_USERSPACE is not enabled, the set of K_THREAD_STACK macros have an identical effect to the K_KERNEL_STACK macros.

Thread stacks If it is known that a stack will need to host user threads, or if this cannot be determined, define the stack with K_THREAD_STACK macros. This may use more memory but the stack object is suitable for hosting user threads.

If CONFIG_USERSPACE is not enabled, the set of K_THREAD_STACK macros have an identical effect to the K_KERNEL_STACK macros.

Thread Priorities A thread’s priority is an integer value, and can be either negative or non-negative. Numerically lower priorities takes precedence over numerically higher values. For example, the scheduler gives thread A of priority 4 higher priority over thread B of priority 7; likewise thread C of priority -2 has higher priority than both thread A and thread B.

The scheduler distinguishes between two classes of threads, based on each thread’s priority.

- A cooperative thread has a negative priority value. Once it becomes the current thread, a cooperative thread remains the current thread until it performs an action that makes it unready.
- A preemptible thread has a non-negative priority value. Once it becomes the current thread, a preemptible thread may be supplanted at any time if a cooperative thread, or a preemptible thread of higher or equal priority, becomes ready.

A thread’s initial priority value can be altered up or down after the thread has been started. Thus it is possible for a preemptible thread to become a cooperative thread, and vice versa, by changing its priority.

Note: The scheduler does not make heuristic decisions to re-prioritize threads. Thread priorities are set and changed only at the application’s request.

The kernel supports a virtually unlimited number of thread priority levels. The configuration options CONFIG_NUM_COOP_PRIORITIES and CONFIG_NUM_PREEMPT_PRIORITIES specify the number of priority levels for each class of thread, resulting in the following usable priority ranges:

- cooperative threads: (-CONFIG_NUM_COOP_PRIORITIES) to -1
- preemptive threads: 0 to (CONFIG_NUM_PREEMPT_PRIORITIES - 1)

For example, configuring 5 cooperative priorities and 10 preemptive priorities results in the ranges -5 to -1 and 0 to 9, respectively.

3.1. Kernel Services
Meta-IRQ Priorities When enabled (see `CONFIG_NUM_METAIRQ_PRIORITIES`), there is a special subclass of cooperative priorities at the highest (numerically lowest) end of the priority space: meta-IRQ threads. These are scheduled according to their normal priority, but also have the special ability to preempt all other threads (and other meta-IRQ threads) at lower priorities, even if those threads are cooperative and/or have taken a scheduler lock. Meta-IRQ threads are still threads, however, and can still be interrupted by any hardware interrupt.

This behavior makes the act of unblocking a meta-IRQ thread (by any means, e.g. creating it, calling `k_sem_give()`, etc.) into the equivalent of a synchronous system call when done by a lower priority thread, or an ARM-like “pended IRQ” when done from true interrupt context. The intent is that this feature will be used to implement interrupt “bottom half” processing and/or “tasklet” features in driver subsystems. The thread, once woken, will be guaranteed to run before the current CPU returns into application code.

Unlike similar features in other OSes, meta-IRQ threads are true threads and run on their own stack (which must be allocated normally), not the per-CPU interrupt stack. Design work to enable the use of the IRQ stack on supported architectures is pending.

Note that because this breaks the promise made to cooperative threads by the Zephyr API (namely that the OS won’t schedule other thread until the current thread deliberately blocks), it should be used only with great care from application code. These are not simply very high priority threads and should not be used as such.

Thread Options The kernel supports a small set of thread options that allow a thread to receive special treatment under specific circumstances. The set of options associated with a thread are specified when the thread is spawned.

A thread that does not require any thread option has an option value of zero. A thread that requires a thread option specifies it by name, using the `|` character as a separator if multiple options are needed (i.e. combine options using the bitwise OR operator).

The following thread options are supported.

**K_ESSENTIAL**
This option tags the thread as an essential thread. This instructs the kernel to treat the termination or aborting of the thread as a fatal system error.

By default, the thread is not considered to be an essential thread.

**K_SSE_REGS**
This x86-specific option indicate that the thread uses the CPU’s SSE registers. Also see K_FP_REGS.

By default, the kernel does not attempt to save and restore the contents of these registers when scheduling the thread.

**K_FP_REGS**
This option indicate that the thread uses the CPU’s floating point registers. This instructs the kernel to take additional steps to save and restore the contents of these registers when scheduling the thread. (For more information see Floating Point Services.)

By default, the kernel does not attempt to save and restore the contents of this register when scheduling the thread.

**K_USER**
If `CONFIG_USERSPACE` is enabled, this thread will be created in user mode and will have reduced privileges. See User Mode. Otherwise this flag does nothing.

**K_INHERIT_PERMS**
If `CONFIG_USERSPACE` is enabled, this thread will inherit all kernel object permissions that the parent thread had, except the parent thread object. See User Mode.
Thread Custom Data  Every thread has a 32-bit custom data area, accessible only by the thread itself, and may be used by the application for any purpose it chooses. The default custom data value for a thread is zero.

Note: Custom data support is not available to ISRs because they operate within a single shared kernel interrupt handling context.

By default, thread custom data support is disabled. The configuration option CONFIG_THREAD_CUSTOM_DATA can be used to enable support.

The k_thread_custom_data_set() and k_thread_custom_data_get() functions are used to write and read a thread’s custom data, respectively. A thread can only access its own custom data, and not that of another thread.

The following code uses the custom data feature to record the number of times each thread calls a specific routine.

Note: Obviously, only a single routine can use this technique, since it monopolizes the use of the custom data feature.

```c
int call_tracking_routine(void)
{
    uint32_t call_count;

    if (k_is_in_isr()) {
        /* ignore any call made by an ISR */
    } else {
        call_count = (uint32_t)k_thread_custom_data_get();
        call_count++;
        k_thread_custom_data_set((void *)call_count);
    }

    /* do rest of routine's processing */
    ...
}
```

Use thread custom data to allow a routine to access thread-specific information, by using the custom data as a pointer to a data structure owned by the thread.

Implementation

Spawning a Thread  A thread is spawned by defining its stack area and its thread control block, and then calling k_thread_create().

The stack area must be defined using K_THREAD_STACK_DEFINE or K_KERNEL_STACK_DEFINE to ensure it is properly set up in memory.

The size parameter for the stack must be one of three values:

- The original requested stack size passed to K_THREAD_STACK or K_KERNEL_STACK family of stack instantiation macros.
- For a stack object defined with the K_THREAD_STACK family of macros, the return value of K_THREAD_STACK_SIZEOF() for that object.
- For a stack object defined with the K_KERNEL_STACK family of macros, the return value of K_KERNEL_STACK_SIZEOF() for that object.
The thread spawning function returns its thread id, which can be used to reference the thread. The following code spawns a thread that starts immediately.

```c
#define MY_STACK_SIZE 500
#define MY_PRIORITY 5

extern void my_entry_point(void *, void *, void *);

K_THREAD_STACK_DEFINE(my_stack_area, MY_STACK_SIZE);
struct k_thread my_thread_data;

k_tid_t my_tid = k_thread_create(&my_thread_data, my_stack_area, K_THREAD_STACK_SIZEOF(my_stack_area), my_entry_point, NULL, NULL, NULL, MY_PRIORITY, 0, K_NO_WAIT);
```

Alternatively, a thread can be declared at compile time by calling `K_THREAD_DEFINE`. Observe that the macro defines the stack area, control block, and thread id variables automatically. The following code has the same effect as the code segment above.

```c
#define MY_STACK_SIZE 500
#define MY_PRIORITY 5

extern void my_entry_point(void *, void *, void *);

K_THREAD_DEFINE(my_tid, MY_STACK_SIZE, my_entry_point, NULL, NULL, NULL, MY_PRIORITY, 0, 0);
```

**Note:** The delay parameter to `k_thread_create()` is a `k_timeout_t` value, so `K_NO_WAIT` means to start the thread immediately. The corresponding parameter to `K_THREAD_DEFINE` is a duration in integral milliseconds, so the equivalent argument is 0.

**User Mode Constraints** This section only applies if `CONFIG_USERSPACE` is enabled, and a user thread tries to create a new thread. The `k_thread_create()` API is still used, but there are additional constraints which must be met or the calling thread will be terminated:

- The calling thread must have permissions granted on both the child thread and stack parameters; both are tracked by the kernel as kernel objects.
- The child thread and stack objects must be in an uninitialized state, i.e. it is not currently running and the stack memory is unused.
- The stack size parameter passed in must be equal to or less than the bounds of the stack object when it was declared.
- The `K_USER` option must be used, as user threads can only create other user threads.
- The `K_ESSENTIAL` option must not be used, user threads may not be considered essential threads.
- The priority of the child thread must be a valid priority value, and equal to or lower than the parent thread.

**Dropping Permissions** If `CONFIG_USERSPACE` is enabled, a thread running in supervisor mode may perform a one-way transition to user mode using the `k_thread_user_mode_enter()` API. This is a one-
way operation which will reset and zero the thread’s stack memory. The thread will be marked as non-essential.

**Terminating a Thread** A thread terminates itself by returning from its entry point function. The following code illustrates the ways a thread can terminate.

```c
void my_entry_point(int unused1, int unused2, int unused3)
{
    while (1) {
        ... 
        if (<some condition>) {
            return; /* thread terminates from mid-entry point function */
        }
        ...
    }
    /* thread terminates at end of entry point function */
}
```

If `CONFIG_USERSPACE` is enabled, aborting a thread will additionally mark the thread and stack objects as uninitialized so that they may be re-used.

**Runtime Statistics** Thread runtime statistics can be gathered and retrieved if `CONFIG_THREAD_RUNTIME_STATS` is enabled, for example, total number of execution cycles of a thread.

By default, the runtime statistics are gathered using the default kernel timer. For some architectures, SoCs or boards, there are timers with higher resolution available via timing functions. Using of these timers can be enabled via `CONFIG_THREAD_RUNTIME_STATS_USE_TIMING_FUNCTIONS`.

Here is an example:

```c
k_thread_runtime_stats_t rt_stats_thread;

k_thread_runtime_stats_get(k_current_get(), &rt_stats_thread);

printk("Cycles:  %llu\n", rt_stats_thread.execution_cycles);
```

**Suggested Uses** Use threads to handle processing that cannot be handled in an ISR. Use separate threads to handle logically distinct processing operations that can execute in parallel.

**Configuration Options** Related configuration options:

- `CONFIG_MAIN_THREAD_PRIORITY`
- `CONFIG_MAIN_STACK_SIZE`
- `CONFIG_IDLE_STACK_SIZE`
- `CONFIG_THREAD_CUSTOM_DATA`
- `CONFIG_NUM_COOP_PRIORITIES`
- `CONFIG_NUM_PREEMPT_PRIORITIES`
- `CONFIG_TIMESLICING`
- `CONFIG_TIMESLICE_SIZE`
• CONFIG_TIMESLICE_PRIORITY
• CONFIG_USERSPACE

API Reference
group thread_apis

Defines

K_ESSENTIAL
    system thread that must not abort

K_FP_REGS
    FPU registers are managed by context switch.
    This option indicates that the thread uses the CPU’s floating point registers. This instructs
    the kernel to take additional steps to save and restore the contents of these registers when
    scheduling the thread. No effect if CONFIG_FPU_SHARING is not enabled.

K_USER
    user mode thread
    This thread has dropped from supervisor mode to user mode and consequently has additional
    restrictions

K_INHERIT_PERMS
    Inherit Permissions.
    Indicates that the thread being created should inherit all kernel object permissions from the
    thread that created it. No effect if CONFIG_USERSPACE is not enabled.

K_CALLBACK_STATE
    Callback item state.
    This is a single bit of state reserved for “callback manager” utilities (p4wq initially) who need
    to track operations invoked from within a user-provided callback they have been invoked.
    Effectively it serves as a tiny bit of zero-overhead TLS data.

k_thread_access_grant(thread, ...)
    Grant a thread access to a set of kernel objects.
    This is a convenience function. For the provided thread, grant access to the remaining argu-
    ments, which must be pointers to kernel objects.
    The thread object must be initialized (i.e. running). The objects don’t need to be. Note that
    NULL shouldn’t be passed as an argument.

Parameters

    • thread – Thread to grant access to objects
    • ... – list of kernel object pointers

K_THREAD_DEFINE(name, stack_size, entry, p1, p2, p3, prio, options, delay)
    Statically define and initialize a thread.
    The thread may be scheduled for immediate execution or a delayed start.
Thread options are architecture-specific, and can include K_ESSENTIAL, K_FP_REGS, and K_SSE_REGS. Multiple options may be specified by separating them using “|” (the logical OR operator).

The ID of the thread can be accessed using:

```c
extern const k_tid_t <name>;
```

**Parameters**

- **name** – Name of the thread.
- **stack_size** – Stack size in bytes.
- **entry** – Thread entry function.
- **p1** – 1st entry point parameter.
- **p2** – 2nd entry point parameter.
- **p3** – 3rd entry point parameter.
- **prio** – Thread priority.
- **options** – Thread options.
- **delay** – Scheduling delay (in milliseconds), zero for no delay.

**Typedefs**

```c
typedef void (*k_thread_user_cb_t)(const struct k_thread *thread, void *user_data)
```

**Functions**

```c
void k_thread_foreach(k_thread_user_cb_t user_cb, void *user_data)
```

Iterate over all the threads in the system.

This routine iterates over all the threads in the system and calls the user_cb function for each thread.

**Note:** CONFIG_THREAD_MONITOR must be set for this function to be effective.

**Note:** This API uses `k_spin_lock` to protect the _kernel.threads list which means creation of new threads and terminations of existing threads are blocked until this API returns.

**Parameters**

- **user_cb** – Pointer to the user callback function.
- **user_data** – Pointer to user data.

```c
void k_thread_foreach_unlocked(k_thread_user_cb_t user_cb, void *user_data)
```

Iterate over all the threads in the system without locking.

This routine works exactly the same like `k_thread_foreach` but unlocks interrupts when `user_cb` is executed.
Note: **CONFIG_THREAD_MONITOR** must be set for this function to be effective.

Note: This API uses *k_spin_lock* only when accessing the _kernel.threads queue elements. It unlocks it during user callback function processing. If a new task is created when this **foreach** function is in progress, the added new task would not be included in the enumeration. If a task is aborted during this enumeration, there would be a race here and there is a possibility that this aborted task would be included in the enumeration.

Note: If the task is aborted and the memory occupied by its *k_thread* structure is reused when this **k_thread_foreach_unlocked** is in progress it might even lead to the system behave unstable. This function may never return, as it would follow some **next** task pointers treating given pointer as a pointer to the **k_thread** structure while it is something different right now. Do not reuse the memory that was occupied by *k_thread* structure of aborted task if it was aborted after this function was called in any context.

### Parameters
- **user_cb** – Pointer to the user callback function.
- **user_data** – Pointer to user data.

```c
k_tid_t k_thread_create(struct k_thread *new_thread, k_thread_stack_t *stack, size_t stack_size, k_thread_entry_t entry, void *p1, void *p2, void *p3, int prio, uint32_t options, k_timeout_t delay)
```

Create a thread.

This routine initializes a thread, then schedules it for execution.

The new thread may be scheduled for immediate execution or a delayed start. If the newly spawned thread does not have a delayed start the kernel scheduler may preempt the current thread to allow the new thread to execute.

Thread options are architecture-specific, and can include K_ESSENTIAL, K_FP_REGS, and K_SSE_REGS. Multiple options may be specified by separating them using “|” (the logical OR operator).

Stack objects passed to this function must be originally defined with either of these macros in order to be portable:

- **K_THREAD_STACK_DEFINE()** - For stacks that may support either user or supervisor threads.
- **K_KERNEL_STACK_DEFINE()** - For stacks that may support supervisor threads only. These stacks use less memory if **CONFIG_USERSPACE** is enabled.

The stack_size parameter has constraints. It must either be:

- The original size value passed to **K_THREAD_STACK_DEFINE()** or **K_KERNEL_STACK_DEFINE()**
- The return value of **K_THREAD_STACK_SIZEOF(stack)** if the stack was defined with **K_THREAD_STACK_DEFINE()**
- The return value of **K_KERNEL_STACK_SIZEOF(stack)** if the stack was defined with **K_KERNEL_STACK_DEFINE()**.
Using other values, or `sizeof(stack)` may produce undefined behavior.

**Parameters**
- `new_thread` – Pointer to uninitialized struct `k_thread`
- `stack` – Pointer to the stack space.
- `stack_size` – Stack size in bytes.
- `entry` – Thread entry function.
- `p1` – 1st entry point parameter.
- `p2` – 2nd entry point parameter.
- `p3` – 3rd entry point parameter.
- `prio` – Thread priority.
- `options` – Thread options.
- `delay` – Scheduling delay, or `K_NO_WAIT` (for no delay).

**Returns**
ID of new thread.

```c
FUNC_NORETURN void k_thread_user_mode_enter(k_thread_entry_t entry, void *p1, void *p2, void *p3)
```

Drop a thread’s privileges permanently to user mode.

This allows a supervisor thread to be re-used as a user thread. This function does not return, but control will transfer to the provided entry point as if this was a new user thread.

The implementation ensures that the stack buffer contents are erased. Any thread-local storage will be reverted to a pristine state.

Memory domain membership, resource pool assignment, kernel object permissions, priority, and thread options are preserved.

A common use of this function is to re-use the main thread as a user thread once all supervisor mode-only tasks have been completed.

**Parameters**
- `entry` – Function to start executing from
- `p1` – 1st entry point parameter
- `p2` – 2nd entry point parameter
- `p3` – 3rd entry point parameter

```c
static inline void k_thread_heap_assign(struct k_thread *thread, struct k_heap *heap)
```

Assign a resource memory pool to a thread.

By default, threads have no resource pool assigned unless their parent thread has a resource pool, in which case it is inherited. Multiple threads may be assigned to the same memory pool.

Changing a thread’s resource pool will not migrate allocations from the previous pool.

**Parameters**
- `thread` – Target thread to assign a memory pool for resource requests.
- `heap` – Heap object to use for resources, or NULL if the thread should no longer have a memory pool.
void k_thread_system_pool_assign(struct k_thread *thread)
    Assign the system heap as a thread’s resource pool.
    Similar to z_thread_heap_assign(), but the thread will use the kernel heap to draw memory.
    Use with caution, as a malicious thread could perform DoS attacks on the kernel heap.

Parameters
    • thread – Target thread to assign the system heap for resource requests

int k_thread_join(struct k_thread *thread, k_timeout_t timeout)
    Sleep until a thread exits.
    The caller will be put to sleep until the target thread exits, either due to being aborted, self-exiting, or taking a fatal error. This API returns immediately if the thread isn’t running.
    This API may only be called from ISRs with a K_NO_WAIT timeout, where it can be useful as a predicate to detect when a thread has aborted.

Parameters
    • thread – Thread to wait to exit
    • timeout – upper bound time to wait for the thread to exit.

Return values
    • 0 – success, target thread has exited or wasn’t running
    • -EBUSY – returned without waiting
    • -EAGAIN – waiting period timed out
    • -EDEADLK – target thread is joining on the caller, or target thread is the caller

int32_t k_sleep(k_timeout_t timeout)
    Put the current thread to sleep.
    This routine puts the current thread to sleep for duration, specified as a k_timeout_t object.

Note: if timeout is set to K_FOREVER then the thread is suspended.

Parameters
    • timeout – Desired duration of sleep.

Returns
    Zero if the requested time has elapsed or the number of milliseconds left to sleep, if thread was woken up by k_wakeup call.

static inline int32_t k_msleep(int32_t ms)
    Put the current thread to sleep.
    This routine puts the current thread to sleep for duration milliseconds.

Parameters
    • ms – Number of milliseconds to sleep.

Returns
    Zero if the requested time has elapsed or the number of milliseconds left to sleep, if thread was woken up by k_wakeup call.
int32_t k_usleep(int32_t us)

Put the current thread to sleep with microsecond resolution.

This function is unlikely to work as expected without kernel tuning. In particular, because the lower bound on the duration of a sleep is the duration of a tick, CONFIG_SYS_CLOCK_TICKS_PER_SEC must be adjusted to achieve the resolution desired. The implications of doing this must be understood before attempting to use k_usleep(). Use with caution.

Parameters

- us – Number of microseconds to sleep.

Returns

Zero if the requested time has elapsed or the number of microseconds left to sleep, if thread was woken up by k_wakeup call.

void k_busy_wait(uint32_t usec_to_wait)

Cause the current thread to busy wait.

This routine causes the current thread to execute a “do nothing” loop for usec_to_wait microseconds.

Note: The clock used for the microsecond-resolution delay here may be skewed relative to the clock used for system timeouts like k_sleep(). For example k_busy_wait(1000) may take slightly more or less time than k_sleep(K_MSEC(1)), with the offset dependent on clock tolerances.

bool k_can_yield(void)

Check whether it is possible to yield in the current context.

This routine checks whether the kernel is in a state where it is possible to yield or call blocking APIs. It should be used by code that needs to yield to perform correctly, but can feasibly be called from contexts where that is not possible. For example in the PRE_KERNEL initialization step, or when being run from the idle thread.

Returns

True if it is possible to yield in the current context, false otherwise.

void k_yield(void)

Yield the current thread.

This routine causes the current thread to yield execution to another thread of the same or higher priority. If there are no other ready threads of the same or higher priority, the routine returns immediately.

void k_wakeup(k_tid_t thread)

Wake up a sleeping thread.

This routine prematurely wakes up thread from sleeping.

If thread is not currently sleeping, the routine has no effect.

Parameters

- thread – ID of thread to wake.

__attribute_const__ static inline k_tid_t k_current_get(void)

Get thread ID of the current thread.

Returns

ID of current thread.
void k_thread_abort(k_tid_t thread)
Abort a thread.

This routine permanently stops execution of thread. The thread is taken off all kernel queues it is part of (i.e. the ready queue, the timeout queue, or a kernel object wait queue). However, any kernel resources the thread might currently own (such as mutexes or memory blocks) are not released. It is the responsibility of the caller of this routine to ensure all necessary cleanup is performed.

After k_thread_abort() returns, the thread is guaranteed not to be running or to become runnable anywhere on the system. Normally this is done via blocking the caller (in the same manner as k_thread_join()), but in interrupt context on SMP systems the implementation is required to spin for threads that are running on other CPUs. Note that as specified, this means that on SMP platforms it is possible for application code to create a deadlock condition by simultaneously aborting a cycle of threads using at least one termination from interrupt context. Zephyr cannot detect all such conditions.

Parameters
• thread – ID of thread to abort.

void k_thread_start(k_tid_t thread)
Start an inactive thread.

If a thread was created with K_FOREVER in the delay parameter, it will not be added to the scheduling queue until this function is called on it.

Parameters
• thread – thread to start

k_ticks_t k_thread_timeout_expires_ticks(const struct k_thread *t)
Get time when a thread wakes up, in system ticks.

This routine computes the system uptime when a waiting thread next executes, in units of system ticks. If the thread is not waiting, it returns current system time.

k_ticks_t k_thread_timeout_remaining_ticks(const struct k_thread *t)
Get time remaining before a thread wakes up, in system ticks.

This routine computes the time remaining before a waiting thread next executes, in units of system ticks. If the thread is not waiting, it returns zero.

int k_thread_priority_get(k_tid_t thread)
Get a thread's priority.

This routine gets the priority of thread.

Parameters
• thread – ID of thread whose priority is needed.

Returns
Priority of thread.

void k_thread_priority_set(k_tid_t thread, int prio)
Set a thread's priority.

This routine immediately changes the priority of thread.

Rescheduling can occur immediately depending on the priority thread is set to:

• If its priority is raised above the priority of the caller of this function, and the caller is preemptible, thread will be scheduled in.
• If the caller operates on itself, it lowers its priority below that of other threads in the system, and the caller is preemptible, the thread of highest priority will be scheduled in.

Priority can be assigned in the range of -CONFIG_NUM_COOP_PRIORITIES to CONFIG_NUM_PREEMPT_PRIORITIES-1, where -CONFIG_NUM_COOP_PRIORITIES is the highest priority.

Warning: Changing the priority of a thread currently involved in mutex priority inheritance may result in undefined behavior.

Parameters

• thread – ID of thread whose priority is to be set.
• prio – New priority.

void k_thread_deadline_set(k_tid_t thread, int deadline)
Set deadline expiration time for scheduler.

This sets the “deadline” expiration as a time delta from the current time, in the same units used by k_cycle_get_32(). The scheduler (when deadline scheduling is enabled) will choose the next expiring thread when selecting between threads at the same static priority. Threads at different priorities will be scheduled according to their static priority.

Note: Deadlines are stored internally using 32 bit unsigned integers. The number of cycles between the “first” deadline in the scheduler queue and the “last” deadline must be less than 2^31 (i.e a signed non-negative quantity). Failure to adhere to this rule may result in scheduled threads running in an incorrect deadline order.

Note: Despite the API naming, the scheduler makes no guarantees the the thread WILL be scheduled within that deadline, nor does it take extra metadata (like e.g. the “runtime” and “period” parameters in Linux sched_setattr()) that allows the kernel to validate the scheduling for achievability. Such features could be implemented above this call, which is simply input to the priority selection logic.

Note: You should enable CONFIG_SCHED_DEADLINE in your project configuration.

Parameters

• thread – A thread on which to set the deadline
• deadline – A time delta, in cycle units

int k_thread_cpu_mask_clear(k_tid_t thread)
Sets all CPU enable masks to zero.

After this returns, the thread will no longer be schedulable on any CPUs. The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters

• thread – Thread to operate upon
Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_enable_all(k_tid_t thread)
Sets all CPU enable masks to one.
After this returns, the thread will be schedulable on any CPU. The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
• thread – Thread to operate upon

Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_enable(k_tid_t thread, int cpu)
Enable thread to run on specified CPU.
The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
• thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

int k_thread_cpu_mask_disable(k_tid_t thread, int cpu)
Prevent thread to run on specified CPU.
The thread must not be currently runnable.

Note: You should enable CONFIG_SCHED_CPU_MASK in your project configuration.

Parameters
• thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

int k_thread_cpu_pin(k_tid_t thread, int cpu)
Pin a thread to a CPU.
Pin a thread to a CPU by first clearing the cpu mask and then enabling the thread on the selected CPU.

Parameters
• thread – Thread to operate upon
• cpu – CPU index

Returns
Zero on success, otherwise error code

```c
void k_thread_suspend(k_tid_t thread)
```
Suspend a thread.

This routine prevents the kernel scheduler from making `thread` the current thread. All other
internal operations on `thread` are still performed; for example, kernel objects it is waiting on
are still handed to it. Note that any existing timeouts (e.g. `k_sleep()`, or a timeout argument to
`k_sem_take()` et. al.) will be canceled. On resume, the thread will begin running immediately
and return from the blocked call.

If `thread` is already suspended, the routine has no effect.

Parameters
• thread – ID of thread to suspend.

```c
void k_thread_resume(k_tid_t thread)
```
Resume a suspended thread.

This routine allows the kernel scheduler to make `thread` the current thread, when it is next
eligible for that role.

If `thread` is not currently suspended, the routine has no effect.

Parameters
• thread – ID of thread to resume.

```c
void k_sched_time_slice_set(int32_t slice, int prio)
```
Set time-slicing period and scope.

This routine specifies how the scheduler will perform time slicing of preemptible threads.
To enable time slicing, `slice` must be non-zero. The scheduler ensures that no thread runs for
more than the specified time limit before other threads of that priority are given a chance to
execute. Any thread whose priority is higher than `prio` is exempted, and may execute as long
as desired without being preempted due to time slicing.

Time slicing only limits the maximum amount of time a thread may continuously execute.
Once the scheduler selects a thread for execution, there is no minimum guaranteed time the
thread will execute before threads of greater or equal priority are scheduled.

When the current thread is the only one of that priority eligible for execution, this routine has
no effect; the thread is immediately rescheduled after the slice period expires.

To disable timeslicing, set both `slice` and `prio` to zero.

Parameters
• slice – Maximum time slice length (in milliseconds).
• prio – Highest thread priority level eligible for time slicing.

```c
void k_thread_time_slice_set(struct k_thread *th, int32_t slice_ticks, k_thread_timeslice_fn_t expired, void *data)
```
Set thread time slice.

As for `k_sched_time_slice_set`, but (when `CONFIG_TIMESLICE_PER_THREAD=y`) sets the
timeslice for a specific thread. When non-zero, this timeslice will take precedence over the
global value.

When such a thread's timeslice expires, the configured callback will be called before the thread
is removed/re-added to the run queue. This callback will occur in interrupt context, and the
specified thread is guaranteed to have been preempted by the currently-executing ISR. Such
a callback is free to, for example, modify the thread priority or slice time for future execution, suspend the thread, etc.

**Note:** Unlike the older API, the time slice parameter here is specified in ticks, not milliseconds. Ticks have always been the internal unit, and not all platforms have integer conversions between the two.

**Note:** Threads with a non-zero slice time set will be timesliced always, even if they are higher priority than the maximum timeslice priority set via `k_sched_time_slice_set()`.

**Note:** The callback notification for slice expiration happens, as it must, while the thread is still “current”, and thus it happens before any registered timeouts at this tick. This has the somewhat confusing side effect that the tick time (c.f. `k_uptime_get()`) does not yet reflect the expired ticks. Applications wishing to make fine-grained timing decisions within this callback should use the cycle API, or derived facilities like `k_thread_runtime_stats_get()`.

**Parameters**

- `th` – A valid, initialized thread
- `slice_ticks` – Maximum timeslice, in ticks
- `expired` – Callback function called on slice expiration
- `data` – Parameter for the expiration handler

```c
void k_sched_lock(void)
Lock the scheduler.
This routine prevents the current thread from being preempted by another thread by instructing the scheduler to treat it as a cooperative thread. If the thread subsequently performs an operation that makes it unready, it will be context switched out in the normal manner. When the thread again becomes the current thread, its non-preemptible status is maintained.
This routine can be called recursively.

**Note:** `k_sched_lock()` and `k_sched_unlock()` should normally be used when the operation being performed can be safely interrupted by ISRs. However, if the amount of processing involved is very small, better performance may be obtained by using `irq_lock()` and `irq_unlock()`.

```c
void k_sched_unlock(void)
Unlock the scheduler.
This routine reverses the effect of a previous call to `k_sched_lock()`. A thread must call the routine once for each time it called `k_sched_lock()` before the thread becomes preemptible.
```

```c
void k_thread_custom_data_set(void *value)
Set current thread’s custom data.
This routine sets the custom data for the current thread to @value.
Custom data is not used by the kernel itself, and is freely available for a thread to use as it sees fit. It can be used as a framework upon which to build thread-local storage.

**Parameters**

- `value` – New custom data value.
```
void *k_thread_custom_data_get(void)
Get current thread’s custom data.
This routine returns the custom data for the current thread.

**Returns**
Current custom data value.

int k_thread_name_set(k_tid_t thread, const char *str)
Set current thread name.
Set the name of the thread to be used when CONFIG_THREAD_MONITOR is enabled for tracing and debugging.

**Parameters**
- `thread` – Thread to set name, or NULL to set the current thread
- `str` – Name string

**Return values**
- 0 – on success
- -EFAULT – Memory access error with supplied string
- -ENOSYS – Thread name configuration option not enabled
- -EINVAL – Thread name too long

const char *k_thread_name_get(k_tid_t thread)
Get thread name.
Get the name of a thread

**Parameters**
- `thread` – Thread ID

**Return values**
- Thread name, or NULL if configuration not enabled

int k_thread_name_copy(k_tid_t thread, char *buf, size_t size)
Copy the thread name into a supplied buffer.

**Parameters**
- `thread` – Thread to obtain name information
- `buf` – Destination buffer
- `size` – Destination buffer size

**Return values**
- -ENOSPC – Destination buffer too small
- -EFAULT – Memory access error
- -ENOSYS – Thread name feature not enabled
- 0 – Success

const char *k_thread_state_str(k_tid_t thread_id, char *buf, size_t buf_size)
Get thread state string.
This routine generates a human friendly string containing the thread’s state, and copies as much of it as possible into `buf`.

**Parameters**
- `thread_id` – Thread ID
• buf – Buffer into which to copy state strings
• buf_size – Size of the buffer

**Return values**

Pointer – to `buf` if data was copied, else a pointer to “”.

```c
struct k_thread
#include <thread.h> Thread Structure

Public Members

struct _callee_saved callee_saved
    defined by the architecture, but all archs need these

void *init_data
    static thread init data

_wait_q_t join_queue
    threads waiting in `k_thread_join()

struct __thread_entry entry
    thread entry and parameters description

struct k_thread *next_thread
    next item in list of all threads

void *custom_data
    crude thread-local storage

struct _thread_stack_info stack_info
    Stack Info

struct _mem_domain_info mem_domain_info
    memory domain info of the thread

k_thread_stack_t *stack_obj
    Base address of thread stack

void *syscall_frame
    current syscall frame pointer

int swap_retval
    z_swap() return value

void *switch_handle
    Context handle returned via `arch_switch()

struct k_heap *resource_pool
    resource pool
```
struct_thread_arch arch
    arch-specifics: must always be at the end

group thread_stack_api
    Thread Stack APIs.

Defines

K_KERNEL_STACK_DECLARE(sym, size)
    Declare a reference to a thread stack.
    This macro declares the symbol of a thread stack defined elsewhere in the current scope.
    Parameters
    • sym – Thread stack symbol name
    • size – Size of the stack memory region

K_KERNEL_STACK_ARRAY_DECLARE(sym, nmemb, size)
    Declare a reference to a thread stack array.
    This macro declares the symbol of a thread stack array defined elsewhere in the current scope.
    Parameters
    • sym – Thread stack symbol name
    • nmemb – Number of stacks defined
    • size – Size of the stack memory region

K_KERNEL_PINNED_STACK_ARRAY_DECLARE(sym, nmemb, size)
    Declare a reference to a pinned thread stack array.
    This macro declares the symbol of a pinned thread stack array defined elsewhere in the current scope.
    Parameters
    • sym – Thread stack symbol name
    • nmemb – Number of stacks defined
    • size – Size of the stack memory region

K_KERNEL_STACK_EXTERN(sym)
    Obtain an extern reference to a stack.
    This macro properly brings the symbol of a thread stack defined elsewhere into scope.

    Deprecated:
    Use K_KERNEL_STACK_DECLARE() instead.
    Parameters
    • sym – Thread stack symbol name

K_KERNEL_STACK_ARRAY_EXTERN(sym, nmemb, size)
    Obtain an extern reference to a stack array.
    This macro properly brings the symbol of a stack array defined elsewhere into scope.
Deprecation:
Use `K_KERNEL_STACK_ARRAY_DECLARE()` instead.

**Parameters**
- `sym` – Thread stack symbol name
- `nmemb` – Number of stacks defined
- `size` – Size of the stack memory region

**K_KERNEL_PINNED_STACK_ARRAY_EXTERN(sym, nmemb, size)**
Obtain an extern reference to a pinned stack array.
This macro properly brings the symbol of a pinned stack array defined elsewhere into scope.

Deprecation:
Use `K_KERNEL_PINNED_STACK_ARRAY_DECLARE()` instead.

**Parameters**
- `sym` – Thread stack symbol name
- `nmemb` – Number of stacks defined
- `size` – Size of the stack memory region

**K_KERNEL_STACK_DEFINE(sym, size)**
Define a top level kernel stack memory region.
This defines a region of memory for use as a thread stack, for threads that exclusively run in supervisor mode. This is also suitable for declaring special stacks for interrupt or exception handling.
Stacks defined with this macro may not host user mode threads.
It is legal to precede this definition with the 'static' keyword.
It is NOT legal to take the sizeof(sym) and pass that to the stackSize parameter of `k_thread_create()`, it may not be the same as the 'size' parameter. Use `K_KERNEL_STACK_SIZEOF()` instead.
The total amount of memory allocated may be increased to accommodate fixed-size stack overflow guards.

**Parameters**
- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region

**K_KERNEL_PINNED_STACK_DEFINE(sym, size)**
Define a top level kernel stack memory region in pinned section.
See `K_KERNEL_STACK_DEFINE()` for more information and constraints.
This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as `K_KERNEL_STACK_DEFINE()`.

**Parameters**
- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region
K_KERNEL_STACK_ARRAY_DEFINE(sym, nmemb, size)
Define a toplevel array of kernel stack memory regions.
Stacks defined with this macro may not host user mode threads.

Parameters
• sym – Kernel stack array symbol name
• nmemb – Number of stacks to define
• size – Size of the stack memory region

K_KERNEL_PINNED_STACK_ARRAY_DEFINE(sym, nmemb, size)
Define a toplevel array of kernel stack memory regions in pinned section.
See K_KERNEL_STACK_ARRAY_DEFINE() for more information and constraints.
This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as K_KERNEL_STACK_ARRAY_DEFINE().

Parameters
• sym – Kernel stack array symbol name
• nmemb – Number of stacks to define
• size – Size of the stack memory region

K_KERNEL_STACK_MEMBER(sym, size)
Define an embedded stack memory region.
Used for kernel stacks embedded within other data structures.
Stacks defined with this macro may not host user mode threads.

Parameters
• sym – Thread stack symbol name
• size – Size of the stack memory region

K_KERNEL_STACK_SIZEOF(sym)

K_THREAD_STACK_DECLARE(sym, size)
Declare a reference to a thread stack.
This macro declares the symbol of a thread stack defined elsewhere in the current scope.

Parameters
• sym – Thread stack symbol name
• size – Size of the stack memory region

K_THREAD_STACK_ARRAY_DECLARE(sym, nmemb, size)
Declare a reference to a thread stack array.
This macro declares the symbol of a thread stack array defined elsewhere in the current scope.

Parameters
• sym – Thread stack symbol name
• nmemb – Number of stacks defined
• size – Size of the stack memory region
K_THREAD_STACK_EXTERN(sym)
Obtain an extern reference to a stack.

This macro properly brings the symbol of a thread stack defined elsewhere into scope.

Deprecated:
Use K_THREAD_STACK_DECLARE() instead.

Parameters
- sym – Thread stack symbol name

K_THREAD_STACK_ARRAY_EXTERN(sym, nmemb, size)
Obtain an extern reference to a thread stack array.

This macro properly brings the symbol of a stack array defined elsewhere into scope.

Deprecated:
Use K_THREAD_STACK_ARRAY_DECLARE() instead.

Parameters
- sym – Thread stack symbol name
- nmemb – Number of stacks defined
- size – Size of the stack memory region

K_THREAD_STACK_SIZEOF(sym)
Return the size in bytes of a stack memory region.

Convenience macro for passing the desired stack size to k_thread_create() since the underlying implementation may actually create something larger (for instance a guard area).

The value returned here is not guaranteed to match the 'size' parameter passed to K_THREAD_STACK_DEFINE and may be larger, but is always safe to pass to k_thread_create() for the associated stack object.

Parameters
- sym – Stack memory symbol

Returns
Size of the stack buffer

K_THREAD_STACK_DEFINE(sym, size)
Define a toplevel thread stack memory region.

This defines a region of memory suitable for use as a thread's stack.

This is the generic, historical definition. Align to Z_THREAD_STACK_OBJ_ALIGN and put in 'noinit' section so that it isn't zeroed at boot

The defined symbol will always be a k_thread_stack_t which can be passed to k_thread_create(), but should otherwise not be manipulated. If the buffer inside needs to be examined, examine thread->stack_info for the associated thread object to obtain the boundaries.

It is legal to precede this definition with the 'static' keyword.

It is NOT legal to take the sizeof(sym) and pass that to the stackSize parameter of k_thread_create(), it may not be the same as the 'size' parameter. Use K_THREAD_STACK_SIZEOF() instead.
Some arches may round the size of the usable stack region up to satisfy alignment constraints. 
*K_THREAD_STACK_SIZEOF()* will return the aligned size.

**Parameters**
- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region

*K_THREAD_PINNED_STACK_DEFINE*(sym, size)

Define a toplevel thread stack memory region in pinned section.
This defines a region of memory suitable for use as a thread's stack.
This is the generic, historical definition. Align to Z_THREAD.Stack.Obj_ALIGN and put in 'noinit' section so that it isn’t zeroed at boot

The defined symbol will always be a k_thread_stack_t which can be passed to k_thread_create(), but should otherwise not be manipulated. If the buffer inside needs to be examined, examine thread->stack_info for the associated thread object to obtain the boundaries.

It is legal to precede this definition with the ‘static’ keyword.

It is NOT legal to take the sizeof(sym) and pass that to the stackSize parameter of k_thread_create(), it may not be the same as the ‘size’ parameter. Use K_THREAD_STACK_SIZEOF() instead.

Some arches may round the size of the usable stack region up to satisfy alignment constraints. 
*K_THREAD_STACK_SIZEOF()* will return the aligned size.

This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as K_THREAD_STACK_DEFINE().

**Parameters**
- `sym` – Thread stack symbol name
- `size` – Size of the stack memory region

*K_THREAD_STACK_LEN*(size)

Calculate size of stacks to be allocated in a stack array.

This macro calculates the size to be allocated for the stacks inside a stack array. It accepts the indicated "size" as a parameter and if required, pads some extra bytes (e.g. for MPU scenarios). Refer K_THREAD_STACK_ARRAY_DEFINE definition to see how this is used. The returned size ensures each array member will be aligned to the required stack base alignment.

**Parameters**
- `size` – Size of the stack memory region

**Returns**
Appropriate size for an array member

*K_THREAD_STACK_ARRAY_DEFINE*(sym, nmemb, size)

Define a toplevel array of thread stack memory regions.

Create an array of equally sized stacks. See K_THREAD_STACK_DEFINE definition for additional details and constraints.

This is the generic, historical definition. Align to Z_THREAD_STACK_OBJ_ALIGN and put in 'noinit' section so that it isn’t zeroed at boot

**Parameters**
- `sym` – Thread stack symbol name
- `nmemb` – Number of stacks to define
• size – Size of the stack memory region

K_THREAD_PINNED_STACK_ARRAY_DEFINE(sym, nmemb, size)
Define a toplevel array of thread stack memory regions in pinned section.

Create an array of equally sized stacks. See K_THREAD_STACK_DEFINE definition for additional details and constraints.

This is the generic, historical definition. Align to Z_THREAD_STACK_OBJ_ALIGN and put in 'noinit' section so that it isn't zeroed at boot.

This puts the stack into the pinned noinit linker section if CONFIG_LINKER_USE_PINNED_SECTION is enabled, or else it would put the stack into the same section as K_THREAD_STACK_DEFINE().

Parameters
• sym – Thread stack symbol name
• nmemb – Number of stacks to define
• size – Size of the stack memory region

K_THREAD_STACK_MEMBER(sym, size)
Define an embedded stack memory region.

Used for stacks embedded within other data structures. Use is highly discouraged but in some cases necessary. For memory protection scenarios, it is very important that any RAM preceding this member not be writable by threads else a stack overflow will lead to silent corruption. In other words, the containing data structure should live in RAM owned by the kernel.

A user thread can only be started with a stack defined in this way if the thread starting it is in supervisor mode.

This is now deprecated, as stacks defined in this way are not usable from user mode. Use K_KERNEL_STACK_MEMBER.

Parameters
• sym – Thread stack symbol name
• size – Size of the stack memory region

Scheduling

The kernel's priority-based scheduler allows an application's threads to share the CPU.

Concepts  The scheduler determines which thread is allowed to execute at any point in time; this thread is known as the current thread.

There are various points in time when the scheduler is given an opportunity to change the identity of the current thread. These points are called reschedule points. Some potential reschedule points are:

• transition of a thread from running state to a suspended or waiting state, for example by k_sem_take() or k_sleep().
• transition of a thread to the ready state, for example by k_sem_give() or k_thread_start()
• return to thread context after processing an interrupt
• when a running thread invokes k_yield()

A thread sleeps when it voluntarily initiates an operation that transitions itself to a suspended or waiting state.
Whenever the scheduler changes the identity of the current thread, or when execution of the current thread is replaced by an ISR, the kernel first saves the current thread’s CPU register values. These register values get restored when the thread later resumes execution.

**Scheduling Algorithm**  The kernel's scheduler selects the highest priority ready thread to be the current thread. When multiple ready threads of the same priority exist, the scheduler chooses the one that has been waiting longest.

A thread's relative priority is primarily determined by its static priority. However, when both earliest-deadline-first scheduling is enabled (CONFIG_SCHED_DEADLINE) and a choice of threads have equal static priority, then the thread with the earlier deadline is considered to have the higher priority. Thus, when earliest-deadline-first scheduling is enabled, two threads are only considered to have the same priority when both their static priorities and deadlines are equal. The routine `k_thread_deadline_set()` is used to set a thread’s deadline.

**Note:** Execution of ISRs takes precedence over thread execution, so the execution of the current thread may be replaced by an ISR at any time unless interrupts have been masked. This applies to both cooperative threads and preemptive threads.

The kernel can be built with one of several choices for the ready queue implementation, offering different choices between code size, constant factor runtime overhead and performance scaling when many threads are added.

- **Simple linked-list ready queue (CONFIG_SCHED_DUMB)**

   The scheduler ready queue will be implemented as a simple unordered list, with very fast constant time performance for single threads and very low code size. This implementation should be selected on systems with constrained code size that will never see more than a small number (3, maybe) of runnable threads in the queue at any given time. On most platforms (that are not otherwise using the red/black tree) this results in a savings of ~2k of code size.

- **Red/black tree ready queue (CONFIG_SCHED_SCALABLE)**

   The scheduler ready queue will be implemented as a red/black tree. This has rather slower constant-time insertion and removal overhead, and on most platforms (that are not otherwise using the red/black tree somewhere) requires an extra ~2kb of code. The resulting behavior will scale cleanly and quickly into the many thousands of threads.

   Use this for applications needing many concurrent runnable threads (> 20 or so). Most applications won’t need this ready queue implementation.

- **Traditional multi-queue ready queue (CONFIG_SCHED_MULTIQ)**

   When selected, the scheduler ready queue will be implemented as the classic/textbook array of lists, one per priority (max 32 priorities).

   This corresponds to the scheduler algorithm used in Zephyr versions prior to 1.12.

   It incurs only a tiny code size overhead vs. the “dumb” scheduler and runs in O(1) time in almost all circumstances with very low constant factor. But it requires a fairly large RAM budget to store those list heads, and the limited features make it incompatible with features like deadline scheduling that need to sort threads more finely, and SMP affinity which need to traverse the list of threads.

   Typical applications with small numbers of runnable threads probably want the DUMB scheduler.

The wait_q abstraction used in IPC primitives to pend threads for later wakeup shares the same backend data structure choices as the scheduler, and can use the same options.

- **Scalable wait_q implementation (CONFIG_WAITQ_SCALABLE)**

   When selected, the wait_q will be implemented with a balanced tree. Choose this if you expect to have many threads waiting on individual primitives. There is a ~2kb code size increase over CONFIG_WAITQ_DUMB (which may be shared with CONFIG_SCHED_SCALABLE) if the red/black tree
is not used elsewhere in the application, and pend/unpend operations on “small” queues will be somewhat slower (though this is not generally a performance path).

- Simple linked-list wait_q (CONFIG_WAITQ_DUMB)
  When selected, the wait_q will be implemented with a doubly-linked list. Choose this if you expect to have only a few threads blocked on any single IPC primitive.

**Cooperative Time Slicing**  Once a cooperative thread becomes the current thread, it remains the current thread until it performs an action that makes it unready. Consequently, if a cooperative thread performs lengthy computations, it may cause an unacceptable delay in the scheduling of other threads, including those of higher priority and equal priority.

To overcome such problems, a cooperative thread can voluntarily relinquish the CPU from time to time to permit other threads to execute. A thread can relinquish the CPU in two ways:

- Calling `k_yield()` puts the thread at the back of the scheduler’s prioritized list of ready threads, and then invokes the scheduler. All ready threads whose priority is higher or equal to that of the yielding thread are then allowed to execute before the yielding thread is rescheduled. If no such ready threads exist, the scheduler immediately reschedules the yielding thread without context switching.

- Calling `k_sleep()` makes the thread unready for a specified time period. Ready threads of *all* priorities are then allowed to execute; however, there is no guarantee that threads whose priority is lower than that of the sleeping thread will actually be scheduled before the sleeping thread becomes ready once again.

**Preemptive Time Slicing**  Once a preemptive thread becomes the current thread, it remains the current thread until a higher priority thread becomes ready, or until the thread performs an action that makes it unready. Consequently, if a preemptive thread performs lengthy computations, it may cause an unacceptable delay in the scheduling of other threads, including those of equal priority.
To overcome such problems, a preemptive thread can perform cooperative time slicing (as described above), or the scheduler's time slicing capability can be used to allow other threads of the same priority to execute.

The scheduler divides time into a series of **time slices**, where slices are measured in system clock ticks. The time slice size is configurable, but this size can be changed while the application is running.

At the end of every time slice, the scheduler checks to see if the current thread is preemptible and, if so, implicitly invokes `k_yield()` on behalf of the thread. This gives other ready threads of the same priority the opportunity to execute before the current thread is scheduled again. If no threads of equal priority are ready, the current thread remains the current thread.

Threads with a priority higher than specified limit are exempt from preemptive time slicing, and are never preempted by a thread of equal priority. This allows an application to use preemptive time slicing only when dealing with lower priority threads that are less time-sensitive.

**Note:** The kernel's time slicing algorithm does not ensure that a set of equal-priority threads receive an
equitable amount of CPU time, since it does not measure the amount of time a thread actually gets to execute. However, the algorithm does ensure that a thread never executes for longer than a single time slice without being required to yield.

**Scheduler Locking** A preemptible thread that does not wish to be preempted while performing a critical operation can instruct the scheduler to temporarily treat it as a cooperative thread by calling `k_sched_lock()`. This prevents other threads from interfering while the critical operation is being performed.

Once the critical operation is complete the preemptible thread must call `k_sched_unlock()` to restore its normal, preemptible status.

If a thread calls `k_sched_lock()` and subsequently performs an action that makes it unready, the scheduler will switch the locking thread out and allow other threads to execute. When the locking thread again becomes the current thread, its non-preemptible status is maintained.

**Note:** Locking out the scheduler is a more efficient way for a preemptible thread to prevent preemption than changing its priority level to a negative value.

**Thread Sleeping** A thread can call `k_sleep()` to delay its processing for a specified time period. During the time the thread is sleeping the CPU is relinquished to allow other ready threads to execute. Once the specified delay has elapsed the thread becomes ready and is eligible to be scheduled once again.

A sleeping thread can be woken up prematurely by another thread using `k_wakeup()`. This technique can sometimes be used to permit the secondary thread to signal the sleeping thread that something has occurred without requiring the threads to define a kernel synchronization object, such as a semaphore. Waking up a thread that is not sleeping is allowed, but has no effect.

**Busy Waiting** A thread can call `k_busy_wait()` to perform a busy wait that delays its processing for a specified time period without relinquishing the CPU to another ready thread.

A busy wait is typically used instead of thread sleeping when the required delay is too short to warrant having the scheduler context switch from the current thread to another thread and then back again.

**Suggested Uses** Use cooperative threads for device drivers and other performance-critical work.

Use cooperative threads to implement mutually exclusion without the need for a kernel object, such as a mutex.

Use preemptive threads to give priority to time-sensitive processing over less time-sensitive processing.

**CPU Idling**

Although normally reserved for the idle thread, in certain special applications, a thread might want to make the CPU idle.
Concepts  Making the CPU idle causes the kernel to pause all operations until an event, normally an interrupt, wakes up the CPU. In a regular system, the idle thread is responsible for this. However, in some constrained systems, it is possible that another thread takes this duty.

Implementation

Making the CPU idle  Making the CPU idle is simple: call the \texttt{k_cpu_idle()} API. The CPU will stop executing instructions until an event occurs. Most likely, the function will be called within a loop. Note that in certain architectures, upon return, \texttt{k_cpu_idle()} unconditionally unmasks interrupts.

\begin{verbatim}
static k_sem my_sem;

void my_isr(void *unused)
{
    k_sem_give(&my_sem);
}

void main(void)
{
    k_sem_init(&my_sem, 0, 1);
    /* wait for semaphore from ISR, then do related work */
    for (;;) {
        /* wait for ISR to trigger work to perform */
        if (k_sem_take(&my_sem, K_NO_WAIT) == 0) {
            /* ... do processing */
        }
        /* put CPU to sleep to save power */
        k_cpu_idle();
    }
}
\end{verbatim}

Making the CPU idle in an atomic fashion  It is possible that there is a need to do some work atomically before making the CPU idle. In such a case, \texttt{k_cpu_atomic_idle()} should be used instead.

In fact, there is a race condition in the previous example: the interrupt could occur between the time the semaphore is taken, finding out it is not available and making the CPU idle again. In some systems, this can cause the CPU to idle until another interrupt occurs, which might be never, thus hanging the system completely. To prevent this, \texttt{k_cpu_atomic_idle()} should have been used, like in this example.

\begin{verbatim}
static k_sem my_sem;

void my_isr(void *unused)
{
    k_sem_give(&my_sem);
}
\end{verbatim}
void main(void)
{
    k_sem_init(&my_sem, 0, 1);
    for (;;)
    {
        unsigned int key = irq_lock();

        /*
         * Wait for semaphore from ISR; if acquired, do related work, then
         * go to next loop iteration (the semaphore might have been given
         * again); else, make the CPU idle.
         */

        if (k_sem_take(&my_sem, K_NO_WAIT) == 0) {
            irq_unlock(key);
            /* ... do processing */

        } else {
            /* put CPU to sleep to save power */
            k_cpu_atomic_idle(key);
        }
    }
}

Suggested Uses Use k_cpu_atomic_idle() when a thread has to do some real work in addition to idling
the CPU to wait for an event. See example above.

Use k_cpu_idle() only when a thread is only responsible for idling the CPU, i.e. not doing any real work,
like in this example below.

void main(void)
{
    /* ... do some system/application initialization */

    /* thread is only used for CPU idling from this point on */
    for (;;)
    {
        k_cpu_idle();
    }
}

Note: Do not use these APIs unless absolutely necessary. In a normal system, the idle thread takes
care of power management, including CPU idling.

API Reference
group cpu_idle_apis
Functions

static inline void k_cpu_idle(void)
    Make the CPU idle.
    This function makes the CPU idle until an event wakes it up.
    In a regular system, the idle thread should be the only thread responsible for making the
    CPU idle and triggering any type of power management. However, in some more constrained
    systems, such as a single-threaded system, the only thread would be responsible for this if
    needed.

    **Note:** In some architectures, before returning, the function un masks interrupts uncondi-
    tionally.

static inline void k_cpu_atomic_idle(unsigned int key)
    Make the CPU idle in an atomic fashion.
    Similar to `k_cpu_idle()`, but must be called with interrupts locked.
    Enabling interrupts and entering a low-power mode will be atomic, i.e. there will be no period
    of time where interrupts are enabled before the processor enters a low-power mode.
    After waking up from the low-power mode, the interrupt lockout state will be restored as if
    by `irq_unlock(key)`.

    **Parameters**
    - key – Interrupt locking key obtained from `irq_lock()`.

System Threads

- **Implementation**
  - Writing a `main()` function
- **Suggested Uses**

A *system thread* is a thread that the kernel spawns automatically during system initialization.
The kernel spawns the following system threads:

**Main thread**
This thread performs kernel initialization, then calls the application's `main()` function (if one is
defined).
By default, the main thread uses the highest configured preemptible thread priority (i.e. 0). If the
kernel is not configured to support preemptible threads, the main thread uses the lowest configured
cooperative thread priority (i.e. -1).
The main thread is an essential thread while it is performing kernel initialization or executing the
application's `main()` function; this means a fatal system error is raised if the thread aborts. If
`main()` is not defined, or if it executes and then does a normal return, the main thread terminates
normally and no error is raised.

**Idle thread**
This thread executes when there is no other work for the system to do. If possible, the idle thread
activates the board's power management support to save power; otherwise, the idle thread simply
performs a "do nothing" loop. The idle thread remains in existence as long as the system is running
and never terminates.
The idle thread always uses the lowest configured thread priority. If this makes it a cooperative thread, the idle thread repeatedly yields the CPU to allow the application’s other threads to run when they need to.

The idle thread is an essential thread, which means a fatal system error is raised if the thread aborts.

Additional system threads may also be spawned, depending on the kernel and board configuration options specified by the application. For example, enabling the system workqueue spawns a system thread that services the work items submitted to it. (See Workqueue Threads.)

Implementation

**Writing a main() function** An application-supplied main() function begins executing once kernel initialization is complete. The kernel does not pass any arguments to the function.

The following code outlines a trivial main() function. The function used by a real application can be as complex as needed.

```c
void main(void)
{
    /* initialize a semaphore */
    ...
    /* register an ISR that gives the semaphore */
    ...
    /* monitor the semaphore forever */
    while (1) {
        /* wait for the semaphore to be given by the ISR */
        ...
        /* do whatever processing is now needed */
        ...
    }
}
```

**Suggested Uses** Use the main thread to perform thread-based processing in an application that only requires a single thread, rather than defining an additional application-specific thread.

Workqueue Threads

- Work Item Lifecycle
- Delayable Work
- Triggered Work
- System Workqueue
- How to Use Workqueues
- Workqueue Best Practices
- Suggested Uses
- Configuration Options
- API Reference
A workqueue is a kernel object that uses a dedicated thread to process work items in a first in, first out manner. Each work item is processed by calling the function specified by the work item. A workqueue is typically used by an ISR or a high-priority thread to offload non-urgent processing to a lower-priority thread so it does not impact time-sensitive processing.

Any number of workqueues can be defined (limited only by available RAM). Each workqueue is referenced by its memory address.

A workqueue has the following key properties:

- A queue of work items that have been added, but not yet processed.
- A thread that processes the work items in the queue. The priority of the thread is configurable, allowing it to be either cooperative or preemptive as required.

Regardless of workqueue thread priority the workqueue thread will yield between each submitted work item, to prevent a cooperative workqueue from starving other threads.

A workqueue must be initialized before it can be used. This sets its queue to empty and spawns the workqueue's thread. The thread runs forever, but sleeps when no work items are available.

Note: The behavior described here is changed from the Zephyr workqueue implementation used prior to release 2.6. Among the changes are:

- Precise tracking of the status of cancelled work items, so that the caller need not be concerned that an item may be processing when the cancellation returns. Checking of return values on cancellation is still required.
- Direct submission of delayable work items to the queue with \texttt{K\_NO\_WAIT} rather than always going through the timeout API, which could introduce delays.
- The ability to wait until a work item has completed or a queue has been drained.
- Finer control of behavior when scheduling a delayable work item, specifically allowing a previous deadline to remain unchanged when a work item is scheduled again.
- Safe handling of work item resubmission when the item is being processed on another workqueue.

Using the return values of \texttt{k\_work\_busy\_get()} or \texttt{k\_work\_is\_pending()}, or measurements of remaining time until delayable work is scheduled, should be avoided to prevent race conditions of the type observed with the previous implementation. See also Workqueue Best Practices.

Work Item Lifecycle

Any number of work items can be defined. Each work item is referenced by its memory address.

A work item is assigned a handler function, which is the function executed by the workqueue's thread when the work item is processed. This function accepts a single argument, which is the address of the work item itself. The work item also maintains information about its status.

A work item must be initialized before it can be used. This records the work item's handler function and marks it as not pending.

A work item may be queued (\texttt{K\_WORK\_QUEUED}) by submitting it to a workqueue by an ISR or a thread. Submitting a work item appends the work item to the workqueue's queue. Once the workqueue's thread has processed all of the preceding work items in its queue the thread will remove the next work item from the queue and invoke the work item's handler function. Depending on the scheduling priority of the workqueue's thread, and the work required by other items in the queue, a queued work item may be processed quickly or it may remain in the queue for an extended period of time.

A delayable work item may be scheduled (\texttt{K\_WORK\_DELAYED}) to a workqueue; see Delayable Work.

A work item will be running (\texttt{K\_WORK\_RUNNING}) when it is running on a work queue, and may also be canceling (\texttt{K\_WORK\_CANCELING}) if it started running before a thread has requested that it be cancelled.

A work item can be in multiple states; for example it can be:
• running on a queue;
• marked canceling (because a thread used `k_work_cancel_sync()` to wait until the work item completed);
• queued to run again on the same queue;
• scheduled to be submitted to a (possibly different) queue

_all simultaneously_. A work item that is in any of these states is pending (`k_work_is_pending()`) or busy (`k_work_busy_get()`).

A handler function can use any kernel API available to threads. However, operations that are potentially blocking (e.g. taking a semaphore) must be used with care, since the workqueue cannot process subsequent work items in its queue until the handler function finishes executing.

The single argument that is passed to a handler function can be ignored if it is not required. If the handler function requires additional information about the work it is to perform, the work item can be embedded in a larger data structure. The handler function can then use the argument value to compute the address of the enclosing data structure with `CONTAINER_OF`, and thereby obtain access to the additional information it needs.

A work item is typically initialized once and then submitted to a specific workqueue whenever work needs to be performed. If an ISR or a thread attempts to submit a work item that is already queued the work item is not affected; the work item remains in its current place in the workqueue's queue, and the work is only performed once.

A handler function is permitted to re-submit its work item argument to the workqueue, since the work item is no longer queued at that time. This allows the handler to execute work in stages, without unduly delaying the processing of other work items in the workqueue's queue.

**Important:** A pending work item _must not_ be altered until the item has been processed by the workqueue thread. This means a work item must not be re-initialized while it is busy. Furthermore, any additional information the work item's handler function needs to perform its work must not be altered until the handler function has finished executing.

**Delayable Work** An ISR or a thread may need to schedule a work item that is to be processed only after a specified period of time, rather than immediately. This can be done by scheduling a delayable work item to be submitted to a workqueue at a future time.

A delayable work item contains a standard work item but adds fields that record when and where the item should be submitted.

A delayable work item is initialized and scheduled to a workqueue in a similar manner to a standard work item, although different kernel APIs are used. When the schedule request is made the kernel initiates a timeout mechanism that is triggered after the specified delay has elapsed. Once the timeout occurs the kernel submits the work item to the specified workqueue, where it remains queued until it is processed in the standard manner.

Note that work handler used for delayable still receives a pointer to the underlying non-delayable work structure, which is not publicly accessible from `k_work_delayable`. To get access to an object that contains the delayable work object use this idiom:

```c
static void work_handler(struct k_work *work)
{
    struct k_work_delayable *dwork = k_work_delayable_from_work(work);
    struct work_context *ctx = CONTAINER_OF(dwork, struct work_context, timed_work);
    ...
}
```
Triggered Work  The \texttt{k\_work\_poll\_submit()} interface schedules a triggered work item in response to a poll event (see Polling API), that will call a user-defined function when a monitored resource becomes available or poll signal is raised, or a timeout occurs. In contrast to \texttt{k\_poll()}, the triggered work does not require a dedicated thread waiting or actively polling for a poll event.

A triggered work item is a standard work item that has the following added properties:

- A pointer to an array of poll events that will trigger work item submissions to the workqueue
- A size of the array containing poll events.

A triggered work item is initialized and submitted to a workqueue in a similar manner to a standard work item, although dedicated kernel APIs are used. When a submit request is made, the kernel begins observing kernel objects specified by the poll events. Once at least one of the observed kernel object’s changes state, the work item is submitted to the specified workqueue, where it remains queued until it is processed in the standard manner.

\textbf{Important:} The triggered work item as well as the referenced array of poll events have to be valid and cannot be modified for a complete triggered work item lifecycle, from submission to work item execution or cancellation.

An ISR or a thread may cancel a triggered work item it has submitted as long as it is still waiting for a poll event. In such case, the kernel stops waiting for attached poll events and the specified work is not executed. Otherwise the cancellation cannot be performed.

System Workqueue  The kernel defines a workqueue known as the system workqueue, which is available to any application or kernel code that requires workqueue support. The system workqueue is optional, and only exists if the application makes use of it.

\textbf{Important:} Additional workqueues should only be defined when it is not possible to submit new work items to the system workqueue, since each new workqueue incurs a significant cost in memory footprint. A new workqueue can be justified if it is not possible for its work items to co-exist with existing system workqueue work items without an unacceptable impact; for example, if the new work items perform blocking operations that would delay other system workqueue processing to an unacceptable degree.

How to Use Workqueues

Defining and Controlling a Workqueue  A workqueue is defined using a variable of type \texttt{k\_work\_q}. The workqueue is initialized by defining the stack area used by its thread, initializing the \texttt{k\_work\_q}, either zeroing its memory or calling \texttt{k\_work\_queue\_init()}, and then calling \texttt{k\_work\_queue\_start()}. The stack area must be defined using \texttt{K\_THREAD\_STACK\_DEFINE} to ensure it is properly set up in memory.

The following code defines and initializes a workqueue:

\begin{verbatim}
#define MY_STACK_SIZE 512
#define MY_PRIORITY 5

K_THREAD_STACK_DEFINE(my_stack_area, MY_STACK_SIZE);

struct k_work_q my_work_q;

k_work_queue_init(&my_work_q);

k_work_queue_start(&my_work_q, my_stack_area, 
K_THREAD_STACK_SIZEOF(my_stack_area), MY_PRIORITY, 
NULL);
\end{verbatim}
In addition the queue identity and certain behavior related to thread rescheduling can be controlled by the optional final parameter; see \texttt{k_work_queue_start()} for details.

The following API can be used to interact with a workqueue:

- \texttt{k_work_queue_drain()} can be used to block the caller until the work queue has no items left. Work items resubmitted from the workqueue thread are accepted while a queue is draining, but work items from any other thread or ISR are rejected. The restriction on submitting more work can be extended past the completion of the drain operation in order to allow the blocking thread to perform additional work while the queue is “plugged”. Note that draining a queue has no effect on scheduling or processing delayable items, but if the queue is plugged and the deadline expires the item will silently fail to be submitted.

- \texttt{k_work_queue_unplug()} removes any previous block on submission to the queue due to a previous drain operation.

**Submitting a Work Item** A work item is defined using a variable of type \texttt{k_work}. It must be initialized by calling \texttt{k_work_init()}, unless it is defined using \texttt{K_WORK_DEFINE} in which case initialization is performed at compile-time.

An initialized work item can be submitted to the system workqueue by calling \texttt{k_work_submit()}, or to a specified workqueue by calling \texttt{k_work_submit_to_queue()}.

The following code demonstrates how an ISR can offload the printing of error messages to the system workqueue. Note that if the ISR attempts to resubmit the work item while it is still queued, the work item is left unchanged and the associated error message will not be printed.

```c
struct device_info {
    struct k_work work;
    char name[16]
} my_device;

void my_isr(void *arg) {
    ... 
    if (error detected) {
        k_work_submit(&my_device.work);
    }
    ...
}

void print_error(struct k_work *item) {
    struct device_info *the_device = CONTAINER_OF(item, struct device_info, work);
    printk("Got error on device %s\n", the_device->name);
}

/* initialize name info for a device */
strcpy(my_device.name, "FOO_dev");

/* initialize work item for printing device's error messages */
k_work_init(&my_device.work, print_error);

/* install my_isr() as interrupt handler for the device (not shown) */
...
```

The following API can be used to check the status of or synchronize with the work item:

- \texttt{k_work_busy_get()} returns a snapshot of flags indicating work item state. A zero value indicates the work is not scheduled, submitted, being executed, or otherwise still being referenced by the
workqueue infrastructure.

- `k_work_is_pending()` is a helper that indicates `true` if and only if the work is scheduled, queued, or running.
- `k_work_flush()` may be invoked from threads to block until the work item has completed. It returns immediately if the work is not pending.
- `k_work_cancel()` attempts to prevent the work item from being executed. This may or may not be successful. This is safe to invoke from ISRs.
- `k_work_cancel_sync()` may be invoked from threads to block until the work completes; it will return immediately if the cancellation was successful or not necessary (the work wasn’t submitted or running). This can be used after `k_work_cancel()` is invoked (from an ISR) to confirm completion of an ISR-initiated cancellation.

Scheduling a Delayable Work Item  A delayable work item is defined using a variable of type `k_work_delayable`. It must be initialized by calling `k_work_init_delayable()`. For delayed work there are two common use cases, depending on whether a deadline should be extended if a new event occurs. An example is collecting data that comes in asynchronously, e.g. characters from a UART associated with a keyboard. There are two APIs that submit work after a delay:

- `k_work_schedule()` (or `k_work_schedule_for_queue()` ) schedules work to be executed at a specific time or after a delay. Further attempts to schedule the same item with this API before the delay completes will not change the time at which the item will be submitted to its queue. Use this if the policy is to keep collecting data until a specified delay since the first unprocessed data was received;
- `k_work_reschedule()` (or `k_work_reschedule_for_queue()` ) unconditionally sets the deadline for the work, replacing any previous incomplete delay and changing the destination queue if necessary. Use this if the policy is to keep collecting data until a specified delay since the last unprocessed data was received.

If the work item is not scheduled both APIs behave the same. If `K_NO_WAIT` is specified as the delay the behavior is as if the item was immediately submitted directly to the target queue, without waiting for a minimal timeout (unless `k_work_schedule()` is used and a previous delay has not completed).

Both also have variants that allow control of the queue used for submission.

The helper function `k_work_delayable_from_work()` can be used to get a pointer to the containing `k_work_delayable` from a pointer to `k_work` that is passed to a work handler function.

The following additional API can be used to check the status of or synchronize with the work item:

- `k_work_delayable_busy_get()` is the analog to `k_work_busy_get()` for delayable work.
- `k_work_delayable_is_pending()` is the analog to `k_work_is_pending()` for delayable work.
- `k_work_flush_delayable()` is the analog to `k_work_flush()` for delayable work.
- `k_work_cancel_delayable()` is the analog to `k_work_cancel()` for delayable work; similarly with `k_work_cancel_delayable_sync()`.

Synchronizing with Work Items  While the state of both regular and delayable work items can be determined from any context using `k_work_busy_get()` and `k_work_delayable_busy_get()` some use cases require synchronizing with work items after they’ve been submitted. `k_work_flush()`, `k_work_cancel_sync()`, and `k_work_cancel_delayable_sync()` can be invoked from thread context to wait until the requested state has been reached.

These APIs must be provided with a `k_work_sync` object that has no application-inspectable components but is needed to provide the synchronization objects. These objects should not be allocated on a stack if the code is expected to work on architectures with `CONFIG_KERNEL_COHERENCE`.

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Workqueue Best Practices

Avoid Race Conditions  Sometimes the data a work item must process is naturally thread-safe, for example when it's put into a `k_queue` by some thread and processed in the work thread. More often external synchronization is required to avoid data races: cases where the work thread might inspect or manipulate shared state that's being accessed by another thread or interrupt. Such state might be a flag indicating that work needs to be done, or a shared object that is filled by an ISR or thread and read by the work handler.

For simple flags [Atomic Services](#) may be sufficient. In other cases spin locks (`k_spinlock_t`) or thread-aware locks (`k_sem`, `k_mutex`, ...) may be used to ensure data races don't occur.

If the selected lock mechanism can `sleep` then allowing the work thread to sleep will starve other work queue items, which may need to make progress in order to get the lock released. Work handlers should try to take the lock with its no-wait path. For example:

```c
static void work_handler(struct work *work)
{
    struct work_context *parent = CONTAINER_OF(work, struct work_context, work_item);

    if (k_mutex_lock(&parent->lock, K_NO_WAIT) != 0) {
        /* NB: Submit will fail if the work item is being cancelled. */
        (void)k_work_submit(work);
        return;
    }

    /* do stuff under lock */
    k_mutex_unlock(&parent->lock);
    /* do stuff without lock */
}
```

Be aware that if the lock is held by a thread with a lower priority than the work queue the resubmission may starve the thread that would release the lock, causing the application to fail. Where the idiom above is required a delayable work item is preferred, and the work should be (re-)scheduled with a non-zero delay to allow the thread holding the lock to make progress.

Note that submitting from the work handler can fail if the work item had been cancelled. Generally this is acceptable, since the cancellation will complete once the handler finishes. If it is not, the code above must take other steps to notify the application that the work could not be performed.

Work items in isolation are self-locking, so you don't need to hold an external lock just to submit or schedule them. Even if you use external state protected by such a lock to prevent further resubmission, it's safe to do the resubmit as long as you're sure that eventually the item will take its lock and check that state to determine whether it should do anything. Where a delayable work item is being rescheduled in its handler due to inability to take the lock some other self-locking state, such as an atomic flag set by the application/driver when the cancel is initiated, would be required to detect the cancellation and avoid the cancelled work item being submitted again after the deadline.

Check Return Values  All work API functions return status of the underlying operation, and in many cases it is important to verify that the intended result was obtained.

- Submitting a work item (`k_work_submit_to_queue()`) can fail if the work is being cancelled or the queue is not accepting new items. If this happens the work will not be executed, which could cause a subsystem that is animated by work handler activity to become non-responsive.
- Asynchronous cancellation (`k_work_cancel()` or `k_work_cancel_delayable()`) can complete while the work item is still being run by a handler. Proceeding to manipulate state shared with the work handler will result in data races that can cause failures.
Many race conditions have been present in Zephyr code because the results of an operation were not checked.

There may be good reason to believe that a return value indicating that the operation did not complete as expected is not a problem. In those cases the code should clearly document this, by (1) casting the return value to void to indicate that the result is intentionally ignored, and (2) documenting what happens in the unexpected case. For example:

```c
/* If this fails, the work handler will check pub->active and * exit without transmitting. */
(void)k_work_cancel_delayable(&pub->timer);
```

However in such a case the following code must still avoid data races, as it cannot guarantee that the work thread is not accessing work-related state.

**Don’t Optimize Prematurely**  The workqueue API is designed to be safe when invoked from multiple threads and interrupts. Attempts to externally inspect a work item’s state and make decisions based on the result are likely to create new problems.

So when new work comes in, just submit it. Don’t attempt to “optimize” by checking whether the work item is already submitted by inspecting snapshot state with `k_work_is_pending()` or `k_work_busy_get()`, or checking for a non-zero delay from `k_work_delayable_remaining_get()`. Those checks are fragile: a “busy” indication can be obsolete by the time the test is returned, and a “not-busy” indication can also be wrong if work is submitted from multiple contexts, or (for delayable work) if the deadline has completed but the work is still in queued or running state.

A general best practice is to always maintain in shared state some condition that can be checked by the handler to confirm whether there is work to be done. This way you can use the work handler as the standard cleanup path: rather than having to deal with cancellation and cleanup at points where items are submitted, you may be able to have everything done in the work handler itself.

A rare case where you could safely use `k_work_is_pending()` is as a check to avoid invoking `k_work_flush()` or `k_work_cancel_sync()`, if you are certain that nothing else might submit the work while you’re checking (generally because you’re holding a lock that prevents access to state used for submission).

**Suggested Uses**  Use the system workqueue to defer complex interrupt-related processing from an ISR to a shared thread. This allows the interrupt-related processing to be done promptly without compromising the system’s ability to respond to subsequent interrupts, and does not require the application to define and manage an additional thread to do the processing.

**Configuration Options**  Related configuration options:

- `CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE`
- `CONFIG_SYSTEM_WORKQUEUE_PRIORITY`
- `CONFIG_SYSTEM_WORKQUEUE_NO_YIELD`

**API Reference**

group workqueue_apis

*Defines*
K_WORK_DELAYABLE_DEFINE(work, work_handler)
Initialize a statically-defined delayable work item.
This macro can be used to initialize a statically-defined delayable work item, prior to its first use. For example,

```
static K_WORK_DELAYABLE_DEFINE(<dwork>, <work_handler>);
```

Note that if the runtime dependencies support initialization with `k_work_init_delayable()` using that will eliminate the initialized object in ROM that is produced by this macro and copied in at system startup.

**Parameters**
- `work` – Symbol name for delayable work item object
- `work_handler` – Function to invoke each time work item is processed.

K_WORK_USER_DEFINE(work, work_handler)
Initialize a statically-defined user work item.
This macro can be used to initialize a statically-defined user work item, prior to its first use. For example,

```
static K_WORK_USER_DEFINE(<work>, <work_handler>);
```

**Parameters**
- `work` – Symbol name for work item object
- `work_handler` – Function to invoke each time work item is processed.

K_WORK_DEFINE(work, work_handler)
Initialize a statically-defined work item.
This macro can be used to initialize a statically-defined workqueue work item, prior to its first use. For example,

```
static K_WORK_DEFINE(<work>, <work_handler>);
```

**Parameters**
- `work` – Symbol name for work item object
- `work_handler` – Function to invoke each time work item is processed.

**Typedefs**

typedef void (*k_work_handler_t)(struct k_work *work)
The signature for a work item handler function.
The function will be invoked by the thread animating a work queue.

**Param work**
the work item that provided the handler.
typedef void (*k_work_user_handler_t)(struct k_work_user *work)

Work item handler function type for user work queues.

A work item’s handler function is executed by a user workqueue’s thread when the work item
is processed by the workqueue.

**Param work**
Address of the work item.

**Enums**

eenum [anonymous]

**Values:**

enumerator K_WORK_RUNNING = BIT(K_WORK_RUNNING_BIT)
Flag indicating a work item that is running under a work queue thread.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_CANCELING = BIT(K_WORK_CANCELING_BIT)
Flag indicating a work item that is being canceled.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_QUEUED = BIT(K_WORK_QUEUED_BIT)
Flag indicating a work item that has been submitted to a queue but has not started run-
ning.
Accessed via k_work_busy_get(). May co-occur with other flags.

enumerator K_WORK_DELAYED = BIT(K_WORK_DELAYED_BIT)
Flag indicating a delayed work item that is scheduled for submission to a queue.
Accessed via k_work_busy_get(). May co-occur with other flags.

**Functions**

void k_work_init(struct k_work *work, k_work_handler_t handler)
Initialize a (non-delayable) work structure.

This must be invoked before submitting a work structure for the first time. It need not be
invoked again on the same work structure. It can be re-invoked to change the associated
handler, but this must be done when the work item is idle.

**Function properties (list may not be complete)**

* isr-ok

**Parameters**

- work – the work structure to be initialized.
- handler – the handler to be invoked by the work item.
int k_work_busy_get(const struct k_work *work)
Busy state flags from the work item.
A zero return value indicates the work item appears to be idle.

**Function properties (list may not be complete)**

**isr-ok**

**Note:** This is a live snapshot of state, which may change before the result is checked. Use locks where appropriate.

**Parameters**

- **work** – pointer to the work item.

**Returns**

a mask of flags K_WORK_DELAYED, K_WORK_QUEUED, K_WORK_RUNNING, and K_WORK_CANCELING.

static inline bool k_work_is_pending(const struct k_work *work)
Test whether a work item is currently pending.
Wrapper to determine whether a work item is in a non-idle dstate.

**Function properties (list may not be complete)**

**isr-ok**

**Note:** This is a live snapshot of state, which may change before the result is checked. Use locks where appropriate.

**Parameters**

- **work** – pointer to the work item.

**Returns**

true if and only if `k_work_busy_get()` returns a non-zero value.

int k_work_submit_to_queue(struct k_work *queue, struct k_work *work)
Submit a work item to a queue.

**Function properties (list may not be complete)**

**isr-ok**

**Parameters**

- **queue** – pointer to the work queue on which the item should run. If NULL the queue from the most recent submission will be used.
- **work** – pointer to the work item.

**Return values**

- 0 – if work was already submitted to a queue
- 1 – if work was not submitted and has been queued to queue
- 2 – if work was running and has been queued to the queue that was running it
int k_work_submit(struct k_work *work)
Submit a work item to the system queue.

Function properties (list may not be complete)
isr-ok

Parameters
• work – pointer to the work item.

Returns
as with k_work_submit_to_queue().

bool k_work_flush(struct k_work *work, struct k_work_sync *sync)
Wait for last-submitted instance to complete.
Resubmissions may occur while waiting, including chained submissions (from within the han-
dler).

Note:  Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.

Note:  Behavior is undefined if this function is invoked on work from a work queue running work.

Parameters
• work – pointer to the work item.
• sync – pointer to an opaque item containing state related to the pending can-
cellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

Return values
• true – if call had to wait for completion
• false – if work was already idle

int k_work_cancel(struct k_work *work)
Cancel a work item.
This attempts to prevent a pending (non-delayable) work item from being processed by removing it from the work queue. If the item is being processed, the work item will continue to be processed, but resubmissions are rejected until cancellation completes.

If this returns zero cancellation is complete, otherwise something (probably a work queue thread) is still referencing the item.

See also \texttt{k_work_cancel\_sync()}.

**Function properties (list may not be complete)**

\texttt{isr-ok}

**Parameters**

- \texttt{work} – pointer to the work item.

**Returns**

the \texttt{k_work\_busy\_get()} status indicating the state of the item after all cancellation steps performed by this call are completed.

\begin{verbatim}
bool k_work_cancel\_sync(struct k_work *work, struct k_work\_sync *sync)

Cancel a work item and wait for it to complete.
Same as \texttt{k_work\_cancel()} but does not return until cancellation is complete. This can be invoked by a thread after \texttt{k_work\_cancel()} to synchronize with a previous cancellation.

On return the work structure will be idle unless something submits it after the cancellation was complete.

\textbf{Note:} Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.

\textbf{Note:} Behavior is undefined if this function is invoked on \texttt{work} from a work queue running \texttt{work}.

\end{verbatim}

**Parameters**

- \texttt{work} – pointer to the work item.
- \texttt{sync} – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

**Return values**

- \texttt{true} – if work was pending (call had to wait for cancellation of a running handler to complete, or scheduled or submitted operations were cancelled);
- \texttt{false} – otherwise

\begin{verbatim}
void k_work\_queue\_init(struct k_work\_q *queue)

Initialize a work queue structure.
This must be invoked before starting a work queue structure for the first time. It need not be invoked again on the same work queue structure.
\end{verbatim}
Function properties (list may not be complete)

**isr-ok**

Parameters

- `queue` – the queue structure to be initialized.

```c
void k_work_queue_start(struct k_work_q *queue, k_thread_stack_t *stack, size_t stack_size, int prio, const struct k_work_queue_config *cfg)
```

Initialize a work queue.

This configures the work queue thread and starts it running. The function should not be re-invoked on a queue.

Parameters

- `queue` – pointer to the queue structure. It must be initialized in zeroed/bss memory or with `k_work_queue_init` before use.
- `stack` – pointer to the work thread stack area.
- `stack_size` – size of the the work thread stack area, in bytes.
- `prio` – initial thread priority
- `cfg` – optional additional configuration parameters. Pass `NULL` if not required, to use the defaults documented in `k_work_queue_config`.

```c
static inline k_tid_t k_work_queue_thread_get(struct k_work_q *queue)
```

Access the thread that animates a work queue.

This is necessary to grant a work queue thread access to things the work items it will process are expected to use.

Parameters

- `queue` – pointer to the queue structure.

Returns

the thread associated with the work queue.

```c
int k_work_queue_drain(struct k_work_q *queue, bool plug)
```

Wait until the work queue has drained, optionally plugging it.

This blocks submission to the work queue except when coming from queue thread, and blocks the caller until no more work items are available in the queue.

If `plug` is true then submission will continue to be blocked after the drain operation completes until `k_work_queue_unplug()` is invoked.

Note that work items that are delayed are not yet associated with their work queue. They must be cancelled externally if a goal is to ensure the work queue remains empty. The `plug` feature can be used to prevent delayed items from being submitted after the drain completes.

Parameters

- `queue` – pointer to the queue structure.
- `plug` – if true the work queue will continue to block new submissions after all items have drained.

Return values

- `1` – if call had to wait for the drain to complete
- `0` – if call did not have to wait
- `negative` – if wait was interrupted or failed
int k_work_queue_unplug(struct k_work_q *queue)
Release a work queue to accept new submissions.
This releases the block on new submissions placed when k_work_queue_drain() is invoked with the plug option enabled. If this is invoked before the drain completes new items may be submitted as soon as the drain completes.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**
- queue – pointer to the queue structure.

**Return values**
- 0 – if successfully unplugged
- -EALREADY – if the work queue was not plugged.

void k_work_init_delayable(struct k_work_delayable *dwork, k_work_handler_t handler)
Initialize a delayable work structure.
This must be invoked before scheduling a delayable work structure for the first time. It need not be invoked again on the same work structure. It can be re-invoked to change the associated handler, but this must be done when the work item is idle.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**
- dwork – the delayable work structure to be initialized.
- handler – the handler to be invoked by the work item.

static inline struct k_work_delayable *k_work_delayable_from_work(struct k_work *work)
Get the parent delayable work structure from a work pointer.
This function is necessary when a k_work_handler_t function is passed to k_work_schedule_for_queue() and the handler needs to access data from the container of the containing k_work_delayable.

**Parameters**
- work – Address passed to the work handler

**Returns**
Address of the containing k_work_delayable structure.

int k_work_delayable_busy_get(const struct k_work_delayable *dwork)
Busy state flags from the delayable work item.

**Function properties (list may not be complete)**

*isr-ok*

**Note:** This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.
Parameters
  • dwork – pointer to the delayable work item.

Returns
  a mask of flags K_WORK_DELAYED, K_WORK_QUEUED, K_WORK_RUNNING, and K_WORK_CANCELING. A zero return value indicates the work item appears to be idle.

static inline bool k_work_delayable_is_pending(const struct k_work_delayable *dwork)
Test whether a delayed work item is currently pending.
Wrapper to determine whether a delayed work item is in a non-idle state.

Function properties (list may not be complete)
  isr-ok

Note: This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

Parameters
  • dwork – pointer to the delayable work item.

Returns
  true if and only if k_work_delayable_busy_get() returns a non-zero value.

static inline k_ticks_t k_work_delayable_expires_get(const struct k_work_delayable *dwork)
Get the absolute tick count at which a scheduled delayable work will be submitted.

Function properties (list may not be complete)
  isr-ok

Note: This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.

Parameters
  • dwork – pointer to the delayable work item.

Returns
  the tick count when the timer that will schedule the work item will expire, or the current tick count if the work is not scheduled.

static inline k_ticks_t k_work_delayable_remaining_get(const struct k_work_delayable *dwork)
Get the number of ticks until a scheduled delayable work will be submitted.

Function properties (list may not be complete)
  isr-ok

Note: This is a live snapshot of state, which may change before the result can be inspected. Use locks where appropriate.
Parameters

- dwork – pointer to the delayable work item.

Returns

the number of ticks until the timer that will schedule the work item will expire, or zero if the item is not scheduled.

#include <k_work.h>

int k_work_schedule_for_queue(struct k_work_q *queue, struct k_work_delayable *dwork, k_timeout_t delay)

Submit an idle work item to a queue after a delay.

Unlike k_work_reschedule_for_queue() this is a no-op if the work item is already scheduled or submitted, even if delay is K_NO_WAIT.

Function properties (list may not be complete)

isr-ok

Parameters

- queue – the queue on which the work item should be submitted after the delay.
- dwork – pointer to the delayable work item.
- delay – the time to wait before submitting the work item. If K_NO_WAIT and the work is not pending this is equivalent to k_work_submit_to_queue().

Return values

- 0 – if work was already scheduled or submitted.
- 1 – if work has been scheduled.
- -EBUSY – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.
- -EINVAL – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.
- -ENODEV – if delay is K_NO_WAIT and k_work_submit_to_queue() fails with this code.

#include <k_work.h>

int k_work_schedule(struct k_work_delayable *dwork, k_timeout_t delay)

Submit an idle work item to the system work queue after a delay.

This is a thin wrapper around k_work_schedule_for_queue(), with all the API characteristics of that function.

Parameters

- dwork – pointer to the delayable work item.
- delay – the time to wait before submitting the work item. If K_NO_WAIT this is equivalent to k_work_submit_to_queue().

Returns

as with k_work_schedule_for_queue().

#include <k_work.h>

int k_work_reschedule_for_queue(struct k_work_q *queue, struct k_work_delayable *dwork, k_timeout_t delay)

Reschedule a work item to a queue after a delay.

Unlike k_work_schedule_for_queue() this function can change the deadline of a scheduled work item, and will schedule a work item that isn't idle (e.g. is submitted or running). This function does not affect ("unsubmit") a work item that has been submitted to a queue.
Function properties (list may not be complete)

\textbullet{} \textit{isr-ok}

\underline{Note:} If \texttt{delay} is \texttt{K\_NO\_WAIT} ("no delay") the return values are as with \texttt{k\_work\_submit\_to\_queue()}. 

\textbf{Parameters}

- \texttt{queue} – the queue on which the work item should be submitted after the delay.
- \texttt{dwork} – pointer to the delayable work item.
- \texttt{delay} – the time to wait before submitting the work item. If \texttt{K\_NO\_WAIT} this is equivalent to \texttt{k\_work\_submit\_to\_queue()} after canceling any previous scheduled submission.

\textbf{Return values}

- \texttt{0} – if \texttt{delay} is \texttt{K\_NO\_WAIT} and work was already on a queue
- \texttt{1} – if
  - delay is \texttt{K\_NO\_WAIT} and work was not submitted but has now been queued to queue; or
  - delay not \texttt{K\_NO\_WAIT} and work has been scheduled
- \texttt{2} – if delay is \texttt{K\_NO\_WAIT} and work was running and has been queued to the queue that was running it
- \texttt{-EBUSY} – if delay is \texttt{K\_NO\_WAIT} and \texttt{k\_work\_submit\_to\_queue()} fails with this code.
- \texttt{-EINVAL} – if delay is \texttt{K\_NO\_WAIT} and \texttt{k\_work\_submit\_to\_queue()} fails with this code.
- \texttt{-ENODEV} – if delay is \texttt{K\_NO\_WAIT} and \texttt{k\_work\_submit\_to\_queue()} fails with this code.

\begin{verbatim}
int k_work_reschedule(struct k_work_delayable *dwork, k_timeout_t delay)

Reschedule a work item to the system work queue after a delay.

This is a thin wrapper around \texttt{k\_work\_reschedule\_for\_queue()}, with all the API characteristics of that function.

\textbf{Parameters}

- \texttt{dwork} – pointer to the delayable work item.
- \texttt{delay} – the time to wait before submitting the work item.

\textbf{Returns}

as with \texttt{k\_work\_reschedule\_for\_queue()}. 
\end{verbatim}

\begin{verbatim}
bool k_work_flush_delayable(struct k_work_delayable *dwork, struct k_work_sync *sync)

Flush delayable work.

If the work is scheduled, it is immediately submitted. Then the caller blocks until the work completes, as with \texttt{k\_work\_flush()}. 

\underline{Note:} Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume. 
\end{verbatim}
**Note:** Behavior is undefined if this function is invoked on `dwork` from a work queue running `dwork`.

**Parameters**

- `dwork` – pointer to the delayable work item.
- `sync` – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

**Return values**

- `true` – if call had to wait for completion
- `false` – if work was already idle

```c
int k_work_cancel_delayable(struct k_work_delayable *dwork)
```

Cancel delayable work.

Similar to `k_work_cancel()` but for delayable work. If the work is scheduled or submitted it is canceled. This function does not wait for the cancellation to complete.

**Function properties (list may not be complete)**

- `isr-ok`

**Note:** The work may still be running when this returns. Use `k_work_flush_delayable()` or `k_work_cancel_delayable_sync()` to ensure it is not running.

**Note:** Canceling delayable work does not prevent rescheduling it. It does prevent submitting it until the cancellation completes.

**Parameters**

- `dwork` – pointer to the delayable work item.

**Returns**

the `k_work_delayable_busy_get()` status indicating the state of the item after all cancellation steps performed by this call are completed.

```c
bool k_work_cancel_delayable_sync(struct k_work_delayable *dwork, struct k_work_sync *sync)
```

Cancel delayable work and wait.

Like `k_work_cancel_delayable()` but waits until the work becomes idle.

**Note:** Canceling delayable work does not prevent rescheduling it. It does prevent submitting it until the cancellation completes.
Note: Be careful of caller and work queue thread relative priority. If this function sleeps it will not return until the work queue thread completes the tasks that allow this thread to resume.

Note: Behavior is undefined if this function is invoked on dwork from a work queue running dwork.

Parameters

- dwork – pointer to the delayable work item.
- sync – pointer to an opaque item containing state related to the pending cancellation. The object must persist until the call returns, and be accessible from both the caller thread and the work queue thread. The object must not be used for any other flush or cancel operation until this one completes. On architectures with CONFIG_KERNEL_COHERENCE the object must be allocated in coherent memory.

Return values

- true – if work was not idle (call had to wait for cancellation of a running handler to complete, or scheduled or submitted operations were cancelled);
- false – otherwise

static inline void k_work_user_init(struct k_work_user *work, k_work_user_handler_t handler)

Initialize a userspace work item.

This routine initializes a user workqueue work item, prior to its first use.

Parameters

- work – Address of work item.
- handler – Function to invoke each time work item is processed.

static inline bool k_work_user_is_pending(struct k_work_user *work)

Check if a userspace work item is pending.

This routine indicates if user work item work is pending in a workqueue’s queue.

Function properties (list may not be complete)

- isr-ok

Note: Checking if the work is pending gives no guarantee that the work will still be pending when this information is used. It is up to the caller to make sure that this information is used in a safe manner.

Parameters

- work – Address of work item.

Returns

true if work item is pending, or false if it is not pending.
static inline int k_work_user_submit_to_queue(struct k_work_user_q *work_q, struct k_work_user *work)

Submit a work item to a user mode workqueue.
Submits a work item to a workqueue that runs in user mode. A temporary memory allocation is made from the caller's resource pool which is freed once the worker thread consumes the k_work item. The workqueue thread must have memory access to the k_work item being submitted. The caller must have permission granted on the work_q parameter's queue object.

Function properties (list may not be complete)

  isr-ok

Parameters

  • work_q – Address of workqueue.
  • work – Address of work item.

Return values

  • -EBUSY – if the work item was already in some workqueue
  • -ENOMEM – if no memory for thread resource pool allocation
  • 0 – Success

void k_work_user_queue_start(struct k_work_user_q *work_q, k_thread_stack_t *stack, size_t stack_size, int prio, const char *name)

Start a workqueue in user mode.
This works identically to k_work_queue_start() except it is callable from user mode, and the worker thread created will run in user mode. The caller must have permissions granted on both the work_q parameter's thread and queue objects, and the same restrictions on priority apply as k_thread_create().

Parameters

  • work_q – Address of workqueue.
  • stack – Pointer to work queue thread's stack space, as defined by K_THREAD_STACK_DEFINE()
  • stack_size – Size of the work queue thread's stack (in bytes), which should either be the same constant passed to K_THREAD_STACK_DEFINE() or the value of K_THREAD_STACK_SIZEOF().
  • prio – Priority of the work queue's thread.
  • name – optional thread name. If not null a copy is made into the thread's name buffer.

static inline k_tid_t k_work_user_queue_thread_get(struct k_work_user_q *work_q)

Access the user mode thread that animates a work queue.
This is necessary to grant a user mode work queue thread access to things the work items it will process are expected to use.

Parameters

  • work_q – pointer to the user mode queue structure.

Returns

  the user mode thread associated with the work queue.
void k_work_poll_init(struct k_work_poll *work, k_work_handler_t handler)

Initialize a triggered work item.

This routine initializes a workqueue triggered work item, prior to its first use.

Parameters

• work – Address of triggered work item.
• handler – Function to invoke each time work item is processed.

int k_work_poll_submit_to_queue(struct k_work_q *work_q, struct k_work_poll *work, struct k_poll_event *events, int num_events, k_timeout_t timeout)

Submit a triggered work item.

This routine schedules work item work to be processed by workqueue work_q when one of the given events is signaled. The routine initiates internal poller for the work item and then returns to the caller. Only when one of the watched events happen the work item is actually submitted to the workqueue and becomes pending.

Submitting a previously submitted triggered work item that is still waiting for the event cancels the existing submission and reschedules it the using the new event list. Note that this behavior is inherently subject to race conditions with the pre-existing triggered work item and work queue, so care must be taken to synchronize such resubmissions externally.

Function properties (list may not be complete)

isr-ok

Warning: Provided array of events as well as a triggered work item must be placed in persistent memory (valid until work handler execution or work cancellation) and cannot be modified after submission.

Parameters

• work_q – Address of workqueue.
• work – Address of delayed work item.
• events – An array of events which trigger the work.
• num_events – The number of events in the array.
• timeout – Timeout after which the work will be scheduled for execution even if not triggered.

Return values

• 0 – Work item started watching for events.
• -EINVAL – Work item is being processed or has completed its work.
• -EADDRINUSE – Work item is pending on a different workqueue.

int k_work_poll_submit(struct k_work_poll *work, struct k_poll_event *events, int num_events, k_timeout_t timeout)

Submit a triggered work item to the system workqueue.

This routine schedules work item work to be processed by system workqueue when one of the given events is signaled. The routine initiates internal poller for the work item and then returns to the caller. Only when one of the watched events happen the work item is actually submitted to the workqueue and becomes pending.

Submitting a previously submitted triggered work item that is still waiting for the event cancels the existing submission and reschedules it the using the new event list. Note that this
behavior is inherently subject to race conditions with the pre-existing triggered work item and work queue, so care must be taken to synchronize such resubmissions externally.

**Function properties (list may not be complete)**

`isr-ok`

**Warning:** Provided array of events as well as a triggered work item must not be modified until the item has been processed by the workqueue.

**Parameters**

- `work` – Address of delayed work item.
- `events` – An array of events which trigger the work.
- `num_events` – The number of events in the array.
- `timeout` – Timeout after which the work will be scheduled for execution even if not triggered.

**Return values**

- `0` – Work item started watching for events.
- `-EINVAL` – Work item is being processed or has completed its work.
- `-EADDRINUSE` – Work item is pending on a different workqueue.

```c
int k_work_poll_cancel(struct k_work_poll *work)
```

Cancel a triggered work item.

This routine cancels the submission of triggered work item `work`. A triggered work item can only be canceled if no event triggered work submission.

**Function properties (list may not be complete)**

`isr-ok`

**Parameters**

- `work` – Address of delayed work item.

**Return values**

- `0` – Work item canceled.
- `-EINVAL` – Work item is being processed or has completed its work.

```c
struct k_work_poll
#include <kernel.h> A structure used to submit work.
```

```c
struct k_work_delayable
#include <kernel.h> A structure used to submit work after a delay.
```

```c
struct k_work_sync
#include <kernel.h> A structure holding internal state for a pending synchronous operation on a work item or queue.
```
Instances of this type are provided by the caller for invocation of `k_work_flush()`, `k_work_cancel_sync()` and sibling flush and cancel APIs. A referenced object must persist until the call returns, and be accessible from both the caller thread and the work queue thread.

**Note:** If CONFIG_KERNEL_COHERENCE is enabled the object must be allocated in coherent memory; see `arch_mem_coherent()`. The stack on these architectures is generally not coherent. be stack-allocated. Violations are detected by runtime assertion.

```
struct k_work_queue_config
#include <kernel.h> A structure holding optional configuration items for a work queue.
This structure, and values it references, are not retained by `k_work_queue_start()`.

Public Members

const char *name
The name to be given to the work queue thread.
If left null the thread will not have a name.

bool no_yield
Control whether the work queue thread should yield between items.
Yielding between items helps guarantee the work queue thread does not starve other
threads, including cooperative ones released by a work item. This is the default behavior.
Set this to `true` to prevent the work queue thread from yielding between items. This may
be appropriate when a sequence of items should complete without yielding control.

struct k_work_q
#include <kernel.h> A structure used to hold work until it can be processed.
```

### Operation without Threads

Thread support is not necessary in some applications:

- Bootloaders
- Simple event-driven applications
- Examples intended to demonstrate core functionality

Thread support can be disabled by setting `CONFIG_MULTITHREADING` to `n`. Since this configuration has a significant impact on Zephyr's functionality and testing of it has been limited, there are conditions on what can be expected to work in this configuration.

**What Can be Expected to Work** These core capabilities shall function correctly when `CONFIG_MULTITHREADING` is disabled:

- The **build system**
- The ability to boot the application to `main()`
- **Interrupt management**
- The system clock including `k_uptime_get()`
- Timers, i.e. `k_timer()`

---

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• Non-sleeping delays e.g. `k_busy_wait()`.
• Sleeping `k_cpu_idle()`.
• Pre `main()` drivers and subsystems initialization e.g. `SYS_INIT`.

**Memory Management**

• Specifically identified drivers in certain subsystems, listed below.

The expectations above affect selection of other features; for example `CONFIG_SYS_CLOCK_EXISTS` cannot be set to `n`.

**What Cannot be Expected to Work** Functionality that will not work with `CONFIG_MULTITHREADING` includes majority of the kernel API:

• **Threads**
• **Scheduling**
• **Workqueue Threads**
• **Polling API**
• **Semaphores**
• **Mutexes**
• **Condition Variables**
• **Data Passing**

**Subsystem Behavior Without Thread Support** The sections below list driver and functional subsystems that are expected to work to some degree when `CONFIG_MULTITHREADING` is disabled. Subsystems that are not listed here should not be expected to work.

Some existing drivers within the listed subsystems do not work when threading is disabled, but are within scope based on their subsystem, or may be sufficiently isolated that supporting them on a particular platform is low-impact. Enhancements to add support to existing capabilities that were not originally implemented to work with threads disabled will be considered.

**Flash** The Flash is expected to work for all SoC flash peripheral drivers. Bus-accessed devices like serial memories may not be supported.

*List/table of supported drivers to go here*

**GPIO** The GPIO is expected to work for all SoC GPIO peripheral drivers. Bus-accessed devices like GPIO extenders may not be supported.

*List/table of supported drivers to go here*

**UART** A subset of the UART is expected to work for all SoC UART peripheral drivers.

• Applications that select `CONFIG_UART_INTERRUPT_DRIVEN` may work, depending on driver implementation.
• Applications that select `CONFIG_UART_ASYNC_API` may work, depending on driver implementation.
• Applications that do not select either `CONFIG_UART_ASYNC_API` or `CONFIG_UART_INTERRUPT_DRIVEN` are expected to work.

*List/table of supported drivers to go here, including which API options are supported*
Interrupts

An interrupt service routine (ISR) is a function that executes asynchronously in response to a hardware or software interrupt. An ISR normally preempts the execution of the current thread, allowing the response to occur with very low overhead. Thread execution resumes only once all ISR work has been completed.

- Concepts
  - Multi-level Interrupt handling
  - Preventing Interruptions
  - Offloading ISR Work
- Implementation
  - Defining a regular ISR
  - Defining a ‘direct’ ISR
  - Implementation Details
- Suggested Uses
- Configuration Options
- API Reference

Concepts  Any number of ISRs can be defined (limited only by available RAM), subject to the constraints imposed by underlying hardware.

An ISR has the following key properties:

- An interrupt request (IRQ) signal that triggers the ISR.
- A priority level associated with the IRQ.
- An interrupt handler function that is invoked to handle the interrupt.
- An argument value that is passed to that function.

An IDT (Interrupt Descriptor Table) or a vector table is used to associate a given interrupt source with a given ISR. Only a single ISR can be associated with a specific IRQ at any given time.

Multiple ISRs can utilize the same function to process interrupts, allowing a single function to service a device that generates multiple types of interrupts or to service multiple devices (usually of the same type). The argument value passed to an ISR's function allows the function to determine which interrupt has been signaled.

The kernel provides a default ISR for all unused IDT entries. This ISR generates a fatal system error if an unexpected interrupt is signaled.

The kernel supports interrupt nesting. This allows an ISR to be preempted in mid-execution if a higher priority interrupt is signaled. The lower priority ISR resumes execution once the higher priority ISR has completed its processing.

An ISR's interrupt handler function executes in the kernel's interrupt context. This context has its own dedicated stack area (or, on some architectures, stack areas). The size of the interrupt context stack must be capable of handling the execution of multiple concurrent ISRs if interrupt nesting support is enabled.

Important: Many kernel APIs can be used only by threads, and not by ISRs. In cases where a routine may be invoked by both threads and ISRs the kernel provides the `k_ts_in_isr()` API to allow the routine to alter its behavior depending on whether it is executing as part of a thread or as part of an ISR.
Multi-level Interrupt handling  A hardware platform can support more interrupt lines than natively-provided through the use of one or more nested interrupt controllers. Sources of hardware interrupts are combined into one line that is then routed to the parent controller.

If nested interrupt controllers are supported, `CONFIG_MULTI_LEVEL_INTERRUPTS` should be set to 1, and `CONFIG_2ND_LEVEL_INTERRUPTS` and `CONFIG_3RD_LEVEL_INTERRUPTS` configured as well, based on the hardware architecture.

A unique 32-bit interrupt number is assigned with information embedded in it to select and invoke the correct Interrupt Service Routine (ISR). Each interrupt level is given a byte within this 32-bit number, providing support for up to four interrupt levels using this arch, as illustrated and explained below:

|   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
| 9 | 2 | 0 |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
|   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
| 5 |   | A |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
|   |   | C | B |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
|   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |
|   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |

|   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |   |

There are three interrupt levels shown here.

- ‘-’ means interrupt line and is numbered from 0 (right most).
- LEVEL 1 has 12 interrupt lines, with two lines (2 and 9) connected to nested controllers and one device ‘A’ on line 4.
- One of the LEVEL 2 controllers has interrupt line 5 connected to a LEVEL 3 nested controller and one device ‘C’ on line 3.
- The other LEVEL 2 controller has no nested controllers but has one device ‘B’ on line 2.
- The LEVEL 3 controller has one device ‘D’ on line 2.

Here’s how unique interrupt numbers are generated for each hardware interrupt. Let’s consider four interrupts shown above as A, B, C, and D:

- A -> 0x00000004
- B -> 0x00000002
- C -> 0x00000049
- D -> 0x00003069

**Note:** The bit positions for LEVEL 2 and onward are offset by 1, as 0 means that interrupt number is not present for that level. For our example, the LEVEL 3 controller has device D on line 2, connected to the LEVEL 2 controller’s line 5, that is connected to the LEVEL 1 controller’s line 9 (2 -> 5 -> 9). Because of the encoding offset for LEVEL 2 and onward, device D is given the number 0x00030609.

Preventing Interruptions  In certain situations it may be necessary for the current thread to prevent ISRs from executing while it is performing time-sensitive or critical section operations.

A thread may temporarily prevent all IRQ handling in the system using an **IRQ lock**. This lock can be applied even when it is already in effect, so routines can use it without having to know if it is already in effect. The thread must unlock its IRQ lock the same number of times it was locked before interrupts can be once again processed by the kernel while the thread is running.

**Important:** The IRQ lock is thread-specific. If thread A locks out interrupts then performs an operation that puts itself to sleep (e.g. sleeping for N milliseconds), the thread’s IRQ lock no longer applies once thread A is swapped out and the next ready thread B starts to run.
This means that interrupts can be processed while thread B is running unless thread B has also locked out interrupts using its own IRQ lock. (Whether interrupts can be processed while the kernel is switching between two threads that are using the IRQ lock is architecture-specific.)

When thread A eventually becomes the current thread once again, the kernel re-establishes thread A’s IRQ lock. This ensures thread A won’t be interrupted until it has explicitly unlocked its IRQ lock.

If thread A does not sleep but does make a higher-priority thread B ready, the IRQ lock will inhibit any preemption that would otherwise occur. Thread B will not run until the next reschedule point reached after releasing the IRQ lock.

Alternatively, a thread may temporarily disable a specified IRQ so its associated ISR does not execute when the IRQ is signaled. The IRQ must be subsequently enabled to permit the ISR to execute.

**Important:** Disabling an IRQ prevents all threads in the system from being preempted by the associated ISR, not just the thread that disabled the IRQ.

---

**Zero Latency Interrupts** Preventing interruptions by applying an IRQ lock may increase the observed interrupt latency. A high interrupt latency, however, may not be acceptable for certain low-latency use-cases.

The kernel addresses such use-cases by allowing interrupts with critical latency constraints to execute at a priority level that cannot be blocked by interrupt locking. These interrupts are defined as zero-latency interrupts. The support for zero-latency interrupts requires `CONFIG_ZERO_LATENCY_IRQS` to be enabled. In addition to that, the flag `IRQ_ZERO_LATENCY` must be passed to `IRQ_CONNECT` or `IRQ_DIRECT_CONNECT` macros to configure the particular interrupt with zero latency.

Zero-latency interrupts are expected to be used to manage hardware events directly, and not to interoperate with the kernel code at all. They should treat all kernel APIs as undefined behavior (i.e. an application that uses the APIs inside a zero-latency interrupt context is responsible for directly verifying correct behavior). Zero-latency interrupts may not modify any data inspected by kernel APIs invoked from normal Zephyr contexts and shall not generate exceptions that need to be handled synchronously (e.g. kernel panic).

**Important:** Zero-latency interrupts are supported on an architecture-specific basis. The feature is currently implemented in the ARM Cortex-M architecture variant.

---

**Offloading ISR Work** An ISR should execute quickly to ensure predictable system operation. If time consuming processing is required the ISR should offload some or all processing to a thread, thereby restoring the kernel’s ability to respond to other interrupts.

The kernel supports several mechanisms for offloading interrupt-related processing to a thread.

- An ISR can signal a helper thread to do interrupt-related processing using a kernel object, such as a FIFO, LIFO, or semaphore.
- An ISR can instruct the system workqueue thread to execute a work item. (See Workqueue Threads.)

When an ISR offloads work to a thread, there is typically a single context switch to that thread when the ISR completes, allowing interrupt-related processing to continue almost immediately. However, depending on the priority of the thread handling the offload, it is possible that the currently executing cooperative thread or other higher-priority threads may execute before the thread handling the offload is scheduled.

---

3.1. Kernel Services
Defining a regular ISR  

An ISR is defined at runtime by calling `IRQ_CONNECT`. It must then be enabled by calling `irq_enable()`.

**Important:** `IRQ_CONNECT()` is not a C function and does some inline assembly magic behind the scenes. All its arguments must be known at build time. Drivers that have multiple instances may need to define per-instance config functions to configure each instance of the interrupt.

The following code defines and enables an ISR.

```c
#define MY_DEV_IRQ 24 /* device uses IRQ 24 */
#define MY_DEV_PRIO 2 /* device uses interrupt priority 2 */
/* argument passed to my_isr(), in this case a pointer to the device */
#define MY_ISR_ARG DEVICE_GET(my_device)
#define MY_IRQ_FLAGS 0 /* IRQ flags */

void my_isr(void *arg)
{
    /* ISR code */
}

void my_isr_installer(void)
{
    ... irq_connect(MY_DEV_IRQ, MY_DEV_PRIO, my_isr, MY_ISR_ARG, MY_IRQ_FLAGS);
    irq_enable(MY_DEV_IRQ);
    ...
}
```

Since the `IRQ_CONNECT` macro requires that all its parameters be known at build time, in some cases this may not be acceptable. It is also possible to install interrupts at runtime with `irq_connect_dynamic()`.

It is used in exactly the same way as `IRQ_CONNECT`:

```c
void my_isr_installer(void)
{
    ... irq_connect_dynamic(MY_DEV_IRQ, MY_DEV_PRIO, my_isr, MY_ISR_ARG, MY_IRQ_FLAGS);
    irq_enable(MY_DEV_IRQ);
    ...
}
```

Dynamic interrupts require the `CONFIG_DYNAMIC_INTERRUPTS` option to be enabled. Removing or re-configuring a dynamic interrupt is currently unsupported.

**Defining a ‘direct’ ISR**  

Regular Zephyr interrupts introduce some overhead which may be unacceptable for some low-latency use-cases. Specifically:

- The argument to the ISR is retrieved and passed to the ISR
- If power management is enabled and the system was idle, all the hardware will be resumed from low-power state before the ISR is executed, which can be very time-consuming
- Although some architectures will do this in hardware, other architectures need to switch to the interrupt stack in code
- After the interrupt is serviced, the OS then performs some logic to potentially make a scheduling decision.
Zephyr supports so-called ‘direct’ interrupts, which are installed via `IRQ_DIRECT_CONNECT`. These direct interrupts have some special implementation requirements and a reduced feature set; see the definition of `IRQ_DIRECT_CONNECT` for details.

The following code demonstrates a direct ISR:

```c
#define MY_DEV_IRQ 24 /* device uses IRQ 24 */
#define MY_DEV_PRIO 2 /* device uses interrupt priority 2 */
/* argument passed to my_isr(), in this case a pointer to the device */
#define MY_IRQ_FLAGS 0 /* IRQ flags */

ISR_DIRECT_DECLARE(my_isr)
{
    do_stuff();
    ISR_DIRECT_PM(); /* PM done after servicing interrupt for best latency */
    return 1; /* We should check if scheduling decision should be made */
}

void my_isr_installer(void)
{
    ...
    IRQ_DIRECT_CONNECT(MY_DEV_IRQ, MY_DEV_PRIO, my_isr, MY_IRQ_FLAGS);
    irq_enable(MY_DEV_IRQ);
    ...
}
```

Installation of dynamic direct interrupts is supported on an architecture-specific basis. (The feature is currently implemented in ARM Cortex-M architecture variant. Dynamic direct interrupts feature is exposed to the user via an ARM-only API.)

**Implementation Details** Interrupt tables are set up at build time using some special build tools. The details laid out here apply to all architectures except x86, which are covered in the x86 Details section below.

Any invocation of `IRQ_CONNECT` will declare an instance of struct `_isr_list` which is placed in a special .intList section:

```c
struct _isr_list {
    /** IRQ line number */
    int32_t irq;
    /** Flags for this IRQ, see ISR_FLAG_* definitions */
    int32_t flags;
    /** ISR to call */
    void *func;
    /** Parameter for non-direct IRQs */
    void *param;
};
```

Zephyr is built in two phases; the first phase of the build produces `${ZEPHYR_PREBUILT_EXECUTABLE}.elf` which contains all the entries in the .intList section preceded by a header:

```c
struct {
    void *spurious_irq_handler;
    void *sw_irq_handler;
    uint32_t num_isr;
    uint32_t num_vectors;
    struct _isr_list isrs[]; /* of size num_isr */
};
```
This data consisting of the header and instances of struct _isr_list inside 
${ZEPHYR_PREBUILT_EXECUTABLE}.elf is then used by the gen_isr_tables.py script to generate a C file defining a vector table and software ISR table that are then compiled and linked into the final application.

The priority level of any interrupt is not encoded in these tables, instead IRQ_CONNECT also has a runtime component which programs the desired priority level of the interrupt to the interrupt controller. Some architectures do not support the notion of interrupt priority, in which case the priority argument is ignored.

Vector Table  A vector table is generated when CONFIG_GEN_IRQ_VECTOR_TABLE is enabled. This data structure is used natively by the CPU and is simply an array of function pointers, where each element n corresponds to the IRQ handler for IRQ line n, and the function pointers are:

1. For 'direct' interrupts declared with IRQ_DIRECT_CONNECT, the handler function will be placed here.

2. For regular interrupts declared with IRQ_CONNECT, the address of the common software IRQ handler is placed here. This code does common kernel interrupt bookkeeping and looks up the ISR and parameter from the software ISR table.

3. For interrupt lines that are not configured at all, the address of the spurious IRQ handler will be placed here. The spurious IRQ handler causes a system fatal error if encountered.

Some architectures (such as the Nios II internal interrupt controller) have a common entry point for all interrupts and do not support a vector table, in which case the CONFIG_GEN_IRQ_VECTOR_TABLE option should be disabled.

Some architectures may reserve some initial vectors for system exceptions and declare this in a table elsewhere, in which case CONFIG_GEN_IRQ_START_VECTOR needs to be set to properly offset the indices in the table.

SW ISR Table  This is an array of struct _isr_table_entry:

```
struct _isr_table_entry {
    void *arg;
    void (*isr)(void *);
};
```

This is used by the common software IRQ handler to look up the ISR and its argument and execute it. The active IRQ line is looked up in an interrupt controller register and used to index this table.

x86 Details  The x86 architecture has a special type of vector table called the Interrupt Descriptor Table (IDT) which must be laid out in a certain way per the x86 processor documentation. It is still fundamentally a vector table, and the arch/x86/gen_idt.py tool uses the .intList section to create it. However, on APIC-based systems the indexes in the vector table do not correspond to the IRQ line. The first 32 vectors are reserved for CPU exceptions, and all remaining vectors (up to index 255) correspond to the priority level, in groups of 16. In this scheme, interrupts of priority level 0 will be placed in vectors 32-47, level 1 48-63, and so forth. When the arch/x86/gen_idt.py tool is constructing the IDT, when it configures an interrupt it will look for a free vector in the appropriate range for the requested priority level and set the handler there.

On x86 when an interrupt or exception vector is executed by the CPU, there is no foolproof way to determine which vector was fired, so a software ISR table indexed by IRQ line is not used. Instead, the IRQ_CONNECT call creates a small assembly language function which calls the common interrupt code in _interrupt_enter() with the ISR and parameter as arguments. It is the address of this assembly interrupt stub which gets placed in the IDT. For interrupts declared with IRQ_DIRECT_CONNECT the parameterless ISR is placed directly in the IDT.
On systems where the position in the vector table corresponds to the interrupt’s priority level, the interrupt controller needs to know at runtime what vector is associated with an IRQ line. `arch/x86/gen_idt.py` additionally creates an `_irq_to_interrupt_vector` array which maps an IRQ line to its configured vector in the IDT. This is used at runtime by `IRQ_CONNECT` to program the IRQ-to-vector association in the interrupt controller.

For dynamic interrupts, the build must generate some 4-byte dynamic interrupt stubs, one stub per dynamic interrupt in use. The number of stubs is controlled by the `CONFIG_X86_DYNAMIC_IRQ_STUBS` option. Each stub pushes an unique identifier which is then used to fetch the appropriate handler function and parameter out of a table populated when the dynamic interrupt was connected.

**Suggested Uses** Use a regular or direct ISR to perform interrupt processing that requires a very rapid response, and can be done quickly without blocking.

**Note:** Interrupt processing that is time consuming, or involves blocking, should be handed off to a thread. See [Offloading ISR Work](#) for a description of various techniques that can be used in an application.

**Configuration Options** Related configuration options:

- `CONFIG_ISR_STACK_SIZE`

Additional architecture-specific and device-specific configuration options also exist.

**API Reference**

`group isr_apis`

**Defines**

`IRQ_CONNECT(irq_p, priority_p, isr_p, isr_param_p, flags_p)`

Initialize an interrupt handler.

This routine initializes an interrupt handler for an IRQ. The IRQ must be subsequently enabled before the interrupt handler begins servicing interrupts.

**Warning:** Although this routine is invoked at run-time, all of its arguments must be computable by the compiler at build time.

**Parameters**

- `irq_p` – IRQ line number.
- `priority_p` – Interrupt priority.
- `isr_p` – Address of interrupt service routine.
- `isr_param_p` – Parameter passed to interrupt service routine.
- `flags_p` – Architecture-specific IRQ configuration flags.

`IRQ_DIRECT_CONNECT(irq_p, priority_p, isr_p, flags_p)`

Initialize a ‘direct’ interrupt handler.

This routine initializes an interrupt handler for an IRQ. The IRQ must be subsequently enabled via `irq_enable()` before the interrupt handler begins servicing interrupts.
These ISRs are designed for performance-critical interrupt handling and do not go through common interrupt handling code. They must be implemented in such a way that it is safe to put them directly in the vector table. For ISRs written in C, the `ISR_DIRECT_DECLARE()` macro will do this automatically. For ISRs written in assembly it is entirely up to the developer to ensure that the right steps are taken.

This type of interrupt currently has a few limitations compared to normal Zephyr interrupts:

- No parameters are passed to the ISR.
- No stack switch is done, the ISR will run on the interrupted context's stack, unless the architecture automatically does the stack switch in HW.
- Interrupt locking state is unchanged from how the HW sets it when the ISR runs. On arches that enter ISRs with interrupts locked, they will remain locked.
- Scheduling decisions are now optional, controlled by the return value of ISRs implemented with the `ISR_DIRECT_DECLARE()` macro
- The call into the OS to exit power management idle state is now optional. Normal interrupts always do this before the ISR is run, but when it runs is now controlled by the placement of a `ISR_DIRECT_PM()` macro, or omitted entirely.

**Warning:** Although this routine is invoked at run-time, all of its arguments must be computable by the compiler at build time.

**Parameters**

- `irq_p` – IRQ line number.
- `priority_p` – Interrupt priority.
- `isr_p` – Address of interrupt service routine.
- `flags_p` – Architecture-specific IRQ configuration flags.

**ISR_DIRECT_HEADER()**

Common tasks before executing the body of an ISR.

This macro must be at the beginning of all direct interrupts and performs minimal architecture-specific tasks before the ISR itself can run. It takes no arguments and has no return value.

**ISR_DIRECT_FOOTER(check_reschedule)**

Common tasks before exiting the body of an ISR.

This macro must be at the end of all direct interrupts and performs minimal architecture-specific tasks like EOI. It has no return value.

In a normal interrupt, a check is done at end of interrupt to invoke z_swap() logic if the current thread is preemptible and there is another thread ready to run in the kernel's ready queue cache. This is now optional and controlled by the check_reschedule argument. If unsure, set to nonzero. On systems that do stack switching and nested interrupt tracking in software, z_swap() should only be called if this was a non-nested interrupt.

**Parameters**

- `check_reschedule` – If nonzero, additionally invoke scheduling logic

**ISR_DIRECT_PM()**

Perform power management idle exit logic.

This macro may optionally be invoked somewhere in between `IRQ_DIRECT_HEADER()` and `IRQ_DIRECT_FOOTER()` invocations. It performs tasks necessary to exit power management idle state. It takes no parameters and returns no arguments. It may be omitted, but be careful!
ISR_DIRECT_DECLARE(name)

Helper macro to declare a direct interrupt service routine.

This will declare the function in a proper way and automatically include the ISR_DIRECT_FOOTER() and ISR_DIRECT_HEADER() macros. The function should return nonzero status if a scheduling decision should potentially be made. See ISR_DIRECT_FOOTER() for more details on the scheduling decision.

For architectures that support 'regular' and 'fast' interrupt types, where these interrupt types require different assembly language handling of registers by the ISR, this will always generate code for the 'fast' interrupt type.

Example usage:

ISR_DIRECT_DECLARE(my_isr)
{
  bool done = do_stuff();
  ISR_DIRECT_PM(); // done after do_stuff() due to latency concerns
  if (!done) {
    return 0; // don't bother checking if we have to z_swap()
  }

  k_sem_give(some_sem);
  return 1;
}

Parameters

- name – symbol name of the ISR

irq_lock()

Lock interrupts.

This routine disables all interrupts on the CPU. It returns an unsigned integer “lock-out key”, which is an architecture-dependent indicator of whether interrupts were locked prior to the call. The lock-out key must be passed to irq_unlock() to re-enable interrupts.

This routine can be called recursively, as long as the caller keeps track of each lock-out key that is generated. Interrupts are re-enabled by passing each of the keys to irq_unlock() in the reverse order they were acquired. (That is, each call to irq_lock() must be balanced by a corresponding call to irq_unlock().)

This routine can only be invoked from supervisor mode. Some architectures (for example, ARM) will fail silently if invoked from user mode instead of generating an exception.

Note: This routine must also serve as a memory barrier to ensure the uniprocessor implementation of k_spinlock_t is correct.

Note: This routine can be called by ISRs or by threads. If it is called by a thread, the interrupt lock is thread-specific; this means that interrupts remain disabled only while the thread is running. If the thread performs an operation that allows another thread to run (for example, giving a semaphore or sleeping for N milliseconds), the interrupt lock no longer applies and interrupts may be re-enabled while other processing occurs. When the thread once again becomes the current thread, the kernel re-establishes its interrupt lock; this ensures the thread won’t be interrupted until it has explicitly released the interrupt lock it established.
Warning: The lock-out key should never be used to manually re-enable interrupts or to inspect or manipulate the contents of the CPU’s interrupt bits.

Returns
An architecture-dependent lock-out key representing the “interrupt disable state” prior to the call.

irq_unlock(key)
Unlock interrupts.
This routine reverses the effect of a previous call to irq_lock() using the associated lock-out key. The caller must call the routine once for each time it called irq_lock(), supplying the keys in the reverse order they were acquired, before interrupts are enabled.

This routine can only be invoked from supervisor mode. Some architectures (for example, ARM) will fail silently if invoked from user mode instead of generating an exception.

Note: This routine must also serve as a memory barrier to ensure the uniprocessor implementation of k_spinlock_t is correct.

Note: Can be called by ISRs.

Parameters
• key – Lock-out key generated by irq_lock().

irq_enable(irq)
Enable an IRQ.
This routine enables interrupts from source irq.

Parameters
• irq – IRQ line.

irq_disable(irq)
Disable an IRQ.
This routine disables interrupts from source irq.

Parameters
• irq – IRQ line.

irq_is_enabled(irq)
Get IRQ enable state.
This routine indicates if interrupts from source irq are enabled.

Parameters
• irq – IRQ line.

Returns
interrupt enable state, true or false
Functions

static inline int irq_connect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)

Configure a dynamic interrupt.
Use this instead of IRQ_CONNECT() if arguments cannot be known at build time.

Parameters
• irq – IRQ line number
• priority – Interrupt priority
• routine – Interrupt service routine
• parameter – ISR parameter
• flags – Arch-specific IRQ configuration flags

Returns
The vector assigned to this interrupt

static inline unsigned int irq_get_level(unsigned int irq)

Return IRQ level This routine returns the interrupt level number of the provided interrupt.

Parameters
• irq – IRQ number in its zephyr format

Returns
1 if IRQ level 1, 2 if IRQ level 2, 3 if IRQ level 3

bool k_is_in_isr(void)

Determine if code is running at interrupt level.
This routine allows the caller to customize its actions, depending on whether it is a thread or an ISR.

Function properties (list may not be complete)

isr-ok

Returns
false if invoked by a thread.

Returns
true if invoked by an ISR.

int k_is_preempt_thread(void)

Determine if code is running in a preemptible thread.
This routine allows the caller to customize its actions, depending on whether it can be pre-empted by another thread. The routine returns a ‘true’ value if all of the following conditions are met:

• The code is running in a thread, not at ISR.
• The thread’s priority is in the preemptible range.
• The thread has not locked the scheduler.
Function properties (list may not be complete)

*isr-ok*

**Returns**
- 0 if invoked by an ISR or by a cooperative thread.
- Non-zero if invoked by a preemptible thread.

static inline bool k_is_pre_kernel(void)

Test whether startup is in the before-main-task phase.

This routine allows the caller to customize its actions, depending on whether it being invoked before the kernel is fully active.

Function properties (list may not be complete)

*isr-ok*

**Returns**
- true if invoked before post-kernel initialization
- false if invoked during/after post-kernel initialization

Polling API

The polling API is used to wait concurrently for any one of multiple conditions to be fulfilled.

- **Concepts**
- **Implementation**
  - Using `k_poll()`
  - Using `k_poll_signal_raise()`
- **Suggested Uses**
- **Configuration Options**
- **API Reference**

**Concepts**  The polling API's main function is `k_poll()`, which is very similar in concept to the POSIX `poll()` function, except that it operates on kernel objects rather than on file descriptors.

The polling API allows a single thread to wait concurrently for one or more conditions to be fulfilled without actively looking at each one individually.

There is a limited set of such conditions:

- a semaphore becomes available
- a kernel FIFO contains data ready to be retrieved
- a poll signal is raised

A thread that wants to wait on multiple conditions must define an array of **poll events**, one for each condition.

All events in the array must be initialized before the array can be polled on.
Each event must specify which **type** of condition must be satisfied so that its state is changed to signal the requested condition has been met.

Each event must specify what **kernel object** it wants the condition to be satisfied.

Each event can optionally specify what **mode** of operation is used when the condition is satisfied.

Apart from the kernel objects, there is also a **poll signal** pseudo-object type that be directly signaled.

The **k_poll()** function returns as soon as one of the conditions it is waiting for is fulfilled. It is possible for more than one to be fulfilled when **k_poll()** returns, if they were fulfilled before **k_poll()** was called, or due to the preemptive multi-threading nature of the kernel. The caller must look at the state of all the poll events in the array to figure out which ones were fulfilled and what actions to take.

Currently, there is only one mode of operation available: the object is not acquired. As an example, this means that when **k_poll()** returns and the poll event states that the semaphore is available, the caller of **k_poll()** must then invoke **k_sem_take()** to take ownership of the semaphore. If the semaphore is contested, there is no guarantee that it will be still available when **k_sem_take()** is called.

### Implementation

**Using k_poll()**  The main API is **k_poll()**, which operates on an array of poll events of type **k_poll_event**. Each entry in the array represents one event a call to **k_poll()** will wait for its condition to be fulfilled.

Poll events can be initialized using either the runtime initializers **K_POLL_EVENT_INITIALIZER()** or **k_poll_event_init()**, or the static initializer **K_POLL_EVENT_STATIC_INITIALIZER()**. An object that matches the **type** specified must be passed to the initializers. The **mode** must be set to **K_POLL_MODE_NOTIFY_ONLY**. The state must be set to **K_POLL_STATE_NOT_READY** (the initializers take care of this). The user **tag** is optional and completely opaque to the API: it is there to help a user to group similar events together. Being optional, it is passed to the static initializer, but not the runtime ones for performance reasons. If using runtime initializers, the user must set it separately in the **k_poll_event** data structure. If an event in the array is to be ignored, most likely temporarily, its type can be set to **K_POLL_TYPE_IGNORE**.

```c
struct k_poll_event events[2] = {
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_SEM_AVAILABLE,
        K_POLL_MODE_NOTIFY_ONLY,
        &my_sem, 0),
    K_POLL_EVENT_STATIC_INITIALIZER(K_POLL_TYPE_FIFO_DATA_AVAILABLE,
        K_POLL_MODE_NOTIFY_ONLY,
        &my_fifo, 0),
};
```

or at runtime

```c
struct k_poll_event events[2];
void some_init(void)
{
    k_poll_event_init(&events[0],
        K_POLL_TYPE_SEM_AVAILABLE,
        K_POLL_MODE_NOTIFY_ONLY,
        &my_sem);

    k_poll_event_init(&events[1],
        K_POLL_TYPE_FIFO_DATA_AVAILABLE,
        K_POLL_MODE_NOTIFY_ONLY,
        &my_fifo);
```

(continues on next page)
After the events are initialized, the array can be passed to `k_poll()`. A timeout can be specified to wait only for a specified amount of time, or the special values `K_NO_WAIT` and `K_FOREVER` to either not wait or wait until an event condition is satisfied and not sooner.

A list of pollers is offered on each semaphore or FIFO and as many events can wait in it as the app wants. Notice that the waiters will be served in first-come-first-serve order, not in priority order.

In case of success, `k_poll()` returns 0. If it times out, it returns `-EAGAIN`

```c
// assume there is no contention on this semaphore and FIFO
// -EADDRINUSE will not occur; the semaphore and/or data will be available

void do_stuff(void)
{
    rc = k_poll(events, 2, 1000);
    if (rc == 0) {
        if (events[0].state == K_POLL_STATE_SEM_AVAILABLE) {
            k_sem_take(events[0].sem, 0);
        } else if (events[1].state == K_POLL_STATE_FIFO_DATA_AVAILABLE) {
            data = k_fifo_get(events[1].fifo, 0);
            // handle data
        }
    } else {
        // handle timeout
    }
}
```

When `k_poll()` is called in a loop, the events state must be reset to `K_POLL_STATE_NOT_READY` by the user.

```c
void do_stuff(void)
{
    for(;;) {
        rc = k_poll(events, 2, K_FOREVER);
        if (events[0].state == K_POLL_STATE_SEM_AVAILABLE) {
            k_sem_take(events[0].sem, 0);
        } else if (events[1].state == K_POLL_STATE_FIFO_DATA_AVAILABLE) {
            data = k_fifo_get(events[1].fifo, 0);
            // handle data
        }
        events[0].state = K_POLL_STATE_NOT_READY;
        events[1].state = K_POLL_STATE_NOT_READY;
    }
}
```

**Using k_poll_signal_raise()** One of the types of events is `K_POLL_TYPE_SIGNAL`: this is a “direct” signal to a poll event. This can be seen as a lightweight binary semaphore only one thread can wait for.

A poll signal is a separate object of type `k_poll_signal` that must be attached to a `k_poll_event`, similar to a semaphore or FIFO. It must first be initialized either via `K_POLL_SIGNAL_INITIALIZER()` or `k_poll_signal_init()`.
It is signaled via the \texttt{k_poll_signal_raise()} function. This function takes a user \texttt{result} parameter that is opaque to the API and can be used to pass extra information to the thread waiting on the event.

If the signal is to be polled in a loop, \textit{both} its event state and its \texttt{signaled} field \texttt{must} be reset on each iteration if it has been signaled.
Note that poll signals are not internally synchronized. A `k_poll()` call that is passed a signal will return after any code in the system calls `k_poll_signal_raise()`. But if the signal is being externally managed and reset via `k_poll_signal_init()`, it is possible that by the time the application checks, the event state may no longer be equal to `K_POLL_STATE_SIGNALED`, and a (naive) application will miss events. Best practice is always to reset the signal only from within the thread invoking the `k_poll()` loop, or else to use some other event type which tracks event counts: semaphores and FIFOs are more error-proof in this sense because they can’t “miss” events, architecturally.

**Suggested Uses** Use `k_poll()` to consolidate multiple threads that would be pending on one object each, saving possibly large amounts of stack space.

Use a poll signal as a lightweight binary semaphore if only one thread pends on it.

**Note:** Because objects are only signaled if no other thread is waiting for them to become available and only one thread can poll on a specific object, polling is best used when objects are not subject of contention between multiple threads, basically when a single thread operates as a main “server” or “dispatcher” for multiple objects and is the only one trying to acquire these objects.

**Configuration Options** Related configuration options:

- `CONFIG_POLL`

**API Reference**

`group poll_apis`

**Defines**

- `K_POLL_TYPE_IGNORE`
- `K_POLL_TYPE_SIGNAL`
- `K_POLL_TYPE_SEM_AVAILABLE`
- `K_POLL_TYPE_DATA_AVAILABLE`
- `K_POLL_TYPE_FIFO_DATA_AVAILABLE`
- `K_POLL_TYPE_MSGQ_DATA_AVAILABLE`
K_POLL_TYPE_PIPE_DATA_AVAILABLE
K_POLL_STATE_NOT_READY
K_POLL_STATE_SIGNALED
K_POLL_STATE_SEM_AVAILABLE
K_POLL_STATE_DATA_AVAILABLE
K_POLL_STATE_FIFO_DATA_AVAILABLE
K_POLL_STATE_MSGQ_DATA_AVAILABLE
K_POLL_STATE_PIPE_DATA_AVAILABLE
K_POLL_STATE_CANCELLED
K_POLL_SIGNAL_INITIALIZER(obj)
K_POLL_EVENT_INITIALIZER(_event_type, _event_mode, _event_obj)
K_POLL_EVENT_STATIC_INITIALIZER(_event_type, _event_mode, _event_obj, event_tag)

Enums

enum k_poll_modes

Values:

enumerator K_POLL_MODE_NOTIFY_ONLY = 0

enumerator K_POLL_NUM_MODES

Functions

void k_poll_event_init(struct k_poll_event *event, uint32_t type, int mode, void *obj)

Initialize one struct k_poll_event instance.

After this routine is called on a poll event, the event it ready to be placed in an event array to be passed to k_poll().

Parameters

• event – The event to initialize.
• type – A bitfield of the types of event, from the K_POLL_TYPE_xxx values. Only values that apply to the same object being polled can be used together. Choosing K_POLL_TYPE_IGNORE disables the event.
• mode – Future. Use K_POLL_MODE_NOTIFY_ONLY.
• obj – Kernel object or poll signal.
int k_poll(struct k_poll_event *events, int num_events, k_timeout_t timeout)

Wait for one or many of multiple poll events to occur.

This routine allows a thread to wait concurrently for one or many of multiple poll events to have occurred. Such events can be a kernel object being available, like a semaphore, or a poll signal event.

When an event notifies that a kernel object is available, the kernel object is not “given” to the thread calling k_poll(): it merely signals the fact that the object was available when the k_poll() call was in effect. Also, all threads trying to acquire an object the regular way, i.e. by pending on the object, have precedence over the thread polling on the object. This means that the polling thread will never get the poll event on an object until the object becomes available and its pend queue is empty. For this reason, the k_poll() call is more effective when the objects being polled only have one thread, the polling thread, trying to acquire them.

When k_poll() returns 0, the caller should loop on all the events that were passed to k_poll() and check the state field for the values that were expected and take the associated actions.

Before being reused for another call to k_poll(), the user has to reset the state field to K_POLL_STATE_NOT_READY.

When called from user mode, a temporary memory allocation is required from the caller’s resource pool.

Parameters

- **events** – An array of events to be polled for.
- **num_events** – The number of events in the array.
- **timeout** – Waiting period for an event to be ready, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- **0** – One or more events are ready.
- **-EAGAIN** – Waiting period timed out.
- **-EINTR** – Polling has been interrupted, e.g. with k_queue_cancel_wait(). All output events are still set and valid, cancelled event(s) will be set to K_POLL_STATE_CANCELLED. In other words, -EINTR status means that at least one of output events is K_POLL_STATE_CANCELLED.
- **-ENOMEM** – Thread resource pool insufficient memory (user mode only)
- **-EINVAL** – Bad parameters (user mode only)

void k_poll_signal_init(struct k_poll_signal *sig)

Initialize a poll signal object.

Ready a poll signal object to be signaled via k_poll_signal_raise().

Parameters

- **sig** – A poll signal.

void k_poll_signal_reset(struct k_poll_signal *sig)

void k_poll_signal_check(struct k_poll_signal *sig, unsigned int *signaled, int *result)

Fetch the signaled state and result value of a poll signal.

Parameters

- **sig** – A poll signal object
- **signaled** – An integer buffer which will be written nonzero if the object was signaled
int k_poll_signal_raise(struct k_poll_signal *sig, int result)

Signal a poll signal object.

This routine makes ready a poll signal, which is basically a poll event of type K_POLL_TYPE_SIGNAL. If a thread was polling on that event, it will be made ready to run. A result value can be specified.

The poll signal contains a ‘signaled’ field that, when set by k_poll_signal_raise(), stays set until the user sets it back to 0 with k_poll_signal_reset(). It thus has to be reset by the user before being passed again to k_poll() or k_poll() will consider it being signaled, and will return immediately.

Note: The result is stored and the ‘signaled’ field is set even if this function returns an error indicating that an expiring poll was not notified. The next k_poll() will detect the missed raise.

Parameters

- sig – A poll signal.
- result – The value to store in the result field of the signal.

Return values

- 0 – The signal was delivered successfully.
- -EAGAIN – The polling thread’s timeout is in the process of expiring.

struct k_poll_signal

#include <kernel.h>

Public Members

sys_dlist_t poll_events

PRIVATE - DO NOT TOUCH

unsigned int signaled

1 if the event has been signaled, 0 otherwise. Stays set to 1 until user resets it to 0.

int result

custom result value passed to k_poll_signal_raise() if needed

struct k_poll_event

#include <kernel.h> Poll Event.

Public Members

struct z_poller *poller

PRIVATE - DO NOT TOUCH
.uint32_t tag
    optional user-specified tag, opaque, untouched by the API

.uint32_t type
    bitfield of event types (bitwise-ORed K_POLL_TYPE_xxx values)

.uint32_t state
    bitfield of event states (bitwise-ORed K_POLL_STATE_xxx values)

.uint32_t mode
    mode of operation, from enum k_poll_modes

.uint32_t unused
    unused bits in 32-bit word

union k_poll_event {anonymous} [anonymous]
    per-type data

Semaphores

A semaphore is a kernel object that implements a traditional counting semaphore.

Concepts

Any number of semaphores can be defined (limited only by available RAM). Each semaphore is referenced by its memory address.

A semaphore has the following key properties:

- A **count** that indicates the number of times the semaphore can be taken. A count of zero indicates that the semaphore is unavailable.
- A **limit** that indicates the maximum value the semaphore's count can reach.

A semaphore must be initialized before it can be used. Its count must be set to a non-negative value that is less than or equal to its limit.

A semaphore may be **given** by a thread or an ISR. Giving the semaphore increments its count, unless the count is already equal to the limit.

A semaphore may be **taken** by a thread. Taking the semaphore decrements its count, unless the semaphore is unavailable (i.e. at zero). When a semaphore is unavailable a thread may choose to
wait for it to be given. Any number of threads may wait on an unavailable semaphore simultaneously. When the semaphore is given, it is taken by the highest priority thread that has waited longest.

**Note:** You may initialize a “full” semaphore (count equal to limit) to limit the number of threads able to execute the critical section at the same time. You may also initialize an empty semaphore (count equal to 0, with a limit greater than 0) to create a gate through which no waiting thread may pass until the semaphore is incremented. All standard use cases of the common semaphore are supported.

**Note:** The kernel does allow an ISR to take a semaphore, however the ISR must not attempt to wait if the semaphore is unavailable.

### Implementation

#### Defining a Semaphore
A semaphore is defined using a variable of type `k_sem`. It must then be initialized by calling `k_sem_init()`.

The following code defines a semaphore, then configures it as a binary semaphore by setting its count to 0 and its limit to 1.

```c
struct k_sem my_sem;

k_sem_init(&my_sem, 0, 1);
```

Alternatively, a semaphore can be defined and initialized at compile time by calling `K_SEM_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_SEM_DEFINE(my_sem, 0, 1);
```

#### Giving a Semaphore
A semaphore is given by calling `k_sem_give()`.

The following code builds on the example above, and gives the semaphore to indicate that a unit of data is available for processing by a consumer thread.

```c
void input_data_interrupt_handler(void *arg)
{
    /* notify thread that data is available */
    k_sem_give(&my_sem);

    ...
}
```

#### Taking a Semaphore
A semaphore is taken by calling `k_sem_take()`.

The following code builds on the example above, and waits up to 50 milliseconds for the semaphore to be given. A warning is issued if the semaphore is not obtained in time.

```c
void consumer_thread(void)
{
    ...

    if (k_sem_take(&my_sem, K_MSEC(50)) != 0) {
        printk("Input data not available!");
    }
    ...
}
```
Suggested Uses

Use a semaphore to control access to a set of resources by multiple threads.
Use a semaphore to synchronize processing between a producing and consuming threads or ISRs.

Configuration Options

Related configuration options:

- None.

API Reference

group semaphore_apis

Defines

K_SEM_MAX_LIMIT

Maximum limit value allowed for a semaphore.
This is intended for use when a semaphore does not have an explicit maximum limit, and instead is just used for counting purposes.

K_SEM_DEFINE(name, initial_count, count_limit)

Statically define and initialize a semaphore.
The semaphore can be accessed outside the module where it is defined using:

```c
extern struct k_sem <name>;
```

Parameters

- name – Name of the semaphore.
- initial_count – Initial semaphore count.
- count_limit – Maximum permitted semaphore count.

Functions

int k_sem_init(struct k_sem *sem, unsigned int initial_count, unsigned int limit)

Initialize a semaphore.
This routine initializes a semaphore object, prior to its first use.

See also:

K_SEM_MAX_LIMIT
Parameters

- sem – Address of the semaphore.
- initial_count – Initial semaphore count.
- limit – Maximum permitted semaphore count.

Return values

- 0 – Semaphore created successfully
- EINVAL – Invalid values

```c
int k_sem_take(struct k_sem *sem, k_timeout_t timeout)
```

Take a semaphore.

This routine takes sem.

Function properties (list may not be complete)

```
isr-ok
```

**Note:** timeout must be set to K_NO_WAIT if called from ISR.

Parameters

- sem – Address of the semaphore.
- timeout – Waiting period to take the semaphore, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- 0 – Semaphore taken.
- EBUSY – Returned without waiting.
- EAGAIN – Waiting period timed out, or the semaphore was reset during the waiting period.

```c
void k_sem_give(struct k_sem *sem)
```

Give a semaphore.

This routine gives sem, unless the semaphore is already at its maximum permitted count.

Function properties (list may not be complete)

```
isr-ok
```

Parameters

- sem – Address of the semaphore.

```c
void k_sem_reset(struct k_sem *sem)
```

Resets a semaphore's count to zero.

This routine sets the count of sem to zero. Any outstanding semaphore takes will be aborted with -EAGAIN.

Parameters

- sem – Address of the semaphore.
unsigned int k_sem_count_get(struct k_sem *sem)
    Get a semaphore's count.

This routine returns the current count of sem.

    Parameters
    • sem – Address of the semaphore.

    Returns
    Current semaphore count.

User Mode Semaphore API Reference The sys_sem exists in user memory working as counter
semaphore for user mode thread when user mode enabled. When user mode isn't enabled, sys_sem
behaves like k_sem.

group user_semaphore_apis

Defines

SYS_SEM_DEFINE(_name, _initial_count, _count_limit)
    Statically define and initialize a sys_sem.

The semaphore can be accessed outside the module where it is defined using:

    extern struct sys_sem <name>;

Route this to memory domains using K_APP_DMEM().

    Parameters
    • _name – Name of the semaphore.
    • _initial_count – Initial semaphore count.
    • _count_limit – Maximum permitted semaphore count.

Functions

int sys_sem_init(struct sys_sem *sem, unsigned int initial_count, unsigned int limit)
    Initialize a semaphore.

This routine initializes a semaphore instance, prior to its first use.

    Parameters
    • sem – Address of the semaphore.
    • initial_count – Initial semaphore count.
    • limit – Maximum permitted semaphore count.

    Return values
    • 0 – Initial success.
    • -EINVAL – Bad parameters, the value of limit should be located in (0, INT_MAX] and initial_count shouldn't be greater than limit.
int sys_sem_give(struct sys_sem *sem)

Give a semaphore.

This routine gives `sem`, unless the semaphore is already at its maximum permitted count.

**Parameters**
- `sem` – Address of the semaphore.

**Return values**
- 0 – Semaphore given.
- -EINVAL – Parameter address not recognized.
- -EAGAIN – Count reached Maximum permitted count and try again.

int sys_sem_take(struct sys_sem *sem, k_timeout_t timeout)

Take a sys_sem.

This routine takes `sem`.

**Parameters**
- `sem` – Address of the sys_sem.
- `timeout` – Waiting period to take the sys_sem, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**
- 0 – sys_sem taken.
- -EINVAL – Parameter address not recognized.
- -ETIMEOUT – Waiting period timed out.
- -EAGAIN – Count reached Maximum permitted count and try again.

unsigned int sys_sem_count_get(struct sys_sem *sem)

Get sys_sem's value.

This routine returns the current value of `sem`.

**Parameters**
- `sem` – Address of the sys_sem.

**Returns**
Current value of sys_sem.

**Mutexes**

A mutex is a kernel object that implements a traditional reentrant mutex. A mutex allows multiple threads to safely share an associated hardware or software resource by ensuring mutually exclusive access to the resource.

- **Concepts**
  - Reentrant Locking
  - Priority Inheritance
- **Implementation**
  - Defining a Mutex
Any number of mutexes can be defined (limited only by available RAM). Each mutex is referenced by its memory address.

A mutex has the following key properties:

- A **lock count** that indicates the number of times the mutex has been locked by the thread that has locked it. A count of zero indicates that the mutex is unlocked.

- An **owning thread** that identifies the thread that has locked the mutex, when it is locked.

A mutex must be initialized before it can be used. This sets its lock count to zero.

A thread that needs to use a shared resource must first gain exclusive rights to access it by **locking** the associated mutex. If the mutex is already locked by another thread, the requesting thread may choose to wait for the mutex to be unlocked.

After locking a mutex, the thread may safely use the associated resource for as long as needed; however, it is considered good practice to hold the lock for as short a time as possible to avoid negatively impacting other threads that want to use the resource. When the thread no longer needs the resource it must **unlock** the mutex to allow other threads to use the resource.

Any number of threads may wait on a locked mutex simultaneously. When the mutex becomes unlocked it is then locked by the highest-priority thread that has waited the longest.

**Note:** Mutex objects are *not* designed for use by ISRs.

**Reentrant Locking** A thread is permitted to lock a mutex it has already locked. This allows the thread to access the associated resource at a point in its execution when the mutex may or may not already be locked.

A mutex that is repeatedly locked by a thread must be unlocked an equal number of times before the mutex becomes fully unlocked so it can be claimed by another thread.

**Priority Inheritance** The thread that has locked a mutex is eligible for **priority inheritance**. This means the kernel will *temporarily* elevate the thread's priority if a higher priority thread begins waiting on the mutex. This allows the owning thread to complete its work and release the mutex more rapidly by executing at the same priority as the waiting thread. Once the mutex has been unlocked, the unlocking thread resets its priority to the level it had before locking that mutex.

**Note:** The `CONFIG_PRIORITY_CEILING` configuration option limits how high the kernel can raise a thread's priority due to priority inheritance. The default value of 0 permits unlimited elevation.

The owning thread's base priority is saved in the mutex when it obtains the lock. Each time a higher priority thread waits on a mutex, the kernel adjusts the owning thread's priority. When the owning
thread releases the lock (or if the high priority waiting thread times out), the kernel restores the thread’s base priority from the value saved in the mutex.

This works well for priority inheritance as long as only one locked mutex is involved. However, if multiple mutexes are involved, sub-optimal behavior will be observed if the mutexes are not unlocked in the reverse order to which the owning thread’s priority was previously raised. Consequently it is recommended that a thread lock only a single mutex at a time when multiple mutexes are shared between threads of different priorities.

### Implementation

**Defining a Mutex**  A mutex is defined using a variable of type `k_mutex`. It must then be initialized by calling `k_mutex_init()`.

The following code defines and initializes a mutex.

```c
struct k_mutex my_mutex;
k_mutex_init(&my_mutex);
```

Alternatively, a mutex can be defined and initialized at compile time by calling `K_MUTEX_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_MUTEX_DEFINE(my_mutex);
```

**Locking a Mutex**  A mutex is locked by calling `k_mutex_lock()`.

The following code builds on the example above, and waits indefinitely for the mutex to become available if it is already locked by another thread.

```c
k_mutex_lock(&my_mutex, K_FOREVER);
```

The following code waits up to 100 milliseconds for the mutex to become available, and gives a warning if the mutex does not become available.

```c
if (k_mutex_lock(&my_mutex, K_MSEC(100)) == 0) {
    /* mutex successfully locked */
} else {
    printf("Cannot lock XYZ display\n");
}
```

**Unlocking a Mutex**  A mutex is unlocked by calling `k_mutex_unlock()`.

The following code builds on the example above, and unlocks the mutex that was previously locked by the thread.

```c
k_mutex_unlock(&my_mutex);
```

**Suggested Uses**  Use a mutex to provide exclusive access to a resource, such as a physical device.

**Configuration Options**  Related configuration options:

- `CONFIG_PRIORITY_CEILING`
API Reference

group mutex_apis

Defines

K_MUTEX_DEFINE(name)

Statically define and initialize a mutex.

The mutex can be accessed outside the module where it is defined using:

```c
extern struct k_mutex <name>;
```

Parameters

- name – Name of the mutex.

Functions

int k_mutex_init(struct k_mutex *mutex)

Initialize a mutex.

This routine initializes a mutex object, prior to its first use.

Upon completion, the mutex is available and does not have an owner.

Parameters

- mutex – Address of the mutex.

Return values

- 0 – Mutex object created

int k_mutex_lock(struct k_mutex *mutex, k_timeout_t timeout)

Lock a mutex.

This routine locks mutex. If the mutex is locked by another thread, the calling thread waits until the mutex becomes available or until a timeout occurs.

A thread is permitted to lock a mutex it has already locked. The operation completes immediately and the lock count is increased by 1.

Mutexes may not be locked in ISRs.

Parameters

- mutex – Address of the mutex.
- timeout – Waiting period to lock the mutex, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

- 0 – Mutex locked.
- -EBUSY – Returned without waiting.
- -EAGAIN – Waiting period timed out.
int k_mutex_unlock(struct k_mutex *mutex)

Unlock a mutex.

This routine unlocks mutex. The mutex must already be locked by the calling thread.

The mutex cannot be claimed by another thread until it has been unlocked by the calling thread as many times as it was previously locked by that thread.

Mutexes may not be unlocked in ISRs, as mutexes must only be manipulated in thread context due to ownership and priority inheritance semantics.

Parameters

- Mutual – Address of the mutex.

Return values

- 0 – Mutex unlocked.
- -EPERM – The current thread does not own the mutex
- -EINVAL – The mutex is not locked

struct k_mutex

#include <kernel.h> Mutex Structure

Public Members

_wait_q_t wait_q
Mutex wait queue

struct k_thread *owner
Mutex owner

uint32_t lock_count
Current lock count

int owner_orig_prio
Original thread priority

Futex API Reference
k_futex is a lightweight mutual exclusion primitive designed to minimize kernel involvement. Uncontended operation relies only on atomic access to shared memory. k_futex are tracked as kernel objects and can live in user memory so that any access bypasses the kernel object permission management mechanism.

Futex APIs

Functions

int k_futex_wait(struct k_futex *futex, int expected, k_timeout_t timeout)
Pend the current thread on a futex.
Tests that the supplied futex contains the expected value, and if so, goes to sleep until some other thread calls k_futex_wake() on it.

Parameters
• **futex** – Address of the futex.
• **expected** – Expected value of the futex, if it is different the caller will not wait on it.
• **timeout** – Non-negative waiting period on the futex, or one of the special values K_NO_WAIT or K_FOREVER.

**Return values**
• -EACCES – Caller does not have read access to futex address.
• -EAGAIN – If the futex value did not match the expected parameter.
• -EINVAL – Futex parameter address not recognized by the kernel.
• -ETIMEDOUT – Thread woke up due to timeout and not a futex wakeup.
• 0 – if the caller went to sleep and was woken up. The caller should check the futex’s value on wakeup to determine if it needs to block again.

```c
int k_futex_wake(struct k_futex *futex, bool wake_all)
```

Wake one/all threads pending on a futex.

Wake up the highest priority thread pending on the supplied futex, or wakeup all the threads pending on the supplied futex, and the behavior depends on `wake_all`.

**Parameters**
• **futex** – Futex to wake up pending threads.
• **wake_all** – If true, wake up all pending threads; If false, wakeup the highest priority thread.

**Return values**
• -EACCES – Caller does not have access to the futex address.
• -EINVAL – Futex parameter address not recognized by the kernel.
• Number – of threads that were woken up.

**User Mode Mutex API Reference**  
`sys_mutex` behaves almost exactly like `k_mutex`, with the added advantage that a `sys_mutex` instance can reside in user memory. When user mode isn’t enabled, `sys_mutex` behaves like `k_mutex`.

```c
SYS_MUTEX_DEFINE(name)
```

Statically define and initialize a `sys_mutex`.

The mutex can be accessed outside the module where it is defined using:

```c
extern struct sys_mutex <name>;
```

Route this to memory domains using `K_APP_DMEM()`.

**Parameters**
• **name** – Name of the mutex.
Functions

static inline void sys_mutex_init(struct sys_mutex *mutex)
    Initialize a mutex.

This routine initializes a mutex object, prior to its first use.

Upon completion, the mutex is available and does not have an owner.

This routine is only necessary to call when userspace is disabled and the mutex was not created
with SYS_MUTEX_DEFINE().

Parameters
• mutex – Address of the mutex.

static inline int sys_mutex_lock(struct sys_mutex *mutex, k_timeout_t timeout)
    Lock a mutex.

This routine locks mutex. If the mutex is locked by another thread, the calling thread waits
until the mutex becomes available or until a timeout occurs.

A thread is permitted to lock a mutex it has already locked. The operation completes imme-
diately and the lock count is increased by 1.

Parameters
• mutex – Address of the mutex, which may reside in user memory
• timeout – Waiting period to lock the mutex, or one of the special values
  K_NO_WAIT and K_FOREVER.

Return values
• 0 – Mutex locked.
• -EBUSY – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -EACCES – Caller has no access to provided mutex address
• -EINVAL – Provided mutex not recognized by the kernel

static inline int sys_mutex_unlock(struct sys_mutex *mutex)
    Unlock a mutex.

This routine unlocks mutex. The mutex must already be locked by the calling thread.

The mutex cannot be claimed by another thread until it has been unlocked by the calling
thread as many times as it was previously locked by that thread.

Parameters
• mutex – Address of the mutex, which may reside in user memory

Return values
• 0 – Mutex unlocked
• -EACCES – Caller has no access to provided mutex address
• -EINVAL – Provided mutex not recognized by the kernel or mutex wasn’t locked
• -EPERM – Caller does not own the mutex
Condition Variables

A condition variable is a synchronization primitive that enables threads to wait until a particular condition occurs.

- Concepts
- Implementation
  - Defining a Condition Variable
  - Waiting on a Condition Variable
  - Signaling a Condition Variable
- Suggested Uses
- Configuration Options
- API Reference

Concepts

Any number of condition variables can be defined (limited only by available RAM). Each condition variable is referenced by its memory address.

To wait for a condition to become true, a thread can make use of a condition variable.

A condition variable is basically a queue of threads that threads can put themselves on when some state of execution (i.e., some condition) is not as desired (by waiting on the condition). The function `k_condvar_wait()` performs atomically the following steps:

1. Releases the last acquired mutex.
2. Puts the current thread in the condition variable queue.

Some other thread, when it changes said state, can then wake one (or more) of those waiting threads and thus allow them to continue by signaling on the condition using `k_condvar_signal()` or `k_condvar_broadcast()` then it:

1. Re-acquires the mutex previously released.
2. Returns from `k_condvar_wait()`.

A condition variable must be initialized before it can be used.

Implementation

Defining a Condition Variable

A condition variable is defined using a variable of type `k_condvar`. It must then be initialized by calling `k_condvar_init()`.

The following code defines a condition variable:

```c
struct k_condvar my_condvar;
k_condvar_init(&my_condvar);
```

Alternatively, a condition variable can be defined and initialized at compile time by calling `K_CONDVAR_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_CONDVAR_DEFINE(my_condvar);
```
Waiting on a Condition Variable  A thread can wait on a condition by calling `k_condvar_wait()`. The following code waits on the condition variable.

```c
K_MUTEX_DEFINE(mutex);
K_CONDVAR_DEFINE(condvar)

void main(void)
{
    k_mutex_lock(&mutex, K_FOREVER);
    /* block this thread until another thread signals cond. While
     * blocked, the mutex is released, then re-acquired before this
     * thread is woken up and the call returns.
     */
    k_condvar_wait(&condvar, &mutex, K_FOREVER);
    ...
    k_mutex_unlock(&mutex);
}
```

Signaling a Condition Variable  A condition variable is signaled on by calling `k_condvar_signal()` for one thread or by calling `k_condvar_broadcast()` for multiple threads. The following code builds on the example above.

```c
void worker_thread(void)
{
    k_mutex_lock(&mutex, K_FOREVER);
    /*
     * Do some work and fulfill the condition
     */
    ...
    k_condvar_signal(&condvar);
    k_mutex_unlock(&mutex);
}
```

Suggested Uses  Use condition variables with a mutex to signal changing states (conditions) from one thread to another thread. Condition variables are not the condition itself and they are not events. The condition is contained in the surrounding programming logic.

Mutexes alone are not designed for use as a notification/synchronization mechanism. They are meant to provide mutually exclusive access to a shared resource only.

Configuration Options  Related configuration options:

- None.

API Reference

group condvar_apis

Defines

3.1. Kernel Services
K_CONDVAR_DEFINE(name)
    Statically define and initialize a condition variable.

    The condition variable can be accessed outside the module where it is defined using:

    extern struct k_condvar <name>;

Parameters
    • name – Name of the condition variable.

Functions

int k_condvar_init(struct k_condvar *condvar)
    Initialize a condition variable.

    Parameters
    • condvar – pointer to a k_condvar structure

    Return values
    0 – Condition variable created successfully

int k_condvar_signal(struct k_condvar *condvar)
    Signals one thread that is pending on the condition variable.

    Parameters
    • condvar – pointer to a k_condvar structure

    Return values
    0 – On success

int k_condvar_broadcast(struct k_condvar *condvar)
    Unblock all threads that are pending on the condition variable.

    Parameters
    • condvar – pointer to a k_condvar structure

    Returns
    An integer with number of woken threads on success

int k_condvar_wait(struct k_condvar *condvar, struct k_mutex *mutex, k_timeout_t timeout)
    Waits on the condition variable releasing the mutex lock.

    Atomically releases the currently owned mutex, blocks the current thread waiting on the condition variable specified by condvar, and finally acquires the mutex again.

    The waiting thread unblocks only after another thread calls k_condvar_signal, or k_condvar_broadcast with the same condition variable.

    Parameters
    • condvar – pointer to a k_condvar structure
    • mutex – Address of the mutex.
    • timeout – Waiting period for the condition variable or one of the special values K_NO_WAIT and K_FOREVER.

    Return values
    • 0 – On success
    • -EAGAIN – Waiting period timed out.
Events

An event object is a kernel object that implements traditional events.

Concepts  Any number of event objects can be defined (limited only by available RAM). Each event object is referenced by its memory address. One or more threads may wait on an event object until the desired set of events has been delivered to the event object. When new events are delivered to the event object, all threads whose wait conditions have been satisfied become ready simultaneously.

An event object has the following key properties:

- A 32-bit value that tracks which events have been delivered to it.

An event object must be initialized before it can be used.

Events may be delivered by a thread or an ISR. When delivering events, the events may either overwrite the existing set of events or add to them in a bitwise fashion. When overwriting the existing set of events, this is referred to as setting. When adding to them in a bitwise fashion, this is referred to as posting. Both posting and setting events have the potential to fulfill match conditions of multiple threads waiting on the event object. All threads whose match conditions have been met are made active at the same time.

Threads may wait on one or more events. They may either wait for all of the requested events, or for any of them. Furthermore, threads making a wait request have the option of resetting the current set of events tracked by the event object prior to waiting. Care must be taken with this option when multiple threads wait on the same event object.

Note: The kernel does allow an ISR to query an event object, however the ISR must not attempt to wait for the events.

Implementation

Defining an Event Object  An event object is defined using a variable of type k_event. It must then be initialized by calling k_event_init().

The following code defines an event object.

```c
struct k_event my_event;

k_event_init(&my_event);
```
Alternatively, an event object can be defined and initialized at compile time by calling `K_EVENT_DEFINE`. The following code has the same effect as the code segment above.

```c
K_EVENT_DEFINE(my_event);
```

### Setting Events
Events in an event object are set by calling `k_event_set()`.
The following code builds on the example above, and sets the events tracked by the event object to 0x001.

```c
void input_available_interrupt_handler(void *arg)
{
    /* notify threads that data is available */
    k_event_set(&my_event, 0x001);
    ...
}
```

### Posting Events
Events are posted to an event object by calling `k_event_post()`.
The following code builds on the example above, and posts a set of events to the event object.

```c
void input_available_interrupt_handler(void *arg)
{
    ...
    /* notify threads that more data is available */
    k_event_post(&my_event, 0x120);
    ...
}
```

### Waiting for Events
Threads wait for events by calling `k_event_wait()`.
The following code builds on the example above, and waits up to 50 milliseconds for any of the specified events to be posted. A warning is issued if none of the events are posted in time.

```c
void consumer_thread(void)
{
    uint32_t events;

    events = k_event_wait(&my_event, 0xFFF, false, K_MSEC(50));
    if (events == 0) {
        printk("No input devices are available!");
    } else {
        /* Access the desired input device(s) */
        ...
    }
    ...
}
```

Alternatively, the consumer thread may desire to wait for all the events before continuing.
```c
void consumer_thread(void)
{
    uint32_t events;

    events = k_event_wait_all(&my_event, 0x121, false, K_MSEC(50));
    if (events == 0) {
        printk("At least one input device is not available!");
    } else {
        /* Access the desired input devices */
        ...
    }
    ...
}
```

**Suggested Uses**  Use events to indicate that a set of conditions have occurred. Use events to pass small amounts of data to multiple threads at once.

**Configuration Options**  Related configuration options:

- CONFIG_EVENTS

**API Reference**

`group event_apis`

**Defines**

`K_EVENT_DEFINE(name)`

Statically define and initialize an event object. The event can be accessed outside the module where it is defined using:

```c
extern struct k_event <name>;
```

**Parameters**

- name – Name of the event object.

**Functions**

`void k_event_init(struct k_event *event)`

Initialize an event object. This routine initializes an event object, prior to its first use.

**Parameters**

- event – Address of the event object.
void k_event_post(struct k_event *event, uint32_t events)
Post one or more events to an event object.

This routine posts one or more events to an event object. All tasks waiting on the event object event whose waiting conditions become met by this posting immediately unpend.

Posting differs from setting in that posted events are merged together with the current set of events tracked by the event object.

**Parameters**
- `event` – Address of the event object
- `events` – Set of events to post to event

void k_event_set(struct k_event *event, uint32_t events)
Set the events in an event object.

This routine sets the events stored in event object to the specified value. All tasks waiting on the event object event whose waiting conditions become met by this immediately unpend.

Setting differs from posting in that set events replace the current set of events tracked by the event object.

**Parameters**
- `event` – Address of the event object
- `events` – Set of events to post to event

void k_event_set_masked(struct k_event *event, uint32_t events, uint32_t events_mask)
Set or clear the events in an event object.

This routine sets the events stored in event object to the specified value. All tasks waiting on the event object event whose waiting conditions become met by this immediately unpend. Unlike k_event_set, this routine allows specific event bits to be set and cleared as determined by the mask.

**Parameters**
- `event` – Address of the event object
- `events` – Set of events to post to event
- `events_mask` – Mask to be applied to events

uint32_t k_event_wait(struct k_event *event, uint32_t events, bool reset, k_timeout_t timeout)
Wait for any of the specified events.

This routine waits on event object event until any of the specified events have been delivered to the event object, or the maximum wait time timeout has expired. A thread may wait on up to 32 distinctly numbered events that are expressed as bits in a single 32-bit word.

**Note:** The caller must be careful when resetting if there are multiple threads waiting for the event object event.

**Parameters**
- `event` – Address of the event object
- `events` – Set of desired events on which to wait
- `reset` – If true, clear the set of events tracked by the event object before waiting. If false, do not clear the events.
- `timeout` – Waiting period for the desired set of events or one of the special values K_NO_WAIT and K_FOREVER.
Return values

- set – of matching events upon success
- 0 – if matching events were not received within the specified time

```c
uint32_t k_event_wait_all(struct k_event *event, uint32_t events, bool reset, k_timeout_t timeout)
```

Wait for any of the specified events.

This routine waits on event object `event` until all of the specified events have been delivered to the event object, or the maximum wait time `timeout` has expired. A thread may wait on up to 32 distinctly numbered events that are expressed as bits in a single 32-bit word.

**Note:** The caller must be careful when resetting if there are multiple threads waiting for the event object `event`.

Parameters

- `event` – Address of the event object
- `events` – Set of desired events on which to wait
- `reset` – If true, clear the set of events tracked by the event object before waiting. If false, do not clear the events.
- `timeout` – Waiting period for the desired set of events or one of the special values `K_NO_WAIT` and `K_FOREVER`.

Return values

- set – of matching events upon success
- 0 – if matching events were not received within the specified time

```c
struct k_event
```

```
#include <kernel.h> Event Structure
```

Symmetric Multiprocessing

On multiprocessor architectures, Zephyr supports the use of multiple physical CPUs running Zephyr application code. This support is “symmetric” in the sense that no specific CPU is treated specially by default. Any processor is capable of running any Zephyr thread, with access to all standard Zephyr APIs supported.

No special application code needs to be written to take advantage of this feature. If there are two Zephyr application threads runnable on a supported dual processor device, they will both run simultaneously.

SMP configuration is controlled under the `CONFIG_SMP` kconfig variable. This must be set to “y” to enable SMP features, otherwise a uniprocessor kernel will be built. In general the platform default will have enabled this anywhere it’s supported. When enabled, the number of physical CPUs available is visible at build time as `CONFIG_MP_NUM_CPUS`. Likewise, the default for this will be the number of available CPUs on the platform and it is not expected that typical apps will change it. But it is legal and supported to set this to a smaller (but obviously not larger) number for special purposes (e.g. for testing, or to reserve a physical CPU for running non-Zephyr code).
Synchronization  At the application level, core Zephyr IPC and synchronization primitives all behave identically under an SMP kernel. For example semaphores used to implement blocking mutual exclusion continue to be a proper application choice.

At the lowest level, however, Zephyr code has often used the `irq_lock()`/`irq_unlock()` primitives to implement fine grained critical sections using interrupt masking. These APIs continue to work via an emulation layer (see below), but the masking technique does not: the fact that your CPU will not be interrupted while you are in your critical section says nothing about whether a different CPU will be running simultaneously and be inspecting or modifying the same data!

Spinlocks  SMP systems provide a more constrained `k_spin_lock()` primitive that not only masks interrupts locally, as done by `irq_lock()`, but also atomically validates that a shared lock variable has been modified before returning to the caller, “spinning” on the check if needed to wait for the other CPU to exit the lock. The default Zephyr implementation of `k_spin_lock()` and `k_spin_unlock()` is built on top of the pre-existing atomic layer (itself usually implemented using compiler intrinsics), though facilities exist for architectures to define their own for performance reasons.

One important difference between IRQ locks and spinlocks is that the earlier API was naturally recursive: the lock was global, so it was legal to acquire a nested lock inside of a critical section. Spinlocks are separable: you can have many locks for separate subsystems or data structures, preventing CPUs from contending on a single global resource. But that means that spinlocks must not be used recursively. Code that holds a specific lock must not try to re-acquire it or it will deadlock (it is perfectly legal to nest distinct spinlocks, however). A validation layer is available to detect and report bugs like this.

When used on a uniprocessor system, the data component of the spinlock (the atomic lock variable) is unnecessary and elided. Except for the recursive semantics above, spinlocks in single-CPU contexts produce identical code to legacy IRQ locks. In fact the entirety of the Zephyr core kernel has now been ported to use spinlocks exclusively.

Legacy irq_lock() emulation  For the benefit of applications written to the uniprocessor locking API, `irq_lock()` and `irq_unlock()` continue to work compatibly on SMP systems with identical semantics to their legacy versions. They are implemented as a single global spinlock, with a nesting count and the ability to be atomically reacquired on context switch into locked threads. The kernel will ensure that only one thread across all CPUs can hold the lock at any time, that it is released on context switch, and that it is re-acquired when necessary to restore the lock state when a thread is switched in. Other CPUs will spin waiting for the release to happen.

The overhead involved in this process has measurable performance impact, however. Unlike uniprocessor apps, SMP apps using `irq_lock()` are not simply invoking a very short (often ~1 instruction) interrupt masking operation. That, and the fact that the IRQ lock is global, means that code expecting to be run in an SMP context should be using the spinlock API wherever possible.

CPU Mask  It is often desirable for real time applications to deliberately partition work across physical CPUs instead of relying solely on the kernel scheduler to decide on which threads to execute. Zephyr provides an API, controlled by the `CONFIG_SCHED_CPU_MASK` kconfig variable, which can associate a specific set of CPUs with each thread, indicating on which CPUs it can run.

By default, new threads can run on any CPU. Calling `k_thread_cpu_mask_disable()` with a particular CPU ID will prevent that thread from running on that CPU in the future. Likewise `k_thread_cpu_mask_enable()` will re-enable execution. There are also `k_thread_cpu_mask_clear()` and `k_thread_cpu_mask_enable_all()` APIs available for convenience. For obvious reasons, these APIs are illegal if called on a runnable thread. The thread must be blocked or suspended, otherwise an `EINVAL` will be returned.

Note that when this feature is enabled, the scheduler algorithm involved in doing the per-CPU mask test requires that the list be traversed in full. The kernel does not keep a per-CPU run queue. That means that the performance benefits from the `CONFIG_SCHED_SCALABLE` and `CONFIG_SCHED_MULTIQ` scheduler backends cannot be realized. CPU mask processing is available only when `CONFIG_SCHED_DUMB` is the selected backend. This requirement is enforced in the configuration layer.
SMP Boot Process  A Zephyr SMP kernel begins boot identically to a uniprocessor kernel. Auxiliary CPUs begin in a disabled state in the architecture layer. All standard kernel initialization, including device initialization, happens on a single CPU before other CPUs are brought online.

Just before entering the application main() function, the kernel calls z_smp_init() to launch the SMP initialization process. This enumerates over the configured CPUs, calling into the architecture layer using arch_start_cpu() for each one. This function is passed a memory region to use as a stack on the foreign CPU (in practice it uses the area that will become that CPU’s interrupt stack), the address of a local smp_init_top() callback function to run on that CPU, and a pointer to a “start flag” address which will be used as an atomic signal.

The local SMP initialization (smp_init_top()) on each CPU is then invoked by the architecture layer. Note that interrupts are still masked at this point. This routine is responsible for calling smp_timer_init() to set up any needed stat in the timer driver. On many architectures the timer is a per-CPU device and needs to be configured specially on auxiliary CPUs. Then it waits (spinning) for the atomic “start flag” to be released in the main thread, to guarantee that all SMP initialization is complete before any Zephyr application code runs, and finally calls z_swap() to transfer control to the appropriate runnable thread via the standard scheduler API.

![SMP Initialization Diagram](image)

**Fig. 3.1:** Example SMP initialization process, showing a configuration with two CPUs and two app threads which begin operating simultaneously.

Interprocessor Interrupts  When running in multiprocessor environments, it is occasionally the case that state modified on the local CPU needs to be synchronously handled on a different processor.

One example is the Zephyr k_thread_abort() API, which cannot return until the thread that had been aborted is no longer runnable. If it is currently running on another CPU, that becomes difficult to implement.

3.1. Kernel Services
Another is low power idle. It is a firm requirement on many devices that system idle be implemented using a low-power mode with as many interrupts (including periodic timer interrupts) disabled or deferred as is possible. If a CPU is in such a state, and on another CPU a thread becomes runnable, the idle CPU has no way to “wake up” to handle the newly-runnable load.

So where possible, Zephyr SMP architectures should implement an interprocessor interrupt. The current framework is very simple: the architecture provides a `arch_sched_ipi()` call, which when invoked will flag an interrupt on all CPUs (except the current one, though that is allowed behavior) which will then invoke the `z_sched_ipi()` function implemented in the scheduler. The expectation is that these APIs will evolve over time to encompass more functionality (e.g. cross-CPU calls), and that the scheduler-specific calls here will be implemented in terms of a more general framework.

Note that not all SMP architectures will have a usable IPI mechanism (either missing, or just undocumented/unimplemented). In those cases Zephyr provides fallback behavior that is correct, but perhaps suboptimal.

Using this, `k_thread_abort()` becomes only slightly more complicated in SMP: for the case where a thread is actually running on another CPU (we can detect this atomically inside the scheduler), we broadcast an IPI and spin, waiting for the thread to either become “DEAD” or for it to re-enter the queue (in which case we terminate it the same way we would have in uniprocessor mode). Note that the “aborted” check happens on any interrupt exit, so there is no special handling needed in the IPI per se. This allows us to implement a reasonable fallback when IPI is not available: we can simply spin, waiting until the foreign CPU receives any interrupt, though this may be a much longer time!

Likewise idle wakeups are trivially implementable with an empty IPI handler. If a thread is added to an empty run queue (i.e. there may have been idle CPUs), we broadcast an IPI. A foreign CPU will then be able to see the new thread when exiting from the interrupt and will switch to it if available.

Without an IPI, however, a low power idle that requires an interrupt will not work to synchronously run new threads. The workaround in that case is more invasive: Zephyr will not enter the system idle handler and will instead spin in its idle loop, testing the scheduler state at high frequency (not spinning on it though, as that would involve severe lock contention) for new threads. The expectation is that power constrained SMP applications are always going to provide an IPI, and this code will only be used for testing purposes or on systems without power consumption requirements.

**SMP Kernel Internals** In general, Zephyr kernel code is SMP-agnostic and, like application code, will work correctly regardless of the number of CPUs available. But in a few areas there are notable changes in structure or behavior.

**Per-CPU data** Many elements of the core kernel data need to be implemented for each CPU in SMP mode. For example, the `_current` thread pointer obviously needs to reflect what is running locally, there are many threads running concurrently. Likewise a kernel-provided interrupt stack needs to be created and assigned for each physical CPU, as does the interrupt nesting count used to detect ISR state.

These fields are now moved into a separate struct `_cpu` instance within the `_kernel` struct, which has a `cpus[]` array indexed by ID. Compatibility fields are provided for legacy uniprocessor code trying to access the fields of `cpus[0]` using the older syntax and assembly offsets.

Note that an important requirement on the architecture layer is that the pointer to this CPU struct be available rapidly when in kernel context. The expectation is that `arch_curr_cpu()` will be implemented using a CPU-provided register or addressing mode that can store this value across arbitrary context switches or interrupts and make it available to any kernel-mode code.

Similarly, where on a uniprocessor system Zephyr could simply create a global “idle thread” at the lowest priority, in SMP we may need one for each CPU. This makes the internal predicate test for “`is_idle()`” in the scheduler, which is a hot path performance environment, more complicated than simply testing the thread pointer for equality with a known static variable. In SMP mode, idle threads are distinguished by a separate field in the thread struct.
Switch-based context switching  The traditional Zephyr context switch primitive has been `z_swap()`. Unfortunately, this function takes no argument specifying a thread to switch to. The expectation has always been that the scheduler has already made its preemption decision when its state was last modified and cached the resulting “next thread” pointer in a location where architecture context switch primitives can find it via a simple struct offset. That technique will not work in SMP, because the other CPU may have modified scheduler state since the current CPU last exited the scheduler (for example: it might already be running that cached thread!).

Instead, the SMP “switch to” decision needs to be made synchronously with the swap call, and as we don’t want per-architecture assembly code to be handling scheduler internal state, Zephyr requires a somewhat lower-level context switch primitives for SMP systems: `arch_switch()` is always called with interrupts masked, and takes exactly two arguments. The first is an opaque (architecture defined) handle to the context to which it should switch, and the second is a pointer to such a handle into which it should store the handle resulting from the thread that is being switched out. The kernel then implements a portable `z_swap()` implementation on top of this primitive which includes the relevant scheduler logic in a location where the architecture doesn’t need to understand it.

Similarly, on interrupt exit, switch-based architectures are expected to call `z_get_next_switch_handle()` to retrieve the next thread to run from the scheduler. The argument to `z_get_next_switch_handle()` is either the interrupted thread’s “handle” reflecting the same opaque type used by `arch_switch()`, or NULL if that thread cannot be released to the scheduler just yet. The choice between a handle value or NULL depends on the way CPU interrupt mode is implemented.

Architectures with a large CPU register file would typically preserve only the caller-saved registers on the current thread’s stack when interrupted in order to minimize interrupt latency, and preserve the callee-saved registers only when `arch_switch()` is called to minimize context switching latency. Such architectures must use NULL as the argument to `z_get_next_switch_handle()` to determine if there is a new thread to schedule, and follow through with their own `arch_switch()` or derivative if so, or directly leave interrupt mode otherwise. In the former case it is up to that switch code to store the handle resulting from the thread that is being switched out in that thread’s “switch_handle” field after its context has fully been saved.

Architectures whose entry in interrupt mode already preserves the entire thread state may pass that thread’s handle directly to `z_get_next_switch_handle()` and be done in one step.

Note that while SMP requires CONFIG_USE_SWITCH, the reverse is not true. A uniprocessor architecture built with CONFIG_SMP set to No might still decide to implement its context switching using `arch_switch()`.

API Reference

`group spinlock_apis`

Spinlock APIs.

`Typedefs`

typedef struct `z_spinlock_key` `k_spinlock_key_t`

Spinlock key type.

This type defines a “key” value used by a spinlock implementation to store the system interrupt state at the time of a call to `k_spin_lock()`. It is expected to be passed to a matching `k_spin_unlock()`.

This type is opaque and should not be inspected by application code.

`Functions`
ALWAYS_INLINE static k_spinlock_key_t k_spin_lock(struct k_spinlock *l)

Lock a spinlock.

This routine locks the specified spinlock, returning a key handle representing interrupt state needed at unlock time. Upon returning, the calling thread is guaranteed not to be suspended or interrupted on its current CPU until it calls k_spin_unlock(). The implementation guarantees mutual exclusion: exactly one thread on one CPU will return from k_spin_lock() at a time. Other CPUs trying to acquire a lock already held by another CPU will enter an implementation-defined busy loop (“spinning”) until the lock is released.

Separate spin locks may be nested. It is legal to lock an (unlocked) spin lock while holding a different lock. Spin locks are not recursive, however: an attempt to acquire a spin lock that the CPU already holds will deadlock.

In circumstances where only one CPU exists, the behavior of k_spin_lock() remains as specified above, though obviously no spinning will take place. Implementations may be free to optimize in uniprocessor contexts such that the locking reduces to an interrupt mask operation.

Parameters

• l – A pointer to the spinlock to lock

Returns

A key value that must be passed to k_spin_unlock() when the lock is released.

ALWAYS_INLINE static void k_spin_unlock(struct k_spinlock *l, k_spinlock_key_t key)

Unlock a spin lock.

This releases a lock acquired by k_spin_lock(). After this function is called, any CPU will be able to acquire the lock. If other CPUs are currently spinning inside k_spin_lock() waiting for this lock, exactly one of them will return synchronously with the lock held.

Spin locks must be properly nested. A call to k_spin_unlock() must be made on the lock object most recently locked using k_spin_lock(), using the key value that it returned. Attempts to unlock mis-nested locks, or to unlock locks that are not held, or to passing a key parameter other than the one returned from k_spin_lock(), are illegal. When CONFIG_SPIN_VALIDATE is set, some of these errors can be detected by the framework.

Parameters

• l – A pointer to the spinlock to release

• key – The value returned from k_spin_lock() when this lock was acquired

ALWAYS_INLINE static void k_spin_release(struct k_spinlock *l)

struct k_spinlock

#include <spinlock.h> Kernel Spin Lock.

This struct defines a spin lock record on which CPUs can wait with k_spin_lock(). Any number of spinlocks may be defined in application code.

3.1.2 Data Passing

These pages cover kernel objects which can be used to pass data between threads and ISRs.

The following table summarizes their high-level features.
<table>
<thead>
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<th>Object</th>
<th>Bidirectional?</th>
<th>Data structure</th>
<th>Data item size</th>
<th>Data Alignment</th>
<th>ISRs can receive?</th>
<th>ISRs can send?</th>
<th>Overrun handling</th>
</tr>
</thead>
<tbody>
<tr>
<td>Stack</td>
<td>No</td>
<td>Array</td>
<td>Word</td>
<td>Word</td>
<td>Yes [3]</td>
<td>Yes</td>
<td>Undefined behavior</td>
</tr>
<tr>
<td>Message queue</td>
<td>No</td>
<td>Ring buffer</td>
<td>Power of two</td>
<td>Power of two</td>
<td>Yes [3]</td>
<td>Yes</td>
<td>Pend thread or return -errno</td>
</tr>
<tr>
<td>Mailbox</td>
<td>Yes</td>
<td>Queue</td>
<td>Arbitrary [1]</td>
<td>Arbitrary</td>
<td>No</td>
<td>No</td>
<td>N/A</td>
</tr>
</tbody>
</table>

[1] Callers allocate space for queue overhead in the data elements themselves.
[2] Objects added with \texttt{k_fifo\_alloc\_put()} and \texttt{k_lifo\_alloc\_put()} do not have alignment constraints, but use temporary memory from the calling thread\'s resource pool.
[3] ISRs can receive only when passing \texttt{K\_NO\_WAIT} as the timeout argument.
[5] ISRs can send and/or receive only when passing \texttt{K\_NO\_WAIT} as the timeout argument.

### Queues

A Queue in Zephyr is a kernel object that implements a traditional queue, allowing threads and ISRs to add and remove data items of any size. The queue is similar to a FIFO and serves as the underlying implementation for both \texttt{k\_fifo} and \texttt{k\_lifo}. For more information on usage see \texttt{k\_fifo}.

### Configuration Options

Related configuration options:
- None

### API Reference

\texttt{group queue\_apis}

**Defines**

\texttt{K\_QUEUE\_DEFINE(name)}

Statically define and initialize a queue.

The queue can be accessed outside the module where it is defined using:

\begin{verbatim}
extern struct k_queue <name>;
\end{verbatim}
Functions

void k_queue_init(struct k_queue *queue)
Initialize a queue.
This routine initializes a queue object, prior to its first use.

Parameters
• queue – Address of the queue.

void k_queue_cancel_wait(struct k_queue *queue)
Cancel waiting on a queue.
This routine causes first thread pending on queue, if any, to return from k_queue_get() call with NULL value (as if timeout expired). If the queue is being waited on by k_poll(), it will return with -EINTR and K_POLL_STATE_CANCELLED state (and per above, subsequent k_queue_get() will return NULL).

Function properties (list may not be complete)
  isr-ok

Parameters
• queue – Address of the queue.

void k_queue_append(struct k_queue *queue, void *data)
Append an element to the end of a queue.
This routine appends a data item to queue. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

Function properties (list may not be complete)
  isr-ok

Parameters
• queue – Address of the queue.
• data – Address of the data item.

int32_t k_queue_alloc_append(struct k_queue *queue, void *data)
Append an element to a queue.
This routine appends a data item to queue. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread's resource pool, which is automatically freed when the item is removed. The data itself is not copied.

Function properties (list may not be complete)
  isr-ok

Parameters
• queue – Address of the queue.
• data – Address of the data item.

Return values
• 0 – on success
• -ENOMEM – if there isn’t sufficient RAM in the caller’s resource pool

void k_queue_prepend(struct k_queue *queue, void *data)
Prepend an element to a queue.
This routine prepends a data item to queue. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel’s use.

Function properties (list may not be complete)
irr-ok

Parameters
• queue – Address of the queue.
• data – Address of the data item.

int32_t k_queue_alloc_prepend(struct k_queue *queue, void *data)
Prepend an element to a queue.
This routine prepends a data item to queue. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread’s resource pool, which is automatically freed when the item is removed. The data itself is not copied.

Function properties (list may not be complete)
irr-ok

Parameters
• queue – Address of the queue.
• data – Address of the data item.

Return values
• 0 – on success
• -ENOMEM – if there isn’t sufficient RAM in the caller’s resource pool

void k_queue_insert(struct k_queue *queue, void *prev, void *data)
Inserts an element to a queue.
This routine inserts a data item to queue after previous item. A queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel’s use.

Function properties (list may not be complete)
irr-ok

Parameters
• queue – Address of the queue.
• prev – Address of the previous data item.
• data – Address of the data item.
int k_queue_append_list(struct k_queue *queue, void *head, void *tail)
  Atomically append a list of elements to a queue.

  This routine adds a list of data items to queue in one operation. The data items must be in a singly-linked list, with the first word in each data item pointing to the next data item; the list must be NULL-terminated.

  Function properties (list may not be complete)
  isr-ok

  Parameters
  • queue – Address of the queue.
  • head – Pointer to first node in singly-linked list.
  • tail – Pointer to last node in singly-linked list.

  Return values
  • 0 – on success
  • -EINVAL – on invalid supplied data

int k_queue_merge_slist(struct k_queue *queue, sys_slist_t *list)
  Atomically add a list of elements to a queue.

  This routine adds a list of data items to queue in one operation. The data items must be in a singly-linked list implemented using a sys_slist_t object. Upon completion, the original list is empty.

  Function properties (list may not be complete)
  isr-ok

  Parameters
  • queue – Address of the queue.
  • list – Pointer to sys_slist_t object.

  Return values
  • 0 – on success
  • -EINVAL – on invalid data

void *k_queue_get(struct k_queue *queue, k_timeout_t timeout)
  Get an element from a queue.

  This routine removes first data item from queue. The first word of the data item is reserved for the kernel's use.

  Function properties (list may not be complete)
  isr-ok

  Note: timeout must be set to K_NO_WAIT if called from ISR.

  Parameters
  • queue – Address of the queue.
• timeout – Non-negative waiting period to obtain a data item or one of the special values K_NO_WAIT and K_FOREVER.

**Returns**
Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

```c
bool k_queue_remove(struct k_queue *queue, void *data)
```

Remove an element from a queue.
This routine removes data item from `queue`. The first word of the data item is reserved for the kernel's use. Removing elements from `k_queue` rely on `sys_slist_find_and_remove` which is not a constant time operation.

**Function properties (list may not be complete)**
*isr-ok*

**Note:** `timeout` must be set to K_NO_WAIT if called from ISR.

**Parameters**
- `queue` – Address of the queue.
- `data` – Address of the data item.

**Returns**
true if data item was removed

```c
bool k_queue_unique_append(struct k_queue *queue, void *data)
```

Append an element to a queue only if it’s not present already.
This routine appends data item to `queue`. The first word of the data item is reserved for the kernel's use. Appending elements to `k_queue` relies on `sys_slist_is_node_in_list` which is not a constant time operation.

**Function properties (list may not be complete)**
*isr-ok*

**Parameters**
- `queue` – Address of the queue.
- `data` – Address of the data item.

**Returns**
true if data item was added, false if not

```c
int k_queue_is_empty(struct k_queue *queue)
```

Query a queue to see if it has data available.
Note that the data might be already gone by the time this function returns if other threads are also trying to read from the queue.

**Function properties (list may not be complete)**
*isr-ok*

**Parameters**
FIFOs

A FIFO is a kernel object that implements a traditional first in, first out (FIFO) queue, allowing threads and ISRs to add and remove data items of any size.

- Concepts
  - Implementation
    - Defining a FIFO
    - Writing to a FIFO
    - Reading from a FIFO
- Suggested Uses
- Configuration Options
- API Reference

Concepts  Any number of FIFOs can be defined (limited only by available RAM). Each FIFO is referenced by its memory address.

A FIFO has the following key properties:

- A queue of data items that have been added but not yet removed. The queue is implemented as a simple linked list.

A FIFO must be initialized before it can be used. This sets its queue to empty.

FIFO data items must be aligned on a word boundary, as the kernel reserves the first word of an item for use as a pointer to the next data item in the queue. Consequently, a data item that holds N bytes
of application data requires N+4 (or N+8) bytes of memory. There are no alignment or reserved space requirements for data items if they are added with `k_fifo_alloc_put()`, instead additional memory is temporarily allocated from the calling thread's resource pool.

A data item may be **added** to a FIFO by a thread or an ISR. The item is given directly to a waiting thread, if one exists; otherwise the item is added to the FIFO's queue. There is no limit to the number of items that may be queued.

A data item may be **removed** from a FIFO by a thread. If the FIFO's queue is empty a thread may choose to wait for a data item to be given. Any number of threads may wait on an empty FIFO simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

**Note:** The kernel does allow an ISR to remove an item from a FIFO, however the ISR must not attempt to wait if the FIFO is empty.

If desired, **multiple data items** can be added to a FIFO in a single operation if they are chained together into a singly-linked list. This capability can be useful if multiple writers are adding sets of related data items to the FIFO, as it ensures the data items in each set are not interleaved with other data items. Adding multiple data items to a FIFO is also more efficient than adding them one at a time, and can be used to guarantee that anyone who removes the first data item in a set will be able to remove the remaining data items without waiting.

### Implementation

**Defining a FIFO** A FIFO is defined using a variable of type `k_fifo`. It must then be initialized by calling `k_fifo_init()`.

The following code defines and initializes an empty FIFO.

```c
struct k_fifo my_fifo;
k_fifo_init(&my_fifo);
```

Alternatively, an empty FIFO can be defined and initialized at compile time by calling `K_FIFO_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_FIFO_DEFINE(my_fifo);
```

**Writing to a FIFO** A data item is added to a FIFO by calling `k_fifo_put()`.

The following code builds on the example above, and uses the FIFO to send data to one or more consumer threads.

```c
struct data_item_t {
    void *fifo_reserved; /* 1st word reserved for use by FIFO */
    ...
};

struct data_item_t tx_data;

void producer_thread(int unused1, int unused2, int unused3)
{
    while (1) {
        /* create data item to send */
        tx_data = ...
```
Additionally, a singly-linked list of data items can be added to a FIFO by calling `k_fifo_put_list()` or `k_fifo_put_slist()`.

Finally, a data item can be added to a FIFO with `k_fifo_alloc_put()`. With this API, there is no need to reserve space for the kernel’s use in the data item, instead additional memory will be allocated from the calling thread’s resource pool until the item is read.

Reading from a FIFO  A data item is removed from a FIFO by calling `k_fifo_get()`.

The following code builds on the example above, and uses the FIFO to obtain data items from a producer thread, which are then processed in some manner.

```c
void consumer_thread(int unused1, int unused2, int unused3)
{
    struct data_item_t *rx_data;

    while (1) {
        rx_data = k_fifo_get(&my_fifo, K_FOREVER);

        /* process FIFO data item */
        ...
    }
}
```

Suggested Uses  Use a FIFO to asynchronously transfer data items of arbitrary size in a “first in, first out” manner.

Configuration Options  Related configuration options:

- None

API Reference

group fifo_apis

Defines

`k_fifo_init(fifo)`

Initialize a FIFO queue.

This routine initializes a FIFO queue, prior to its first use.

Parameters

- `fifo` – Address of the FIFO queue.
k_fifo_cancel_wait(fifo)

Cancel waiting on a FIFO queue.

This routine causes first thread pending on fifo, if any, to return from \texttt{k_fifo_get()} call with NULL value (as if timeout expired).

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

\textbf{Parameters}
- \texttt{fifo} – Address of the FIFO queue.

\noindent k_fifo_put(fifo, data)

Add an element to a FIFO queue.

This routine adds a data item to \texttt{fifo}. A FIFO data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

\textbf{Parameters}
- \texttt{fifo} – Address of the FIFO.
- \texttt{data} – Address of the data item.

\noindent k_fifo_alloc_put(fifo, data)

Add an element to a FIFO queue.

This routine adds a data item to \texttt{fifo}. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread's resource pool, which is automatically freed when the item is removed. The data itself is not copied.

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

\textbf{Parameters}
- \texttt{fifo} – Address of the FIFO.
- \texttt{data} – Address of the data item.

\textbf{Return values}
- \texttt{0} – on success
- \texttt{-ENOMEM} – if there isn't sufficient RAM in the caller's resource pool

\noindent k_fifo_put_list(fifo, head, tail)

Atomically add a list of elements to a FIFO.

This routine adds a list of data items to \texttt{fifo} in one operation. The data items must be in a singly-linked list, with the first word of each data item pointing to the next data item; the list must be NULL-terminated.

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}
Parameters

• fifo – Address of the FIFO queue.
• head – Pointer to first node in singly-linked list.
• tail – Pointer to last node in singly-linked list.

\texttt{k_fifo_put_slist(fifo, list)}

Atomically add a list of elements to a FIFO queue.

This routine adds a list of data items to \texttt{fifo} in one operation. The data items must be in a singly-linked list implemented using a \texttt{sys\_slist\_t} object. Upon completion, the \texttt{sys\_slist\_t} object is invalid and must be re-initialized via \texttt{sys\_slist\_init()}.  

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

Parameters

• fifo – Address of the FIFO queue.
• list – Pointer to \texttt{sys\_slist\_t} object.

\texttt{k_fifo_get(fifo, timeout)}

Get an element from a FIFO queue.

This routine removes a data item from \texttt{fifo} in a “first in, first out” manner. The first word of the data item is reserved for the kernel’s use.

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

\textbf{Note:} \textit{timeout} must be set to \texttt{K\_NO\_WAIT} if called from ISR.

Parameters

• fifo – Address of the FIFO queue.
• timeout – Waiting period to obtain a data item, or one of the special values \texttt{K\_NO\_WAIT} and \texttt{K\_FOREVER}.

\textbf{Returns}

Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

\texttt{k_fifo_is_empty(fifo)}

Query a FIFO queue to see if it has data available.

Note that the data might be already gone by the time this function returns if other threads is also trying to read from the FIFO.

\textbf{Function properties (list may not be complete)}
\textit{isr-ok}

Parameters

• fifo – Address of the FIFO queue.
**Returns**
Non-zero if the FIFO queue is empty.

**Returns**
0 if data is available.

`k_fifo_peek_head(fifo)`
Peek element at the head of a FIFO queue.
Return element from the head of FIFO queue without removing it. A usecase for this is if elements of the FIFO object are themselves containers. Then on each iteration of processing, a head container will be peeked, and some data processed out of it, and only if the container is empty, it will be completely remove from the FIFO queue.

**Parameters**
- fifo – Address of the FIFO queue.

**Returns**
Head element, or NULL if the FIFO queue is empty.

`k_fifo_peek_tail(fifo)`
Peek element at the tail of FIFO queue.
Return element from the tail of FIFO queue (without removing it). A usecase for this is if elements of the FIFO queue are themselves containers. Then it may be useful to add more data to the last container in a FIFO queue.

**Parameters**
- fifo – Address of the FIFO queue.

**Returns**
Tail element, or NULL if a FIFO queue is empty.

`K_FIFO_DEFINE(name)`
Statically define and initialize a FIFO queue.
The FIFO queue can be accessed outside the module where it is defined using:

```c
extern struct k_fifo <name>;
```

**Parameters**
- name – Name of the FIFO queue.

**LIFOs**

A **LIFO** is a kernel object that implements a traditional last in, first out (LIFO) queue, allowing threads and ISRs to add and remove data items of any size.

- **Concepts**
- **Implementation**
  - **Defining a LIFO**
  - **Writing to a LIFO**
  - **Reading from a LIFO**
- **Suggested Uses**
Any number of LIFOs can be defined (limited only by available RAM). Each LIFO is referenced by its memory address.

A LIFO has the following key properties:

- A queue of data items that have been added but not yet removed. The queue is implemented as a simple linked list.

A LIFO must be initialized before it can be used. This sets its queue to empty.

LIFO data items must be aligned on a word boundary, as the kernel reserves the first word of an item for use as a pointer to the next data item in the queue. Consequently, a data item that holds \(N\) bytes of application data requires \(N+4\) (or \(N+8\)) bytes of memory. There are no alignment or reserved space requirements for data items if they are added with `k_lifo_alloc_put()`, instead additional memory is temporarily allocated from the calling thread’s resource pool.

A data item may be **added** to a LIFO by a thread or an ISR. The item is given directly to a waiting thread, if one exists; otherwise the item is added to the LIFO’s queue. There is no limit to the number of items that may be queued.

A data item may be **removed** from a LIFO by a thread. If the LIFO’s queue is empty a thread may choose to wait for a data item to be given. Any number of threads may wait on an empty LIFO simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

**Note:** The kernel does allow an ISR to remove an item from a LIFO, however the ISR must not attempt to wait if the LIFO is empty.

### Implementation

#### Defining a LIFO

A LIFO is defined using a variable of type `k_lifo`. It must then be initialized by calling `k_lifo_init()`.

The following defines and initializes an empty LIFO.

```c
struct k_lifo my_lifo;
k_lifo_init(&my_lifo);
```

Alternatively, an empty LIFO can be defined and initialized at compile time by calling `K_LIFO_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_LIFO_DEFINE(my_lifo);
```

#### Writing to a LIFO

A data item is added to a LIFO by calling `k_lifo_put()`.

The following code builds on the example above, and uses the LIFO to send data to one or more consumer threads.

```c
struct data_item_t {
    void *LIFO_reserved;       /* 1st word reserved for use by LIFO */
    ...
};
```
struct data_item_t tx_data;

void producer_thread(int unused1, int unused2, int unused3)
{
    while (1) {
        /* create data item to send */
        tx_data = ...;
        /* send data to consumers */
        k_lifo_put(&my_lifo, &tx_data);
        ...
    }
}

A data item can be added to a LIFO with `k_lifo_alloc_put()`. With this API, there is no need to reserve space for the kernel's use in the data item, instead additional memory will be allocated from the calling thread's resource pool until the item is read.

Reading from a LIFO  A data item is removed from a LIFO by calling `k_lifo_get()`.

The following code builds on the example above, and uses the LIFO to obtain data items from a producer thread, which are then processed in some manner.

```c
void consumer_thread(int unused1, int unused2, int unused3)
{
    struct data_item_t *rx_data;
    while (1) {
        rx_data = k_lifo_get(&my_lifo, K_FOREVER);
        /* process LIFO data item */
        ...
    }
}
```

Suggested Uses  Use a LIFO to asynchronously transfer data items of arbitrary size in a “last in, first out” manner.

Configuration Options  Related configuration options:

- None.

API Reference

`group lifo_apis`

Defines

- `k_lifo_init(lifo)`
  
  Initialize a LIFO queue.

  This routine initializes a LIFO queue object, prior to its first use.
Parameters

- lifo – Address of the LIFO queue.

\texttt{k\_lifo\_put( lifo, data )}

Add an element to a LIFO queue.

This routine adds a data item to \texttt{lifo}. A LIFO queue data item must be aligned on a word boundary, and the first word of the item is reserved for the kernel's use.

**Function properties (list may not be complete)**

\texttt{isr-ok}

Parameters

- lifo – Address of the LIFO queue.
- data – Address of the data item.

\texttt{k\_lifo\_alloc\_put( lifo, data )}

Add an element to a LIFO queue.

This routine adds a data item to \texttt{lifo}. There is an implicit memory allocation to create an additional temporary bookkeeping data structure from the calling thread's resource pool, which is automatically freed when the item is removed. The data itself is not copied.

**Function properties (list may not be complete)**

\texttt{isr-ok}

Parameters

- lifo – Address of the LIFO queue.
- data – Address of the data item.

Return values

- 0 – on success
- -ENOMEM – if there isn’t sufficient RAM in the caller’s resource pool

\texttt{k\_lifo\_get( lifo, timeout )}

Get an element from a LIFO queue.

This routine removes a data item from \texttt{LIFO} in a “last in, first out” manner. The first word of the data item is reserved for the kernel's use.

**Function properties (list may not be complete)**

\texttt{isr-ok}

\textbf{Note: } \texttt{timeout} must be set to \texttt{K\_NO\_WAIT} if called from ISR.

Parameters

- lifo – Address of the LIFO queue.
- timeout – Waiting period to obtain a data item, or one of the special values \texttt{K\_NO\_WAIT} and \texttt{K\_FOREVER}. 
Returns
Address of the data item if successful; NULL if returned without waiting, or waiting period timed out.

K_LIFO_DEFINE(name)
Statically define and initialize a LIFO queue.
The LIFO queue can be accessed outside the module where it is defined using:

extern struct k_lifo <name>;

Parameters

- name – Name of the fifo.

Stacks
A stack is a kernel object that implements a traditional last in, first out (LIFO) queue, allowing threads and ISRs to add and remove a limited number of integer data values.

- Concepts
- Implementation
  - Defining a Stack
  - Pushing to a Stack
  - Popping from a Stack
- Suggested Uses
- Configuration Options
- API Reference

Concepts Any number of stacks can be defined (limited only by available RAM). Each stack is referenced by its memory address.

A stack has the following key properties:

- A queue of integer data values that have been added but not yet removed. The queue is implemented using an array of stack_data_t values and must be aligned on a native word boundary. The stack_data_t type corresponds to the native word size i.e. 32 bits or 64 bits depending on the CPU architecture and compilation mode.

- A maximum quantity of data values that can be queued in the array.

A stack must be initialized before it can be used. This sets its queue to empty.

A data value can be added to a stack by a thread or an ISR. The value is given directly to a waiting thread, if one exists; otherwise the value is added to the LIFO’s queue.

Note: If CONFIG_NO_RUNTIME_CHECKS is enabled, the kernel will not detect and prevent attempts to add a data value to a stack that has already reached its maximum quantity of queued values. Adding a data value to a stack that is already full will result in array overflow, and lead to unpredictable behavior.
A data value may be removed from a stack by a thread. If the stack's queue is empty a thread may choose to wait for it to be given. Any number of threads may wait on an empty stack simultaneously. When a data item is added, it is given to the highest priority thread that has waited longest.

**Note:** The kernel does allow an ISR to remove an item from a stack, however the ISR must not attempt to wait if the stack is empty.

### Implementation

**Defining a Stack** A stack is defined using a variable of type `k_stack`. It must then be initialized by calling `k_stack_init()` or `k_stack_alloc_init()`. In the latter case, a buffer is not provided and it is instead allocated from the calling thread's resource pool.

The following code defines and initializes an empty stack capable of holding up to ten word-sized data values.

```c
#define MAX_ITEMS 10

stack_data_t my_stack_array[MAX_ITEMS];
struct k_stack my_stack;

k_stack_init(&my_stack, my_stack_array, MAX_ITEMS);
```

Alternatively, a stack can be defined and initialized at compile time by calling `K_STACK_DEFINE`.

The following code has the same effect as the code segment above. Observe that the macro defines both the stack and its array of data values.

```c
K_STACK_DEFINE(my_stack, MAX_ITEMS);
```

**Pushing to a Stack** A data item is added to a stack by calling `k_stack_push()`.

The following code builds on the example above, and shows how a thread can create a pool of data structures by saving their memory addresses in a stack.

```c
/* define array of data structures */
struct my_buffer_type {
    int field1;
    ...
};
struct my_buffer_type my_buffers[MAX_ITEMS];

/* save address of each data structure in a stack */
for (int i = 0; i < MAX_ITEMS; i++) {
    k_stack_push(&my_stack, (stack_data_t)&my_buffers[i]);
}
```

**Popping from a Stack** A data item is taken from a stack by calling `k_stack_pop()`.

The following code builds on the example above, and shows how a thread can dynamically allocate an unused data structure. When the data structure is no longer required, the thread must push its address back on the stack to allow the data structure to be reused.
struct my_buffer_type *new_buffer;

k_stack_pop(&buffer_stack, (stack_data_t *)&new_buffer, K_FOREVER);
new_buffer->field1 = ...  

Suggested Uses  Use a stack to store and retrieve integer data values in a “last in, first out” manner, when the maximum number of stored items is known.

Configuration Options  Related configuration options:
  • None.

API Reference

group stack_apis

Defines

K_STACK_DEFINE(name, stack_num_entries)
  Statically define and initialize a stack.
  The stack can be accessed outside the module where it is defined using:

  extern struct k_stack <name>;

Parameters
  • name – Name of the stack.
  • stack_num_entries – Maximum number of values that can be stacked.

Functions

void k_stack_init(struct k_stack *stack, stack_data_t *buffer, uint32_t num_entries)
  Initialize a stack.
  This routine initializes a stack object, prior to its first use.

  Parameters
    • stack – Address of the stack.
    • buffer – Address of array used to hold stacked values.
    • num_entries – Maximum number of values that can be stacked.

int32_t k_stack_alloc_init(struct k_stack *stack, uint32_t num_entries)
  Initialize a stack.
  This routine initializes a stack object, prior to its first use. Internal buffers will be allocated from the calling thread's resource pool. This memory will be released if k_stack_cleanup() is called, or userspace is enabled and the stack object loses all references to it.

  Parameters
    • stack – Address of the stack.
• `num_entries` – Maximum number of values that can be stacked.

**Returns**
- `ENOMEM` if memory couldn’t be allocated

```c
int k_stack_cleanup(struct k_stack *stack)
```
Release a stack’s allocated buffer.
If a stack object was given a dynamically allocated buffer via `k_stack_alloc_init()`, this will free it. This function does nothing if the buffer wasn’t dynamically allocated.

**Parameters**
- `stack` – Address of the stack.

**Return values**
- `0` – on success
- `-EAGAIN` – when object is still in use

```c
int k_stack_push(struct k_stack *stack, stack_data_t data)
```
Push an element onto a stack.
This routine adds a stack_data_t value `data` to `stack`.

**Function properties (list may not be complete)**

*`isr-ok`*

**Parameters**
- `stack` – Address of the stack.
- `data` – Value to push onto the stack.

**Return values**
- `0` – on success
- `-ENOMEM` – if stack is full

```c
int k_stack_pop(struct k_stack *stack, stack_data_t *data, k_timeout_t timeout)
```
Pop an element from a stack.
This routine removes a stack_data_t value from `stack` in a “last in, first out” manner and stores the value in `data`.

**Function properties (list may not be complete)**

*`isr-ok`*

**Parameters**
- `stack` – Address of the stack.
- `data` – Address of area to hold the value popped from the stack.
- `timeout` – Waiting period to obtain a value, or one of the special values `K_NO_WAIT` and `K_FOREVER`.

**Return values**
- `0` – Element popped from stack.

---

**Note:** `timeout` must be set to `K_NO_WAIT` if called from ISR.
Message Queues

A *message queue* is a kernel object that implements a simple message queue, allowing threads and ISRs to asynchronously send and receive fixed-size data items.

**Concepts**

Any number of message queues can be defined (limited only by available RAM). Each message queue is referenced by its memory address.

A message queue has the following key properties:

- A *ring buffer* of data items that have been sent but not yet received.
- A *data item size*, measured in bytes.
- A *maximum quantity* of data items that can be queued in the ring buffer.

The message queue's ring buffer must be aligned to an N-byte boundary, where N is a power of 2 (i.e. 1, 2, 4, 8, \ldots). To ensure that the messages stored in the ring buffer are similarly aligned to this boundary, the data item size must also be a multiple of N.

A message queue must be initialized before it can be used. This sets its ring buffer to empty.

A data item can be **sent** to a message queue by a thread or an ISR. The data item pointed at by the sending thread is copied to a waiting thread, if one exists; otherwise the item is copied to the message queue's ring buffer, if space is available. In either case, the size of the data area being sent must equal the message queue's data item size.

If a thread attempts to send a data item when the ring buffer is full, the sending thread may choose to wait for space to become available. Any number of sending threads may wait simultaneously when the ring buffer is full; when space becomes available it is given to the highest priority sending thread that has waited the longest.

A data item can be **received** from a message queue by a thread. The data item is copied to the area specified by the receiving thread; the size of the receiving area must equal the message queue's data item size.

If a thread attempts to receive a data item when the ring buffer is empty, the receiving thread may choose to wait for a data item to be sent. Any number of receiving threads may wait simultaneously when the ring buffer is empty; when a data item becomes available it is given to the highest priority receiving thread that has waited the longest.
A thread can also **peek** at the message on the head of a message queue without removing it from the queue. The data item is copied to the area specified by the receiving thread; the size of the receiving area **must** equal the message queue's data item size.

**Note:** The kernel does allow an ISR to receive an item from a message queue, however the ISR must not attempt to wait if the message queue is empty.

---

### Implementation

#### Defining a Message Queue

A message queue is defined using a variable of type `k_msgq`. It must then be initialized by calling `k_msgq_init()`.

The following code defines and initializes an empty message queue that is capable of holding 10 items, each of which is 12 bytes long.

```c
struct data_item_type {
    uint32_t field1;
    uint32_t field2;
    uint32_t field3;
};

char __aligned(4) my_msgq_buffer[10 * sizeof(struct data_item_type)];
struct k_msgq my_msgq;

k_msgq_init(&my_msgq, my_msgq_buffer, sizeof(struct data_item_type), 10);
```

Alternatively, a message queue can be defined and initialized at compile time by calling `K_MSGQ_DEFINE`.

The following code has the same effect as the code segment above. Observe that the macro defines both the message queue and its buffer.

```c
K_MSGQ_DEFINE(my_msgq, sizeof(struct data_item_type), 10, 4);
```

The following code demonstrates an alignment implementation for the structure defined in the previous example code. `aligned` means each `data_item_type` will begin on the specified byte boundary. `aligned(4)` means that the structure is aligned to an address that is divisible by 4.

```c
typedef struct {
    uint32_t field1;
    uint32_t field2;
    uint32_t field3;
}__attribute__((aligned(4))) data_item_type;
```

#### Writing to a Message Queue

A data item is added to a message queue by calling `k_msgq_put()`.

The following code builds on the example above, and uses the message queue to pass data items from a producing thread to one or more consuming threads. If the message queue fills up because the consumers can't keep up, the producing thread throws away all existing data so the newer data can be saved.

```c
void producer_thread(void)
{
    struct data_item_type data;

    while (1) {
        /* create data item to send (e.g. measurement, timestamp, ...) */
        // (continues on next page)
    }
}
```
Reading from a Message Queue
A data item is taken from a message queue by calling `k_msgq_get()`. The following code builds on the example above, and uses the message queue to process data items generated by one or more producing threads. Note that the return value of `k_msgq_get()` should be tested as `-ENOMEM` can be returned due to `k_msgq_purge()`.

```c
void consumer_thread(void)
{
    struct data_item_type data;

    while (1) {
        /* get a data item */
        k_msgq_get(&my_msgq, &data, K_FOREVER);

        /* process data item */
        ...
    }
}
```

Peeking into a Message Queue
A data item is read from a message queue by calling `k_msgq_peek()`. The following code peeks into the message queue to read the data item at the head of the queue that is generated by one or more producing threads.

```c
void consumer_thread(void)
{
    struct data_item_type data;

    while (1) {
        /* read a data item by peeking into the queue */
        k_msgq_peek(&my_msgq, &data);

        /* process data item */
        ...
    }
}
```

Suggested Uses
Use a message queue to transfer small data items between threads in an asynchronous manner.

Note: A message queue can be used to transfer large data items, if desired. However, this can increase interrupt latency as interrupts are locked while a data item is written or read. The time to write or read
A data item increases linearly with its size since the item is copied in its entirety to or from the buffer in memory. For this reason, it is usually preferable to transfer large data items by exchanging a pointer to the data item, rather than the data item itself.

A synchronous transfer can be achieved by using the kernel’s mailbox object type.

**Configuration Options**  Related configuration options:
- None.

**API Reference**

*group msgq_apis*

**Defines**

K_MSGQ_FLAG_ALLOC  
K_MSGQ_DEFINE(q_name, q_msg_size, q_max_msgs, q_align)

Synchronously define and initialize a message queue.

The message queue’s ring buffer contains space for q_max_msgs messages, each of which is q_msg_size bytes long. The buffer is aligned to a q_align-byte boundary, which must be a power of 2. To ensure that each message is similarly aligned to this boundary, q_msg_size must also be a multiple of q_align.

The message queue can be accessed outside the module where it is defined using:

```c
extern struct k_msgq <name>;
```

**Parameters**

- q_name – Name of the message queue.
- q_msg_size – Message size (in bytes).
- q_max_msgs – Maximum number of messages that can be queued.
- q_align – Alignment of the message queue’s ring buffer.

**Functions**

void k_msgq_init(struct k_msgq *msgq, char *buffer, size_t msg_size, uint32_t max_msgs)

Initialize a message queue.

This routine initializes a message queue object, prior to its first use.

The message queue’s ring buffer must contain space for max_msgs messages, each of which is msg_size bytes long. The buffer must be aligned to an N-byte boundary, where N is a power of 2 (i.e., 1, 2, 4, ...). To ensure that each message is similarly aligned to this boundary, q_msg_size must also be a multiple of N.

**Parameters**

- msgq – Address of the message queue.
- buffer – Pointer to ring buffer that holds queued messages.
- **msg_size** – Message size (in bytes).
- **max_msgs** – Maximum number of messages that can be queued.

```c
int k_msgq_alloc_init(struct k_msgq *msgq, size_t msg_size, uint32_t max_msgs)
```

Initialize a message queue.

This routine initializes a message queue object, prior to its first use, allocating its internal ring buffer from the calling thread’s resource pool.

Memory allocated for the ring buffer object can be released by calling `k_msgq_cleanup()`, or if userspace is enabled and the msgq object loses all of its references.

**Parameters**

- **msgq** – Address of the message queue.
- **msg_size** – Message size (in bytes).
- **max_msgs** – Maximum number of messages that can be queued.

**Returns**

0 on success, -ENOMEM if there was insufficient memory in the thread’s resource pool, or -EINVAL if the size parameters cause an integer overflow.

```c
int k_msgq_cleanup(struct k_msgq *msgq)
```

Release allocated buffer for a queue.

Releases memory allocated for the ring buffer.

**Parameters**

- **msgq** – message queue to cleanup

**Return values**

- 0 – on success
- -EBUSY – Queue not empty

```c
int k_msgq_put(struct k_msgq *msgq, const void *data, k_timeout_t timeout)
```

Send a message to a message queue.

This routine sends a message to message queue q.

**Function properties (list may not be complete)**

- `isr-ok`

**Note:** The message content is copied from `data` into `msgq` and the `data` pointer is not retained, so the message content will not be modified by this function.

**Parameters**

- **msgq** – Address of the message queue.
- **data** – Pointer to the message.
- **timeout** – Non-negative waiting period to add the message, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**

- 0 – Message sent.
- -ENOMEM – Returned without waiting or queue purged.
- -EAGAIN – Waiting period timed out.
int k_msgq_get(struct k_msgq *msgq, void *data, k_timeout_t timeout)

Receive a message from a message queue.
This routine receives a message from message queue q in a “first in, first out” manner.

Function properties (list may not be complete)

isr-ok

Note: timeout must be set to K_NO_WAIT if called from ISR.

Parameters
- msgq – Address of the message queue.
- data – Address of area to hold the received message.
- timeout – Waiting period to receive the message, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
- 0 – Message received.
- -ENOMEM – Returned without waiting.
- -EAGAIN – Waiting period timed out.

int k_msgq_peek(struct k_msgq *msgq, void *data)

Peek/read a message from a message queue.
This routine reads a message from message queue q in a “first in, first out” manner and leaves the message in the queue.

Function properties (list may not be complete)

isr-ok

Parameters
- msgq – Address of the message queue.
- data – Address of area to hold the message read from the queue.

Return values
- 0 – Message read.
- -ENOMEM – Returned when the queue has no message.

void k_msgq_purge(struct k_msgq *msgq)

Purge a message queue.
This routine discards all unreceived messages in a message queue's ring buffer. Any threads that are blocked waiting to send a message to the message queue are unblocked and see an -ENOMEM error code.

Parameters
- msgq – Address of the message queue.


```c
uint32_t k_msgq_num_free_get(struct k_msgq *msgq)
Get the amount of free space in a message queue.

This routine returns the number of unused entries in a message queue's ring buffer.

Parameters
• msgq – Address of the message queue.

Returns
Number of unused ring buffer entries.
```

```c
void k_msgq_get_attrs(struct k_msgq *msgq, struct k_msgq_attrs *attrs)
Get basic attributes of a message queue.

This routine fetches basic attributes of message queue into attr argument.

Parameters
• msgq – Address of the message queue.
• attrs – pointer to message queue attribute structure.
```

```c
uint32_t k_msgq_num_used_get(struct k_msgq *msgq)
Get the number of messages in a message queue.

This routine returns the number of messages in a message queue's ring buffer.

Parameters
• msgq – Address of the message queue.

Returns
Number of messages.
```

```c
struct k_msgq
#include <kernel.h> Message Queue Structure.
```

**Public Members**

```c
_wait_q_t wait_q
Message queue wait queue
```

```c
struct k_spinlock lock
Lock
```

```c
size_t msg_size
Message size
```

```c
uint32_t max_msgs
Maximal number of messages
```

```c
char *buffer_start
Start of message buffer
```

```c
char *buffer_end
End of message buffer
```
char *read_ptr
    Read pointer

cchar *write_ptr
    Write pointer

uint32_t used_msgs
    Number of used messages

uint8_t flags
    Message queue

struct k_msgq_attrs
    #include <kernel.h> Message Queue Attributes.

Public Members

size_t msg_size
    Message Size

uint32_t max_msgs
    Maximal number of messages

uint32_t used_msgs
    Used messages

Mailboxes

A mailbox is a kernel object that provides enhanced message queue capabilities that go beyond the capabilities of a message queue object. A mailbox allows threads to send and receive messages of any size synchronously or asynchronously.

- **Concepts**
  - Message Format
  - Message Lifecycle
  - Thread Compatibility
  - Message Flow Control

- **Implementation**
  - Defining a Mailbox
  - Message Descriptors
  - Sending a Message
  - Receiving a Message

- **Suggested Uses**
- **Configuration Options**
Concepts  Any number of mailboxes can be defined (limited only by available RAM). Each mailbox is referenced by its memory address.

A mailbox has the following key properties:

- A **send queue** of messages that have been sent but not yet received.
- A **receive queue** of threads that are waiting to receive a message.

A mailbox must be initialized before it can be used. This sets both of its queues to empty.

A mailbox allows threads, but not ISRs, to exchange messages. A thread that sends a message is known as the **sending thread**, while a thread that receives the message is known as the **receiving thread**. Each message may be received by only one thread (i.e. point-to-multipoint and broadcast messaging is not supported).

Messages exchanged using a mailbox are handled non-anonymously, allowing both threads participating in an exchange to know (and even specify) the identity of the other thread.

**Message Format**  A **message descriptor** is a data structure that specifies where a message's data is located, and how the message is to be handled by the mailbox. Both the sending thread and the receiving thread supply a message descriptor when accessing a mailbox. The mailbox uses the message descriptors to perform a message exchange between compatible sending and receiving threads. The mailbox also updates certain message descriptor fields during the exchange, allowing both threads to know what has occurred.

A mailbox message contains zero or more bytes of **message data**. The size and format of the message data is application-defined, and can vary from one message to the next.

A **message buffer** is an area of memory provided by the thread that sends or receives the message data. An array or structure variable can often be used for this purpose.

A message that has neither form of message data is called an **empty message**.

**Note:**  A message whose message buffer exists, but contains zero bytes of actual data, is *not* an empty message.

**Message Lifecycle**  The life cycle of a message is straightforward. A message is created when it is given to a mailbox by the sending thread. The message is then owned by the mailbox until it is given to a receiving thread. The receiving thread may retrieve the message data when it receives the message from the mailbox, or it may perform data retrieval during a second, subsequent mailbox operation. Only when data retrieval has occurred is the message deleted by the mailbox.

**Thread Compatibility**  A sending thread can specify the address of the thread to which the message is sent, or send it to any thread by specifying `K_ANY`. Likewise, a receiving thread can specify the address of the thread from which it wishes to receive a message, or it can receive a message from any thread by specifying `K_ANY`. A message is exchanged only when the requirements of both the sending thread and receiving thread are satisfied; such threads are said to be **compatible**.

For example, if thread A sends a message to thread B (and only thread B) it will be received by thread B if thread B tries to receive a message from thread A or if thread B tries to receive from any thread. The exchange will not occur if thread B tries to receive a message from thread C. The message can never be received by thread C, even if it tries to receive a message from thread A (or from any thread).
Message Flow Control Mailbox messages can be exchanged synchronously or asynchronously. In a synchronous exchange, the sending thread blocks until the message has been fully processed by the receiving thread. In an asynchronous exchange, the sending thread does not wait until the message has been received by another thread before continuing; this allows the sending thread to do other work (such as gather data that will be used in the next message) before the message is given to a receiving thread and fully processed. The technique used for a given message exchange is determined by the sending thread.

The synchronous exchange technique provides an implicit form of flow control, preventing a sending thread from generating messages faster than they can be consumed by receiving threads. The asynchronous exchange technique provides an explicit form of flow control, which allows a sending thread to determine if a previously sent message still exists before sending a subsequent message.

Implementation

Defining a Mailbox A mailbox is defined using a variable of type \texttt{k_mbox}. It must then be initialized by calling \texttt{k_mbox_init()}. The following code defines and initializes an empty mailbox.

```c
struct k_mbox my_mailbox;
k_mbox_init(&my_mailbox);
```

Alternatively, a mailbox can be defined and initialized at compile time by calling \texttt{K_MBOX_DEFINE}. The following code has the same effect as the code segment above.

```c
K_MBOX_DEFINE(my_mailbox);
```

Message Descriptors A message descriptor is a structure of type \texttt{k_mbox_msg}. Only the fields listed below should be used; any other fields are for internal mailbox use only.

\textbf{info} A 32-bit value that is exchanged by the message sender and receiver, and whose meaning is defined by the application. This exchange is bi-directional, allowing the sender to pass a value to the receiver during any message exchange, and allowing the receiver to pass a value to the sender during a synchronous message exchange.

\textbf{size} The message data size, in bytes. Set it to zero when sending an empty message, or when sending a message buffer with no actual data. When receiving a message, set it to the maximum amount of data desired, or to zero if the message data is not wanted. The mailbox updates this field with the actual number of data bytes exchanged once the message is received.

\textbf{tx_data} A pointer to the sending thread's message buffer. Set it to \texttt{NULL} when sending an empty message. Leave this field uninitialized when receiving a message.

\textbf{tx_target_thread} The address of the desired receiving thread. Set it to \texttt{K_ANY} to allow any thread to receive the message. Leave this field uninitialized when receiving a message. The mailbox updates this field with the actual receiver's address once the message is received.

\textbf{rx_source_thread} The address of the desired sending thread. Set it to \texttt{K_ANY} to receive a message sent by any thread. Leave this field uninitialized when sending a message. The mailbox updates this field with the actual sender's address when the message is put into the mailbox.
Sending a Message  A thread sends a message by first creating its message data, if any. Next, the sending thread creates a message descriptor that characterizes the message to be sent, as described in the previous section. Finally, the sending thread calls a mailbox send API to initiate the message exchange. The message is immediately given to a compatible receiving thread, if one is currently waiting. Otherwise, the message is added to the mailbox's send queue. Any number of messages may exist simultaneously on a send queue. The messages in the send queue are sorted according to the priority of the sending thread. Messages of equal priority are sorted so that the oldest message can be received first. For a synchronous send operation, the operation normally completes when a receiving thread has both received the message and retrieved the message data. If the message is not received before the waiting period specified by the sending thread is reached, the message is removed from the mailbox's send queue and the send operation fails. When a send operation completes successfully the sending thread can examine the message descriptor to determine which thread received the message, how much data was exchanged, and the application-defined info value supplied by the receiving thread.

Note: A synchronous send operation may block the sending thread indefinitely, even when the thread specifies a maximum waiting period. The waiting period only limits how long the mailbox waits before the message is received by another thread. Once a message is received there is no limit to the time the receiving thread may take to retrieve the message data and unblock the sending thread.

For an asynchronous send operation, the operation always completes immediately. This allows the sending thread to continue processing regardless of whether the message is given to a receiving thread immediately or added to the send queue. The sending thread may optionally specify a semaphore that the mailbox gives when the message is deleted by the mailbox, for example, when the message has been received and its data retrieved by a receiving thread. The use of a semaphore allows the sending thread to easily implement a flow control mechanism that ensures that the mailbox holds no more than an application-specified number of messages from a sending thread (or set of sending threads) at any point in time.

Note: A thread that sends a message asynchronously has no way to determine which thread received the message, how much data was exchanged, or the application-defined info value supplied by the receiving thread.

Sending an Empty Message  This code uses a mailbox to synchronously pass 4 byte random values to any consuming thread that wants one. The message “info” field is large enough to carry the information being exchanged, so the data portion of the message isn’t used.

```c
void producer_thread(void)
{
    struct k_mbox_msg send_msg;

    while (1) {
        /* generate random value to send */
        uint32_t random_value = sys_rand32_get();

        /* prepare to send empty message */
        send_msg.info = random_value;
        send_msg.size = 0;
        send_msg.tx_data = NULL;
        send_msg.tx_block.data = NULL;
    }
}
```
Sending Data Using a Message Buffer  This code uses a mailbox to synchronously pass variable-sized requests from a producing thread to any consuming thread that wants it. The message “info” field is used to exchange information about the maximum size message buffer that each thread can handle.

```c
void producer_thread(void)
{
    char buffer[100];
    int buffer_bytes_used;

    struct k_mbox_msg send_msg;

    while (1) {
        /* generate data to send */
        ...
        buffer_bytes_used = ... ;
        memcpy(buffer, source, buffer_bytes_used);

        /* prepare to send message */
        send_msg.info = buffer_bytes_used;
        send_msg.size = buffer_bytes_used;
        send_msg.tx_data = buffer;
        send_msg.tx_block.data = NULL;
        send_msg.tx_target_thread = K_ANY;

        /* send message and wait until a consumer receives it */
        k_mbox_put(&my_mailbox, &send_msg, K_FOREVER);

        /* info, size, and tx_target_thread fields have been updated */

        /* verify that message data was fully received */
        if (send_msg.size < buffer_bytes_used) {
            printf("some message data dropped during transfer!");
            printf("receiver only had room for %d bytes", send_msg.info);
        }
    }
}
```

Receiving a Message  A thread receives a message by first creating a message descriptor that characterizes the message it wants to receive. It then calls one of the mailbox receive APIs. The mailbox searches its send queue and takes the message from the first compatible thread it finds. If no compatible thread exists, the receiving thread may choose to wait for one. If no compatible thread appears before the waiting period specified by the receiving thread is reached, the receive operation fails. Once a receive operation completes successfully the receiving thread can examine the message descriptor to determine which thread sent the message, how much data was exchanged, and the application-defined info value supplied by the sending thread.

Any number of receiving threads may wait simultaneously on a mailboxes' receive queue. The threads
are sorted according to their priority; threads of equal priority are sorted so that the one that started
waiting first can receive a message first.

**Note:** Receiving threads do not always receive messages in a first in, first out (FIFO) order, due to the
thread compatibility constraints specified by the message descriptors. For example, if thread A waits to
receive a message only from thread X and then thread B waits to receive a message from thread Y, an
incoming message from thread Y to any thread will be given to thread B and thread A will continue to
wait.

The receiving thread controls both the quantity of data it retrieves from an incoming message and where
the data ends up. The thread may choose to take all of the data in the message, to take only the initial
part of the data, or to take no data at all. Similarly, the thread may choose to have the data copied into
a message buffer of its choice.

The following sections outline various approaches a receiving thread may use when retrieving message
data.

**Retrieving Data at Receive Time** The most straightforward way for a thread to retrieve message data
is to specify a message buffer when the message is received. The thread indicates both the location of
the message buffer (which must not be NULL) and its size.

The mailbox copies the message's data to the message buffer as part of the receive operation. If the
message buffer is not big enough to contain all of the message's data, any uncopied data is lost. If the
message is not big enough to fill all of the buffer with data, the unused portion of the message buffer
is left unchanged. In all cases the mailbox updates the receiving thread's message descriptor to indicate
how many data bytes were copied (if any).

The immediate data retrieval technique is best suited for small messages where the maximum size of a
message is known in advance.

The following code uses a mailbox to process variable-sized requests from any producing thread, using
the immediate data retrieval technique. The message "info" field is used to exchange information about
the maximum size message buffer that each thread can handle.

```c
void consumer_thread(void)
{
    struct k_mbox_msg recv_msg;
    char buffer[100];
    int i;
    int total;

    while (1) {
        /* prepare to receive message */
        recv_msg.info = 100;
        recv_msg.size = 100;
        recv_msg.rx_source_thread = K_ANY;

        /* get a data item, waiting as long as needed */
        k_mbox_get(&my_mailbox, &recv_msg, buffer, K_FOREVER);

        /* info, size, and rx_source_thread fields have been updated */

        /* verify that message data was fully received */
        if (recv_msg.info != recv_msg.size) {
            printf("some message data dropped during transfer!");
            printf("sender tried to send %d bytes", recv_msg.info);
        }
    }
}
```

(continues on next page)
compute sum of all message bytes (from 0 to 100 of them) */
    total = 0;
    for (i = 0; i < recv_msg.size; i++) {
        total += buffer[i];
    }
}

Retrieving Data Later Using a Message Buffer

A receiving thread may choose to defer message data retrieval at the time the message is received, so that it can retrieve the data into a message buffer at a later time. The thread does this by specifying a message buffer location of NULL and a size indicating the maximum amount of data it is willing to retrieve later.

The mailbox does not copy any message data as part of the receive operation. However, the mailbox still updates the receiving thread’s message descriptor to indicate how many data bytes are available for retrieval.

The receiving thread must then respond as follows:

- If the message descriptor size is zero, then either the sender's message contained no data or the receiving thread did not want to receive any data. The receiving thread does not need to take any further action, since the mailbox has already completed data retrieval and deleted the message.
- If the message descriptor size is non-zero and the receiving thread still wants to retrieve the data, the thread must call k_mbox_data_get() and supply a message buffer large enough to hold the data. The mailbox copies the data into the message buffer and deletes the message.
- If the message descriptor size is non-zero and the receiving thread does not want to retrieve the data, the thread must call k_mbox_data_get() and specify a message buffer of NULL. The mailbox deletes the message without copying the data.

The subsequent data retrieval technique is suitable for applications where immediate retrieval of message data is undesirable. For example, it can be used when memory limitations make it impractical for the receiving thread to always supply a message buffer capable of holding the largest possible incoming message.

The following code uses a mailbox’s deferred data retrieval mechanism to get message data from a producing thread only if the message meets certain criteria, thereby eliminating unneeded data copying. The message “info” field supplied by the sender is used to classify the message.

```c
void consumer_thread(void)
{
    struct k_mbox_msg recv_msg;
    char buffer[10000];

    while (1) {
        /* prepare to receive message */
        recv_msg.size = 10000;
        recv_msg.rx_source_thread = K_ANY;

        /* get message, but not its data */
        k_mbox_get(&my_mailbox, &recv_msg, NULL, K_FOREVER);

        /* get message data for only certain types of messages */
        if (is_message_type_ok(recv_msg.info)) {
            /* retrieve message data and delete the message */
            k_mbox_data_get(&recv_msg, buffer);
```

(continues on next page)
Suggested Uses  Use a mailbox to transfer data items between threads whenever the capabilities of a message queue are insufficient.

Configuration Options  Related configuration options:

• CONFIG_NUM_MBOX_ASYNC_MSGS

API Reference

group mailbox_apis

Defines

K_MBOX_DEFINE(name)

Statically define and initialize a mailbox.

The mailbox is to be accessed outside the module where it is defined using:

extern struct k_mbox <name>;

Parameters

• name – Name of the mailbox.

Functions

void k_mbox_init(struct k mbox *mbox)

Initialize a mailbox.

This routine initializes a mailbox object, prior to its first use.

Parameters

• mbox – Address of the mailbox.

int k_mbox_put(struct k mbox *mbox, struct k mbox_msg *tx_msg, k_timeout_t timeout)

Send a mailbox message in a synchronous manner.

This routine sends a message to mbox and waits for a receiver to both receive and process it.

The message data may be in a buffer, in a memory pool block, or non-existent (i.e. an empty message).

Parameters

• mbox – Address of the mailbox.
• tx_msg – Address of the transmit message descriptor.

• timeout – Waiting period for the message to be received, or one of the special values K_NO_WAIT and K_FOREVER. Once the message has been received, this routine waits as long as necessary for the message to be completely processed.

Return values

• 0 – Message sent.

• -ENOMSG – Returned without waiting.

• -EAGAIN – Waiting period timed out.

void k_mbox_async_put (struct k_mbox *mbox, struct k_mbox_msg *tx_msg, struct k_sem *sem)

Send a mailbox message in an asynchronous manner.

This routine sends a message to mbox without waiting for a receiver to process it. The message data may be in a buffer, in a memory pool block, or non-existent (i.e. an empty message). Optionally, the semaphore sem will be given when the message has been both received and completely processed by the receiver.

Parameters

• mbox – Address of the mailbox.

• tx_msg – Address of the transmit message descriptor.

• sem – Address of a semaphore, or NULL if none is needed.

int k_mbox_get (struct k_mbox *mbox, struct k_mbox_msg *rx_msg, void *buffer, k_timeout_t timeout)

Receive a mailbox message.

This routine receives a message from mbox, then optionally retrieves its data and disposes of the message.

Parameters

• mbox – Address of the mailbox.

• rx_msg – Address of the receive message descriptor.

• buffer – Address of the buffer to receive data, or NULL to defer data retrieval and message disposal until later.

• timeout – Waiting period for a message to be received, or one of the special values K_NO_WAIT and K_FOREVER.

Return values

• 0 – Message received.

• -ENOMSG – Returned without waiting.

• -EAGAIN – Waiting period timed out.

void k_mbox_data_get (struct k_mbox_msg *rx_msg, void *buffer)

Retrieve mailbox message data into a buffer.

This routine completes the processing of a received message by retrieving its data into a buffer, then disposing of the message.

Alternatively, this routine can be used to dispose of a received message without retrieving its data.

Parameters

• rx_msg – Address of the receive message descriptor.

• buffer – Address of the buffer to receive data, or NULL to discard the data.
struct k_mbox_msg
    
    include <kernel.h> Mailbox Message Structure.

Public Members

size_t size
    size of message (in bytes)

uint32_t info
    application-defined information value

void *tx_data
    sender's message data buffer

struct k_mem_block tx_block
    message data block descriptor

k_tid_t rx_source_thread
    source thread id

k_tid_t tx_target_thread
    target thread id

struct k_mbox
    include <kernel.h> Mailbox Structure.

Public Members

_wait_q_t tx_msg_queue
    Transmit messages queue

_wait_q_t rx_msg_queue
    Receive message queue

Pipes

A pipe is a kernel object that allows a thread to send a byte stream to another thread. Pipes can be used to synchronously transfer chunks of data in whole or in part.

- Concepts
- Implementation
  - Writing to a Pipe
  - Reading from a Pipe
  - Flushing a Pipe's Buffer
  - Flushing a Pipe
The pipe can be configured with a ring buffer which holds data that has been sent but not yet received; alternatively, the pipe may have no ring buffer.

Any number of pipes can be defined (limited only by available RAM). Each pipe is referenced by its memory address.

A pipe has the following key property:

- A size that indicates the size of the pipe's ring buffer. Note that a size of zero defines a pipe with no ring buffer.

A pipe must be initialized before it can be used. The pipe is initially empty.

Data is synchronously sent either in whole or in part to a pipe by a thread. If the specified minimum number of bytes can not be immediately satisfied, then the operation will either fail immediately or attempt to send as many bytes as possible and then pend in the hope that the send can be completed later. Accepted data is either copied to the pipe's ring buffer or directly to the waiting reader(s).

Data is synchronously received from a pipe by a thread. If the specified minimum number of bytes can not be immediately satisfied, then the operation will either fail immediately or attempt to receive as many bytes as possible and then pend in the hope that the receive can be completed later. Accepted data is either copied from the pipe's ring buffer or directly from the waiting sender(s).

Data may also be flushed from a pipe by a thread. Flushing can be performed either on the entire pipe or on only its ring buffer. Flushing the entire pipe is equivalent to reading all the information in the ring buffer and waiting to be written into a giant temporary buffer which is then discarded. Flushing the ring buffer is equivalent to reading only the data in the ring buffer into a temporary buffer which is then discarded. Flushing the ring buffer does not guarantee that the ring buffer will stay empty; flushing it may allow a pended writer to fill the ring buffer.

**Note:** Flushing does not in practice allocate or use additional buffers.

**Note:** The kernel does allow for an ISR to flush a pipe from an ISR. It also allows it to send/receive data to/from one provided it does not attempt to wait for space/data.

### Implementation

A pipe is defined using a variable of type `k_pipe` and an optional character buffer of type `unsigned char`. It must then be initialized by calling `k_pipe_init()`.

The following code defines and initializes an empty pipe that has a ring buffer capable of holding 100 bytes and is aligned to a 4-byte boundary.

```c
unsigned char __aligned(4) my_ring_buffer[100];
struct k_pipe my_pipe;

k_pipe_init(&my_pipe, my_ring_buffer, sizeof(my_ring_buffer));
```

Alternatively, a pipe can be defined and initialized at compile time by calling `K_PIPE_DEFINE`.

The following code has the same effect as the code segment above. Observe that that macro defines both the pipe and its ring buffer.
K_PIPE_DEFINE(my_pipe, 100, 4);

**Writing to a Pipe**  Data is added to a pipe by calling `k.pipe_put()`.
The following code builds on the example above, and uses the pipe to pass data from a producing thread
to one or more consuming threads. If the pipe's ring buffer fills up because the consumers can't keep up,
the producing thread waits for a specified amount of time.

```c
struct message_header {
  ...
};

void producer_thread(void)
{
  unsigned char *data;
  size_t total_size;
  size_t bytes_written;
  int    rc;
  ...

  while (1) {
    /* Craft message to send in the pipe */
    data = ...;
    total_size = ...;

    /* send data to the consumers */
    rc = k.pipe_put(&my_pipe, data, total_size, &bytes_written,
                    sizeof(struct message_header), K_NO_WAIT);

    if (rc < 0) {
      /* Incomplete message header sent */
      ...
    } else if (bytes_written < total_size) {
      /* Some of the data was sent */
      ...
    } else {
      /* All data sent */
      ...
    }
  }
}
```

**Reading from a Pipe**  Data is read from the pipe by calling `k.pipe_get()`.
The following code builds on the example above, and uses the pipe to process data items generated by
one or more producing threads.

```c
void consumer_thread(void)
{
  unsigned char buffer[120];
  size_t  bytes_read;
  struct message_header *header = (struct message_header *)buffer;

  while (1) {
    rc = k.pipe_get(&my_pipe, buffer, sizeof(buffer), &bytes_read,
                    sizeof(header), K_MSEC(100));

    (continues on next page)
```
if ((rc < 0) || (bytes_read < sizeof (header))) {
    /* Incomplete message header received */
    ...
} else if (header->num_data_bytes + sizeof(header) > bytes_read) {
    /* Only some data was received */
    ...
} else {
    /* All data was received */
    ...
}
}

Use a pipe to send streams of data between threads.

**Note:** A pipe can be used to transfer long streams of data if desired. However it is often preferable to send pointers to large data items to avoid copying the data.

### Flushing a Pipe’s Buffer
Data is flushed from the pipe’s ring buffer by calling `k_pipe_buffer_flush()`.

The following code builds on the examples above, and flushes the pipe’s buffer.

```c
void monitor_thread(void)
{
    while (1) {
        /* Pipe buffer contains stale data. Flush it. */
        k_pipe_buffer_flush(&my_pipe);
        ...
    }
}
```

### Flushing a Pipe
All data in the pipe is flushed by calling `k_pipe_flush()`.

The following code builds on the examples above, and flushes all the data in the pipe.

```c
void monitor_thread(void)
{
    while (1) {
        /* Critical error detected. Flush the entire pipe to reset it. */
        k_pipe_flush(&my_pipe);
        ...
    }
}
```

**Suggested uses** Use a pipe to send streams of data between threads.

**Note:** A pipe can be used to transfer long streams of data if desired. However it is often preferable to send pointers to large data items to avoid copying the data. Copying large data items will negatively
impact interrupt latency as a spinlock is held while copying that data.

**Configuration Options**  Related configuration options:

- CONFIG_PIPES

**API Reference**

**group** pipe_apis

**Defines**

```c
K_PIPE_DEFINE(name, pipe_buffer_size, pipe_align)
```

Statically define and initialize a pipe.

The pipe can be accessed outside the module where it is defined using:

```c
extern struct k_pipe <name>;
```

**Parameters**

- **name** – Name of the pipe.
- **pipe_buffer_size** – Size of the pipe's ring buffer (in bytes), or zero if no ring buffer is used.
- **pipe_align** – Alignment of the pipe's ring buffer (power of 2).

**Functions**

```c
void k_pipe_init(struct k_pipe *pipe, unsigned char *buffer, size_t size)
```

Initialize a pipe.

This routine initializes a pipe object, prior to its first use.

**Parameters**

- **pipe** – Address of the pipe.
- **buffer** – Address of the pipe's ring buffer, or NULL if no ring buffer is used.
- **size** – Size of the pipe's ring buffer (in bytes), or zero if no ring buffer is used.

```c
int k_pipe_cleanup(struct k_pipe *pipe)
```

Release a pipe's allocated buffer.

If a pipe object was given a dynamically allocated buffer via `k_pipe_alloc_init()`, this will free it. This function does nothing if the buffer wasn't dynamically allocated.

**Parameters**

- **pipe** – Address of the pipe.

**Return values**

- **0** – on success
- **-EAGAIN** – nothing to cleanup
int k_pipe_alloc_init(struct k_pipe *pipe, size_t size)
  Initialize a pipe and allocate a buffer for it.

  Storage for the buffer region will be allocated from the calling thread’s resource pool. This
  memory will be released if k_pipe_cleanup() is called, or userspace is enabled and the pipe
  object loses all references to it.

  This function should only be called on uninitialized pipe objects.

  Parameters
  • pipe – Address of the pipe.
  • size – Size of the pipe’s ring buffer (in bytes), or zero if no ring buffer is used.

  Return values
  • 0 – on success
  • -ENOMEM – if memory couldn’t be allocated

int k_pipe_put(struct k_pipe *pipe, void *data, size_t bytes_to_write, size_t *bytes_written,
                 size_t min_xfer, k_timeout_t timeout)

  Write data to a pipe.

  This routine writes up to bytes_to_write bytes of data to pipe.

  Parameters
  • pipe – Address of the pipe.
  • data – Address of data to write.
  • bytes_to_write – Size of data (in bytes).
  • bytes_written – Address of area to hold the number of bytes written.
  • min_xfer – Minimum number of bytes to write.
  • timeout – Waiting period to wait for the data to be written, or one of the
    special values K_NO_WAIT and K_FOREVER.

  Return values
  • 0 – At least min_xfer bytes of data were written.
  • -EIO – Returned without waiting; zero data bytes were written.
  • -EAGAIN – Waiting period timed out; between zero and min_xfer minus one
    data bytes were written.

int k_pipe_get(struct k_pipe *pipe, void *data, size_t bytes_to_read, size_t *bytes_read, size_t
                 min_xfer, k_timeout_t timeout)

  Read data from a pipe.

  This routine reads up to bytes_to_read bytes of data from pipe.

  Parameters
  • pipe – Address of the pipe.
  • data – Address to place the data read from pipe.
  • bytes_to_read – Maximum number of data bytes to read.
  • bytes_read – Address of area to hold the number of bytes read.
  • min_xfer – Minimum number of data bytes to read.
  • timeout – Waiting period to wait for the data to be read, or one of the special
    values K_NO_WAIT and K_FOREVER.

  Return values
• 0 – At least \( \min_xfer \) bytes of data were read.
• -EINVAL – invalid parameters supplied
• -EIO – Returned without waiting; zero data bytes were read.
• -EAGAIN – Waiting period timed out; between zero and \( \min_xfer \) minus one data bytes were read.

\texttt{size_t k\_pipe\_read\_avail(\texttt{struct k\_pipe *pipe})}

Query the number of bytes that may be read from \texttt{pipe}.

**Parameters**

• \texttt{pipe} – Address of the pipe.

**Return values**

\( a \) – number \( n \) such that \( 0 \leq n \leq \texttt{k\_pipe\_size} \); the result is zero for unbuffered pipes.

\texttt{size_t k\_pipe\_write\_avail(\texttt{struct k\_pipe *pipe})}

Query the number of bytes that may be written to \texttt{pipe}.

**Parameters**

• \texttt{pipe} – Address of the pipe.

**Return values**

\( a \) – number \( n \) such that \( 0 \leq n \leq \texttt{k\_pipe\_size} \); the result is zero for unbuffered pipes.

\texttt{void k\_pipe\_flush(\texttt{struct k\_pipe *pipe})}

Flush the pipe of write data.

This routine flushes the pipe. flushing the pipe is equivalent to reading both all the data in the pipe's buffer and all the data waiting to go into that pipe into a large temporary buffer and discarding the buffer. Any writers that were previously pended become unpended.

**Parameters**

• \texttt{pipe} – Address of the pipe.

\texttt{void k\_pipe\_buffer\_flush(\texttt{struct k\_pipe *pipe})}

Flush the pipe's internal buffer.

This routine flushes the pipe's internal buffer. This is equivalent to reading up to \( N \) bytes from the pipe (where \( N \) is the size of the pipe's buffer) into a temporary buffer and then discarding that buffer. If there were writers previously pending, then some may unpend as they try to fill up the pipe's emptied buffer.

**Parameters**

• \texttt{pipe} – Address of the pipe.

\texttt{struct k\_pipe}

\#include <kernel.h> Pipe Structure

**Public Members**

\texttt{unsigned char *buffer}

Pipe buffer: may be NULL

3.1. Kernel Services
3.1.3 Memory Management

See Memory Management.

3.1.4 Timing

These pages cover timing related services.

Kernel Timing

Zephyr provides a robust and scalable timing framework to enable reporting and tracking of timed events from hardware timing sources of arbitrary precision.
Time Units  Kernel time is tracked in several units which are used for different purposes.

Real time values, typically specified in milliseconds or microseconds, are the default presentation of time to application code. They have the advantages of being universally portable and pervasively understood, though they may not match the precision of the underlying hardware perfectly.

The kernel presents a “cycle” count via the `k_cycle_get_32()` and `k_cycle_get_64()` APIs. The intent is that this counter represents the fastest cycle counter that the operating system is able to present to the user (for example, a CPU cycle counter) and that the read operation is very fast. The expectation is that very sensitive application code might use this in a polling manner to achieve maximal precision. The frequency of this counter is required to be steady over time, and is available from `sys_clock_hw_cycles_per_sec()` (which on almost all platforms is a runtime constant that evaluates to `CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC`).

For asynchronous timekeeping, the kernel defines a “ticks” concept. A “tick” is the internal count in which the kernel does all its internal uptime and timeout bookkeeping. Interrupts are expected to be delivered on tick boundaries to the extent practical, and no fractional ticks are tracked. The choice of tick rate is configurable via `CONFIG_SYS_CLOCK_TICKS_PER_SEC`. Defaults on most hardware platforms (ones that support setting arbitrary interrupt timeouts) are expected to be in the range of 10 kHz, with software emulation platforms and legacy drivers using a more traditional 100 Hz value.

Conversion  Zephyr provides an extensively enumerated conversion library with rounding control for all time units. Any unit of “ms” (milliseconds), “us” (microseconds), “tick”, or “cyc” can be converted to any other. Control of rounding is provided, and each conversion is available in “floor” (round down to nearest output unit), “ceil” (round up) and “near” (round to nearest). Finally the output precision can be specified as either 32 or 64 bits.

For example: `k_ms_to_ticksceil32()` will convert a millisecond input value to the next higher number of ticks, returning a result truncated to 32 bits of precision; and `k_cyc_to_usfloor64()` will convert a measured cycle count to an elapsed number of microseconds in a full 64 bits of precision. See the reference documentation for the full enumeration of conversion routines.

On most platforms, where the various counter rates are integral multiples of each other and where the output fits within a single word, these conversions expand to a 2-4 operation sequence, requiring full precision only where actually required and requested.

Uptime  The kernel tracks a system uptime count on behalf of the application. This is available at all times via `k_uptime_get()`, which provides an uptime value in milliseconds since system boot. This is expected to be the utility used by most portable application code.

The internal tracking, however, is as a 64 bit integer count of ticks. Apps with precise timing requirements (that are willing to do their own conversions to portable real time units) may access this with `k_uptime_ticks()`.

Timeouts  The Zephyr kernel provides many APIs with a “timeout” parameter. Conceptually, this indicates the time at which an event will occur. For example:

- Kernel blocking operations like `k_sem_take()` or `k_queue_get()` may provide a timeout after which the routine will return with an error code if no data is available.
- Kernel `k_timer` objects must specify delays for their duration and period.
- The kernel `k_work_delayable` API provides a timeout parameter indicating when a work queue item will be added to the system queue.

All these values are specified using a `k_timeout_t` value. This is an opaque struct type that must be initialized using one of a family of kernel timeout macros. The most common, `K_MSEC`, defines a time in milliseconds after the current time (strictly: the time at which the kernel receives the timeout value).
Other options for timeout initialization follow the unit conventions described above: \( K_{\text{NSEC}}() \), \( K_{\text{USEC}} \), \( K_{\text{TICKS}} \) and \( K_{\text{CYC}}() \) specify timeout values that will expire after specified numbers of nanoseconds, microseconds, ticks and cycles, respectively.

Precision of \( k_{\text{timeout}} \) values is configurable, with the default being 32 bits. Large uptime counts in non-tick units will experience complicated rollover semantics, so it is expected that timing-sensitive applications with long uptimes will be configured to use a 64 bit timeout type.

Finally, it is possible to specify timeouts as absolute times since system boot. A timeout initialized with \( K_{\text{TIMEOUT\_ABS\_MS}} \) indicates a timeout that will expire after the system uptime reaches the specified value. There are likewise nanosecond, microsecond, cycles and ticks variants of this API.

### Timing Internals

#### Timeout Queue

All Zephyr \( k_{\text{timeout}} \) events specified using the API above are managed in a single, global queue of events. Each event is stored in a double-linked list, with an attendant delta count in ticks from the previous event. The action to take on an event is specified as a callback function pointer provided by the subsystem requesting the event, along with a \_timeout tracking struct that is expected to be embedded within subsystem-defined data structures (for example: a wait_q struct, or a k_tid_t thread struct).

Note that all variant units passed via a \( k_{\text{timeout}} \) are converted to ticks once on insertion into the list. There no multiple-conversion steps internal to the kernel, so precision is guaranteed at the tick level no matter how many events exist or how long a timeout might be.

Note that the list structure means that the CPU work involved in managing large numbers of timeouts is quadratic in the number of active timeouts. The API design of the timeout queue was intended to permit a more scalable backend data structure, but no such implementation exists currently.

#### Timer Drivers

Kernel timing at the tick level is driven by a timer driver with a comparatively simple API.

- The driver is expected to be able to “announce” new ticks to the kernel via the \texttt{sys\_clock\_announce()} call, which passes an integer number of ticks that have elapsed since the last announce call (or system boot). These calls can occur at any time, but the driver is expected to attempt to ensure (to the extent practical given interrupt latency interactions) that they occur near tick boundaries (i.e. not “halfway through” a tick), and most importantly that they be correct over time and subject to minimal skew vs. other counters and real world time.

- The driver is expected to provide a \texttt{sys\_clock\_set\_timeout()} call to the kernel which indicates how many ticks may elapse before the kernel must receive an announce call to trigger registered timeouts. It is legal to announce new ticks before that moment (though they must be correct) but delay after that will cause events to be missed. Note that the timeout value passed here is in a delta from current time, but that does not absolve the driver of the requirement to provide ticks at a steady rate over time. Naive implementations of this function are subject to bugs where the fractional tick gets “reset” incorrectly and causes clock skew.

- The driver is expected to provide a \texttt{sys\_clock\_elapsed()} call which provides a current indication of how many ticks have elapsed (as compared to a real world clock) since the last call to \texttt{sys\_clock\_announce()}, which the kernel needs to test newly arriving timeouts for expiration.

Note that a natural implementation of this API results in a “tickless” kernel, which receives and processes timer interrupts only for registered events, relying on programmable hardware counters to provide irregular interrupts. But a traditional, “ticked” or “dumb” counter driver can be trivially implemented also:

- The driver can receive interrupts at a regular rate corresponding to the OS tick rate, calling \texttt{sys\_clock\_announce()} with an argument of one each time.

- The driver can ignore calls to \texttt{sys\_clock\_set\_timeout()}, as every tick will be announced regardless of timeout status.
• The driver can return zero for every call to `sys_clock_elapsed()` as no more than one tick can be detected as having elapsed (because otherwise an interrupt would have been received).

SMP Details In general, the timer API described above does not change when run in a multiprocessor context. The kernel will internally synchronize all access appropriately, and ensure that all critical sections are small and minimal. But some notes are important to detail:

• Zephyr is agnostic about which CPU services timer interrupts. It is not illegal (though probably undesirable in some circumstances) to have every timer interrupt handled on a single processor. Existing SMP architectures implement symmetric timer drivers.

• The `sys_clock_announce()` call is expected to be globally synchronized at the driver level. The kernel does not do any per-CPU tracking, and expects that if two timer interrupts fire near simultaneously, that only one will provide the current tick count to the timing subsystem. The other may legally provide a tick count of zero if no ticks have elapsed. It should not “skip” the announce call because of timeslicing requirements (see below).

• Some SMP hardware uses a single, global timer device, others use a per-CPU counter. The complexity here (for example: ensuring counter synchronization between CPUs) is expected to be managed by the driver, not the kernel.

• The next timeout value passed back to the driver via `sys_clock_set_timeout()` is done identically for every CPU. So by default, every CPU will see simultaneous timer interrupts for every event, even though by definition only one of them should see a non-zero ticks argument to `sys_clock_announce()`. This is probably a correct default for timing sensitive applications (because it minimizes the chance that an errant ISR or interrupt lock will delay a timeout), but may be a performance problem in some cases. The current design expects that any such optimization is the responsibility of the timer driver.

Time Slicing An auxiliary job of the timing subsystem is to provide tick counters to the scheduler that allow implementation of time slicing of threads. A thread time-slice cannot be a timeout value, as it does not reflect a global expiration but instead a per-CPU value that needs to be tracked independently on each CPU in an SMP context.

Because there may be no other hardware available to drive timeslicing, Zephyr multiplexes the existing timer driver. This means that the value passed to `sys_clock_set_timeout()` may be clamped to a smaller value than the current next timeout when a time sliced thread is currently scheduled.

Subsystems that keep millisecond APIs In general, code like this will port just like applications code will. Millisecond values from the user may be treated any way the subsystem likes, and then converted into kernel timeouts using `K_MSEC()` at the point where they are presented to the kernel.

Obviously this comes at the cost of not being able to use new features, like the higher precision timeout constructors or absolute timeouts. But for many subsystems with simple needs, this may be acceptable.

One complexity is `K_FOREVER`. Subsystems that might have been able to accept this value to their millisecond API in the past no longer can, because it is no longer an integral type. Such code will need to use a different, integer-valued token to represent “forever”. `K_NO_WAIT` has the same typesafety concern too, of course, but as it is (and has always been) simply a numerical zero, it has a natural porting path.

Subsystems using `k_timeout_t` Ideally, code that takes a “timeout” parameter specifying a time to wait should be using the kernel native abstraction where possible. But `k_timeout_t` is opaque, and needs to be converted before it can be inspected by an application.

Some conversions are simple. Code that needs to test for `K_FOREVER` can simply use the `K_TIMEOUT_EQ()` macro to test the opaque struct for equality and take special action.

The more complicated case is when the subsystem needs to take a timeout and loop, waiting for it to finish while doing some processing that may require multiple blocking operations on underlying kernel code. For example, consider this design:
```c
void my_wait_for_event(struct my_subsys *obj, int32_t timeout_in_ms)
{
    while (true) {
        uint32_t start = k_uptime_get_32();

        if (is_event_complete(obj)) {
            return;
        }

        /* Wait for notification of state change */
        k_sem_take(obj->sem, timeout_in_ms);

        /* Subtract elapsed time */
        timeout_in_ms -= (k_uptime_get_32() - start);
    }
}
```

This code requires that the timeout value be inspected, which is no longer possible. For situations like this, the new API provides an internal `sys_clock_timeout_end_calc()` routine that converts an arbitrary timeout to the uptime value in ticks at which it will expire. So such a loop might look like:

```c
void my_wait_for_event(struct my_subsys *obj, k_timeout_t timeout_in_ms)
{
    /* Compute the end time from the timeout */
    uint64_t end = sys_clock_timeout_end_calc(timeout_in_ms);

    while (end > k_uptime_ticks()) {
        if (is_event_complete(obj)) {
            return;
        }

        /* Wait for notification of state change */
        k_sem_take(obj->sem, timeout_in_ms);
    }
}
```

Note that `sys_clock_timeout_end_calc()` returns values in units of ticks, to prevent conversion aliasing, is always presented at 64 bit uptime precision to prevent rollover bugs, handles special `K_FOREVER` naturally (as UINT64_MAX), and works identically for absolute timeouts as well as conventional ones.

But some care is still required for subsystems that use it. Note that delta timeouts need to be interpreted relative to a “current time”, and obviously that time is the time of the call to `sys_clock_timeout_end_calc()`. But the user expects that the time is the time they passed the timeout to you. Care must be taken to call this function just once, as synchronously as possible to the timeout creation in user code. It should not be used on a “stored” timeout value, and should never be called iteratively in a loop.

**API Reference**

**group clock_apis**

Clock APIs.

**Defines**

`K_NO_WAIT`

Generate null timeout delay.
This macro generates a timeout delay that instructs a kernel API not to wait if the requested operation cannot be performed immediately.

**Returns**
Timeout delay value.

\( K\_\text{NSEC}(t) \)
Generate timeout delay from nanoseconds.

This macro generates a timeout delay that instructs a kernel API to wait up to \( t \) nanoseconds to perform the requested operation. Note that timer precision is limited to the tick rate, not the requested value.

**Parameters**
- \( t \) – Duration in nanoseconds.

**Returns**
Timeout delay value.

\( K\_\text{USEC}(t) \)
Generate timeout delay from microseconds.

This macro generates a timeout delay that instructs a kernel API to wait up to \( t \) microseconds to perform the requested operation. Note that timer precision is limited to the tick rate, not the requested value.

**Parameters**
- \( t \) – Duration in microseconds.

**Returns**
Timeout delay value.

\( K\_\text{CYC}(t) \)
Generate timeout delay from cycles.

This macro generates a timeout delay that instructs a kernel API to wait up to \( t \) cycles to perform the requested operation.

**Parameters**
- \( t \) – Duration in cycles.

**Returns**
Timeout delay value.

\( K\_\text{TICKS}(t) \)
Generate timeout delay from system ticks.

This macro generates a timeout delay that instructs a kernel API to wait up to \( t \) ticks to perform the requested operation.

**Parameters**
- \( t \) – Duration in system ticks.

**Returns**
Timeout delay value.

\( K\_\text{MSEC}(ms) \)
Generate timeout delay from milliseconds.

This macro generates a timeout delay that instructs a kernel API to wait up to \( ms \) milliseconds to perform the requested operation.

**Parameters**
- \( ms \) – Duration in milliseconds.
Returns
Timeout delay value.

\texttt{K\_SECONDS(s)}

Generate timeout delay from seconds.

This macro generates a timeout delay that instructs a kernel API to wait up to \( s \) seconds to perform the requested operation.

Parameters
- \( s \) – Duration in seconds.

Returns
Timeout delay value.

\texttt{K\_MINUTES(m)}

Generate timeout delay from minutes.

This macro generates a timeout delay that instructs a kernel API to wait up to \( m \) minutes to perform the requested operation.

Parameters
- \( m \) – Duration in minutes.

Returns
Timeout delay value.

\texttt{K\_HOURS(h)}

Generate timeout delay from hours.

This macro generates a timeout delay that instructs a kernel API to wait up to \( h \) hours to perform the requested operation.

Parameters
- \( h \) – Duration in hours.

Returns
Timeout delay value.

\texttt{K\_FOREVER}

Generate infinite timeout delay.

This macro generates a timeout delay that instructs a kernel API to wait as long as necessary to perform the requested operation.

Returns
Timeout delay value.

\texttt{K\_TICKS\_FOREVER}

\texttt{K\_TIMEOUT\_EQ(a, b)}

Compare timeouts for equality.

The \texttt{k\_timeout\_t} object is an opaque struct that should not be inspected by application code. This macro exists so that users can test timeout objects for equality with known constants (e.g. \texttt{K\_NO\_WAIT} and \texttt{K\_FOREVER}) when implementing their own APIs in terms of Zephyr timeout constants.

Returns
True if the timeout objects are identical
typedef uint32_t k_ticks_t

Tick precision used in timeout APIs.

This type defines the word size of the timeout values used in k_timeout_t objects, and thus defines an upper bound on maximum timeout length (or equivalently minimum tick duration). Note that this does not affect the size of the system uptime counter, which is always a 64 bit count of ticks.

Functions

void sys_clock_set_timeout(int32_t ticks, bool idle)

Set system clock timeout.

Informs the system clock driver that the next needed call to sys_clock_announce() will not be until the specified number of ticks from the current time have elapsed. Note that spurious calls to sys_clock_announce() are allowed (i.e. it's legal to announce every tick and implement this function as a noop), the requirement is that one tick announcement should occur within one tick before the specified expiration (that is, passing ticks==1 means "announce the next tick", this convention was chosen to match legacy usage). Similarly a ticks value of zero (or even negative) is legal and treated identically: it simply indicates the kernel would like the next tick announcement as soon as possible.

Note that ticks can also be passed the special value K_TICKS_FOREVER, indicating that no future timer interrupts are expected or required and that the system is permitted to enter an indefinite sleep even if this could cause rollover of the internal counter (i.e. the system uptime counter is allowed to be wrong).

Note also that it is conventional for the kernel to pass INT_MAX for ticks if it wants to preserve the uptime tick count but doesn't have a specific event to await. The intent here is that the driver will schedule any needed timeout as far into the future as possible. For the specific case of INT_MAX, the next call to sys_clock_announce() may occur at any point in the future, not just at INT_MAX ticks. But the correspondence between the announced ticks and real-world time must be correct.

A final note about SMP: note that the call to sys_clock_set_timeout() is made on any CPU, and reflects the next timeout desired globally. The resulting calls(s) to sys_clock_announce() must be properly serialized by the driver such that a given tick is announced exactly once across the system. The kernel does not (cannot, really) attempt to serialize things by “assigning” timeouts to specific CPUs.

Parameters

- ticks – Timeout in tick units
- idle – Hint to the driver that the system is about to enter the idle state immediately after setting the timeout

void sys_clock_idle_exit(void)

Timer idle exit notification.

This notifies the timer driver that the system is exiting the idle and allows it to do whatever bookkeeping is needed to restore timer operation and compute elapsed ticks.

Note: Legacy timer drivers also use this opportunity to call back into sys_clock_announce() to notify the kernel of expired ticks. This is allowed for compatibility, but not recommended. The kernel will figure that out on its own.
void sys_clock_announce(int32_t ticks)
    Announce time progress to the kernel.
    Informs the kernel that the specified number of ticks have elapsed since the last call to
    sys_clock_announce() (or system startup for the first call). The timer driver is expected to
delivery these announcements as close as practical (subject to hardware and latency limitations)
to tick boundaries.

Parameters

- ticks – Elapsed time, in ticks

uint32_t sys_clock_elapsed(void)
    Ticks elapsed since last sys_clock_announce() call.
    Queries the clock driver for the current time elapsed since the last call to sys_clock_announce() was made. The kernel will call this with appropriate locking, the driver needs only provide an
instantaneous answer.

void sys_clock_disable(void)
    Disable system timer.
    This function is a no-op if the system timer does not have the capability of being disabled.

int64_t k_uptime_ticks(void)
    Get system uptime, in system ticks.
    This routine returns the elapsed time since the system booted, in ticks (c.f. CONFIG_SYS_CLOCK_TICKS_PER_SEC), which is the fundamental unit of resolution of kernel
timekeeping.

Returns

- Current uptime in ticks.

static inline int64_t k_uptime_get(void)
    Get system uptime.
    This routine returns the elapsed time since the system booted, in milliseconds.

Note: While this function returns time in milliseconds, it does not mean it has millisecond resolution. The actual resolution depends on CONFIG_SYS_CLOCK_TICKS_PER_SEC config
option.

Calling

- Current uptime in milliseconds.

static inline uint32_t k_uptime_get_32(void)
    Get system uptime (32-bit version).
    This routine returns the lower 32 bits of the system uptime in milliseconds.

Because correct conversion requires full precision of the system clock there is no benefit to
using this over k_uptime_get() unless you know the application will never run long enough for the system clock to approach 2^32 ticks. Calls to this function may involve interrupt
blocking and 64-bit math.

Note: While this function returns time in milliseconds, it does not mean it has millisecond resolution. The actual resolution depends on CONFIG_SYS_CLOCK_TICKS_PER_SEC config
option.
Returns
The low 32 bits of the current uptime, in milliseconds.

static inline int64_t k_uptime_delta(int64_t *reftime)
Get elapsed time.
This routine computes the elapsed time between the current system uptime and an earlier
reference time, in milliseconds.

Parameters
• reftime – Pointer to a reference time, which is updated to the current uptime
upon return.

Returns
Elapsed time.

static inline uint32_t k_cycle_get_32(void)
Read the hardware clock.
This routine returns the current time, as measured by the system's hardware clock.

Returns
Current hardware clock up-counter (in cycles).

static inline uint64_t k_cycle_get_64(void)
Read the 64-bit hardware clock.
This routine returns the current time in 64-bits, as measured by the system's hardware clock,
if available.

See also:
CONFIG_TIMER_HAS_64BIT_CYCLE_COUNTER

Returns
Current hardware clock up-counter (in cycles).

struct k_timeout_t
#include <sys_clock.h> Kernel timeout type.
Timeout arguments presented to kernel APIs are stored in this opaque type, which is capable of representing times in various formats and units. It should be constructed from application data using one of the macros defined for this purpose (e.g. K_MSEC(), K_TIMEOUT_ABS_TICKS(), etc...), or be one of the two constants K_NO_WAIT or K_FOREVER. Applications should not inspect the internal data once constructed. Timeout values may be compared for equality with the K_TIMEOUT_EQ() macro.

Timers
A timer is a kernel object that measures the passage of time using the kernel's system clock. When
a timer's specified time limit is reached it can perform an application-defined action, or it can simply
record the expiration and wait for the application to read its status.

• Concepts
• Implementation
  – Defining a Timer
Concepts  Any number of timers can be defined (limited only by available RAM). Each timer is referenced by its memory address.

A timer has the following key properties:

- A **duration** specifying the time interval before the timer expires for the first time. This is a \texttt{k_timeout_t} value that may be initialized via different units.

- A **period** specifying the time interval between all timer expirations after the first one, also a \texttt{k_timeout_t}. It must be non-negative. A period of \texttt{K_NO_WAIT} (i.e. zero) or \texttt{K_FOREVER} means that the timer is a one shot timer that stops after a single expiration. (For example then, if a timer is started with a duration of 200 and a period of 75, it will first expire after 200ms and then every 75ms after that.)

- An **expiry function** that is executed each time the timer expires. The function is executed by the system clock interrupt handler. If no expiry function is required a \texttt{NULL} function can be specified.

- A **stop function** that is executed if the timer is stopped prematurely while running. The function is executed by the thread that stops the timer. If no stop function is required a \texttt{NULL} function can be specified.

- A **status** value that indicates how many times the timer has expired since the status value was last read.

A timer must be initialized before it can be used. This specifies its expiry function and stop function values, sets the timer's status to zero, and puts the timer into the **stopped** state.

A timer is **started** by specifying a duration and a period. The timer's status is reset to zero, then the timer enters the **running** state and begins counting down towards expiry.

Note that the timer's duration and period parameters specify **minimum** delays that will elapse. Because of internal system timer precision (and potentially runtime interactions like interrupt delay) it is possible that more time may have passed as measured by reads from the relevant system time APIs. But at least this much time is guaranteed to have elapsed.

When a running timer expires its status is incremented and the timer executes its expiry function, if one exists; If a thread is waiting on the timer, it is unblocked. If the timer's period is zero the timer enters the stopped state; otherwise the timer restarts with a new duration equal to its period.

A running timer can be stopped in mid-countdown, if desired. The timer's status is left unchanged, then the timer enters the stopped state and executes its stop function, if one exists. If a thread is waiting on the timer, it is unblocked. Attempting to stop a non-running timer is permitted, but has no effect on the timer since it is already stopped.

A running timer can be restarted in mid-countdown, if desired. The timer's status is reset to zero, then the timer begins counting down using the new duration and period values specified by the caller. If a thread is waiting on the timer, it continues waiting.

A timer's status can be read directly at any time to determine how many times the timer has expired since its status was last read. Reading a timer's status resets its value to zero. The amount of time remaining before the timer expires can also be read; a value of zero indicates that the timer is stopped.

A thread may read a timer's status indirectly by **synchronizing** with the timer. This blocks the thread until the timer's status is non-zero (indicating that it has expired at least once) or the timer is stopped; if
the timer status is already non-zero or the timer is already stopped the thread continues without waiting. The synchronization operation returns the timer's status and resets it to zero.

**Note:** Only a single user should examine the status of any given timer, since reading the status (directly or indirectly) changes its value. Similarly, only a single thread at a time should synchronize with a given timer. ISRs are not permitted to synchronize with timers, since ISRs are not allowed to block.

### Implementation

**Defining a Timer** A timer is defined using a variable of type `k_timer`. It must then be initialized by calling `k_timer_init()`.

The following code defines and initializes a timer.

```c
struct k_timer my_timer;
extern void my_expiry_function(struct k_timer *timer_id);
k_timer_init(&my_timer, my_expiry_function, NULL);
```

Alternatively, a timer can be defined and initialized at compile time by calling `K_TIMER_DEFINE`.

The following code has the same effect as the code segment above.

```c
K_TIMER_DEFINE(my_timer, my_expiry_function, NULL);
```

**Using a Timer Expiry Function** The following code uses a timer to perform a non-trivial action on a periodic basis. Since the required work cannot be done at interrupt level, the timer's expiry function submits a work item to the system workqueue, whose thread performs the work.

```c
void my_work_handler(struct k_work *work)
{
    /* do the processing that needs to be done periodically */
    ...
}
K_WORK_DEFINE(my_work, my_work_handler);

void my_timer_handler(struct k_timer *dummy)
{
    k_work_submit(&my_work);
}
K_TIMER_DEFINE(my_timer, my_timer_handler, NULL);
...
/* start periodic timer that expires once every second */
k_timer_start(&my_timer, K_SECONDS(1), K_SECONDS(1));
```

**Reading Timer Status** The following code reads a timer's status directly to determine if the timer has expired on not.
Using Timer Status Synchronization

The following code performs timer status synchronization to allow a thread to do useful work while ensuring that a pair of protocol operations are separated by the specified time interval.

```c
K_TIMER_DEFINE(my_status_timer, NULL, NULL);

... /* start one shot timer that expires after 200 ms */
k_timer_start(&my_status_timer, K_MSEC(200), K_NO_WAIT);

/* do work */
...

/* check timer status */
if (k_timer_status_get(&my_status_timer) > 0) {
    /* timer has expired */
} else if (k_timer_remaining_get(&my_status_timer) == 0) {
    /* timer was stopped (by someone else) before expiring */
} else {
    /* timer is still running */
}
```

**Note:** If the thread had no other work to do it could simply sleep between the two protocol operations, without using a timer.

**Suggested Uses**

Use a timer to initiate an asynchronous operation after a specified amount of time.

Use a timer to determine whether or not a specified amount of time has elapsed. In particular, timers should be used when higher precision and/or unit control is required than that afforded by the simpler `k_sleep()` and `k_usleep()` calls.

Use a timer to perform other work while carrying out operations involving time limits.

**Note:** If a thread needs to measure the time required to perform an operation it can read the system timer.
**clock or the hardware clock** directly, rather than using a timer.

**Configuration Options**  Related configuration options:

- None

**API Reference**  
*group timerApis*

**Defines**

```c
K_TIMER_DEFINE(name, expiry_fn, stop_fn)
```

Safely define and initialize a timer.

The timer can be accessed outside the module where it is defined using:

```c
extern struct k_timer <name>;
```

**Parameters**

- **name** – Name of the timer variable.
- **expiry_fn** – Function to invoke each time the timer expires.
- **stop_fn** – Function to invoke if the timer is stopped while running.

**Typedefs**

```c
typedef void (*k_timer_expiry_t)(struct k_timer *timer)
```

Timer expiry function type.

A timer's expiry function is executed by the system clock interrupt handler each time the timer expires. The expiry function is optional, and is only invoked if the timer has been initialized with one.

**Param timer**

Address of timer.

```c
typedef void (*k_timer_stop_t)(struct k_timer *timer)
```

Timer stop function type.

A timer's stop function is executed if the timer is stopped prematurely. The function runs in the context of call that stops the timer. As k_timer_stop() can be invoked from an ISR, the stop function must be callable from interrupt context (isr-ok).

The stop function is optional, and is only invoked if the timer has been initialized with one.

**Param timer**

Address of timer.
Functions

void k_timer_init(struct k_timer *timer, k_timer_expiry_t expiry_fn, k_timer_stop_t stop_fn)
Initialize a timer.
This routine initializes a timer, prior to its first use.

Parameters
• timer – Address of timer.
• expiry_fn – Function to invoke each time the timer expires.
• stop_fn – Function to invoke if the timer is stopped while running.

void k_timer_start(struct k_timer *timer, k_timeout_t duration, k_timeout_t period)
Start a timer.
This routine starts a timer, and resets its status to zero. The timer begins counting down using
the specified duration and period values.
Attempting to start a timer that is already running is permitted. The timer's status is reset to
zero and the timer begins counting down using the new duration and period values.

Parameters
• timer – Address of timer.
• duration – Initial timer duration.
• period – Timer period.

void k_timer_stop(struct k_timer *timer)
Stop a timer.
This routine stops a running timer prematurely. The timer's stop function, if one exists, is
invoked by the caller.
Attempting to stop a timer that is not running is permitted, but has no effect on the timer.

Function properties (list may not be complete)

isr-ok

Note: The stop handler has to be callable from ISRs if k_timer_stop is to be called from ISRs.

Parameters
• timer – Address of timer.

uint32_t k_timer_status_get(struct k_timer *timer)
Read timer status.
This routine reads the timer's status, which indicates the number of times it has expired since
its status was last read.
Calling this routine resets the timer's status to zero.

Parameters
• timer – Address of timer.

Returns
Timer status.


uint32_t k_timer_status_sync(struct k_timer *timer)

Synchronize thread to timer expiration.

This routine blocks the calling thread until the timer's status is non-zero (indicating that it has expired at least once since it was last examined) or the timer is stopped. If the timer status is already non-zero, or the timer is already stopped, the caller continues without waiting.

Calling this routine resets the timer's status to zero.

This routine must not be used by interrupt handlers, since they are not allowed to block.

Parameters
- \textit{timer} – Address of timer.

Returns
- Timer status.

\textit{k_ticks_t} k_timer_expires_ticks(const struct k_timer *timer)

Get next expiration time of a timer, in system ticks.

This routine returns the future system uptime reached at the next time of expiration of the timer, in units of system ticks. If the timer is not running, current system time is returned.

Parameters
- \textit{timer} – The timer object

Returns
- Uptime of expiration, in ticks

\textit{k_ticks_t} k_timer_remaining_ticks(const struct k_timer *timer)

Get time remaining before a timer next expires, in system ticks.

This routine computes the time remaining before a running timer next expires, in units of system ticks. If the timer is not running, it returns zero.

\textit{static inline uint32_t} k_timer_remaining_get(struct k_timer *timer)

Get time remaining before a timer next expires.

This routine computes the (approximate) time remaining before a running timer next expires. If the timer is not running, it returns zero.

Parameters
- \textit{timer} – Address of timer.

Returns
- Remaining time (in milliseconds).

void k_timer_user_data_set(struct k_timer *timer, void *user_data)

Associate user-specific data with a timer.

This routine records the \textit{user_data} with the \textit{timer}, to be retrieved later.

It can be used e.g. in a timer handler shared across multiple subsystems to retrieve data specific to the subsystem this timer is associated with.

Parameters
- \textit{timer} – Address of timer.
- \textit{user_data} – User data to associate with the timer.

void *k_timer_user_data_get(const struct k_timer *timer)

Retrieve the user-specific data from a timer.

Parameters
- \textit{timer} – Address of timer.
Returns
The user data.

3.1.5 Other

These pages cover other kernel services.

Atomic Services

An atomic variable is one that can be read and modified by threads and ISRs in an uninterruptible manner. It 32-bit on 32-bit machines and 64-bit on 64-bit machines.

- Concepts
- Implementation
  - Defining an Atomic Variable
  - Manipulating an Atomic Variable
  - Manipulating an Array of Atomic Variables
  - Memory Ordering
- Suggested Uses
- Configuration Options
- API Reference

Concepts  Any number of atomic variables can be defined (limited only by available RAM).

Using the kernel’s atomic APIs to manipulate an atomic variable guarantees that the desired operation occurs correctly, even if higher priority contexts also manipulate the same variable.

The kernel also supports the atomic manipulation of a single bit in an array of atomic variables.

Implementation

Defining an Atomic Variable  An atomic variable is defined using a variable of type atomic_t.

By default an atomic variable is initialized to zero. However, it can be given a different value using ATOMIC_INIT:

```
atomic_t flags = ATOMIC_INIT(0xFF);
```

Manipulating an Atomic Variable  An atomic variable is manipulated using the APIs listed at the end of this section.

The following code shows how an atomic variable can be used to keep track of the number of times a function has been invoked. Since the count is incremented atomically, there is no risk that it will become corrupted in mid-increment if a thread calling the function is interrupted if by a higher priority context that also calls the routine.
atomic_t call_count;

int call_counting_routine(void)
{
    /* increment invocation counter */
    atomic_inc(&call_count);

    /* do rest of routine's processing */
    ...
}

Manipulating an Array of Atomic Variables  
An array of 32-bit atomic variables can be defined in the conventional manner. However, you can also define an N-bit array of atomic variables using ATOMIC_DEFINE.

A single bit in an array of atomic variables can be manipulated using the APIs listed at the end of this section that end with _bit().

The following code shows how a set of 200 flag bits can be implemented using an array of atomic variables.

#define NUM_FLAG_BITS 200

ATOMIC_DEFINE(flag_bits, NUM_FLAG_BITS);

/* set specified flag bit & return its previous value */
int set_flag_bit(int bit_position)
{
    return (int)atomic_set_bit(flag_bits, bit_position);
}

Memory Ordering  
For consistency and correctness, all Zephyr atomic APIs are expected to include a full memory barrier (in the sense of e.g. “serializing” instructions on x86, “DMB” on ARM, or a “sequentially consistent” operation as defined by the C++ memory model) where needed by hardware to guarantee a reliable picture across contexts. Any architecture-specific implementations are responsible for ensuring this behavior.

Suggested Uses  
Use an atomic variable to implement critical section processing that only requires the manipulation of a single 32-bit value.

Use multiple atomic variables to implement critical section processing on a set of flag bits in a bit array longer than 32 bits.

Note: Using atomic variables is typically far more efficient than using other techniques to implement critical sections such as using a mutex or locking interrupts.

Configuration Options  
Related configuration options:

- CONFIG_ATOMIC_OPERATIONS_BUILTIN
- CONFIG_ATOMIC_OPERATIONS_ARCH
- CONFIG_ATOMIC_OPERATIONS_C
Important: All atomic services APIs can be used by both threads and ISRs.


group atomic_apis

Defines

ATOMIC_INIT(i)

Initialize an atomic variable.

This macro can be used to initialize an atomic variable. For example,

```c
atomic_t my_var = ATOMIC_INIT(75);
```

Parameters

- `i` – Value to assign to atomic variable.

ATOMIC_PTR_INIT(p)

Initialize an atomic pointer variable.

This macro can be used to initialize an atomic pointer variable. For example,

```c
atomic_ptr_t my_ptr = ATOMIC_PTR_INIT(&data);
```

Parameters

- `p` – Pointer value to assign to atomic pointer variable.

ATOMIC_BITMAP_SIZE(num_bits)

This macro computes the number of atomic variables necessary to represent a bitmap with `num_bits`.

Parameters

- `num_bits` – Number of bits.

ATOMIC_DEFINE(name, num_bits)

Define an array of atomic variables.

This macro defines an array of atomic variables containing at least `num_bits` bits.

Note: If used from file scope, the bits of the array are initialized to zero; if used from within a function, the bits are left uninitialized.

Parameters

- `name` – Name of array of atomic variables.
- `num_bits` – Number of bits needed.

Functions
static inline bool atomic_test_bit(const atomic_t *target, int bit)
  Atomically test a bit.

  This routine tests whether bit number bit of target is set or not. The target may be a single
  atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where
applicable).

**Parameters**
- target – Address of atomic variable or array.
- bit – Bit number (starting from 0).

**Returns**
  true if the bit was set, false if it wasn't.

static inline bool atomic_test_and_clear_bit(atomic_t *target, int bit)
  Atomically test and clear a bit.

  Atomically clear bit number bit of target and return its old value. The target may be a single
  atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where
applicable).

**Parameters**
- target – Address of atomic variable or array.
- bit – Bit number (starting from 0).

**Returns**
  true if the bit was set, false if it wasn't.

static inline bool atomic_test_and_set_bit(atomic_t *target, int bit)
  Atomically set a bit.

  Atomically set bit number bit of target and return its old value. The target may be a single
  atomic variable or an array of them.

**Note:** As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where
applicable).

**Parameters**
- target – Address of atomic variable or array.
- bit – Bit number (starting from 0).

**Returns**
  true if the bit was set, false if it wasn't.

static inline void atomic_clear_bit(atomic_t *target, int bit)
  Atomically clear a bit.

  Atomically clear bit number bit of target. The target may be a single atomic variable or an
  array of them.
Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- *target* – Address of atomic variable or array.
- *bit* – Bit number (starting from 0).

```c
static inline void atomic_set_bit(atomic_t *target, int bit)
```
Atomically set a bit.

Atomically set bit number *bit* of *target*. The target may be a single atomic variable or an array of them.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- *target* – Address of atomic variable or array.
- *bit* – Bit number (starting from 0).
- *val* – true for 1, false for 0.

```c
static inline bool atomic_cas(atomic_t *target, atomic_val_t old_value, atomic_val_t new_value)
```
Atomic compare-and-set.

This routine performs an atomic compare-and-set on *target*. If the current value of *target* equals *old_value*, *target* is set to *new_value*. If the current value of *target* does not equal *old_value*, *target* is left unchanged.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

**Parameters**
- *target* – Address of atomic variable.
- *old_value* – Original value to compare against.
• new_value – New value to store.

Returns
true if new_value is written, false otherwise.

static inline bool atomic_ptr_cas(atomic_ptr_t *target, atomic_ptr_val_t old_value, atomic_ptr_val_t new_value)

Atomic compare-and-set with pointer values.
This routine performs an atomic compare-and-set on target. If the current value of target equals old_value, target is set to new_value. If the current value of target does not equal old_value, target is left unchanged.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• old_value – Original value to compare against.
• new_value – New value to store.

Returns
true if new_value is written, false otherwise.

static inline atomic_val_t atomic_add(atomic_t *target, atomic_val_t value)

Atomic addition.
This routine performs an atomic addition on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to add.

Returns
Previous value of target.

static inline atomic_val_t atomic_sub(atomic_t *target, atomic_val_t value)

Atomic subtraction.
This routine performs an atomic subtraction on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to subtract.

Returns
Previous value of target.
static inline atomic_val_t atomic_inc(atomic_t *target)
Atomic increment.
This routine performs an atomic increment by 1 on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.

Returns
Previous value of target.

static inline atomic_val_t atomic_dec(atomic_t *target)
Atomic decrement.
This routine performs an atomic decrement by 1 on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.

Returns
Previous value of target.

static inline atomic_val_t atomic_get(const atomic_t *target)
Atomic get.
This routine performs an atomic read on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.

Returns
Value of target.

static inline atomic_ptr_val_t atomic_ptr_get(const atomic_ptr_t *target)
Atomic get a pointer value.
This routine performs an atomic read on target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of pointer variable.
Returns
Value of target.

static inline atomic_val_t atomic_set(atomic_t *target, atomic_val_t value)
Atomic get-and-set.
This routine atomically sets target to value and returns the previous value of target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to write to target.

Returns
Previous value of target.

static inline atomic_ptr_val_t atomic_ptr_set(atomic_ptr_t *target, atomic_ptr_val_t value)
Atomic get-and-set for pointer values.
This routine atomically sets target to value and returns the previous value of target.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to write to target.

Returns
Previous value of target.

static inline atomic_val_t atomic_clear(atomic_t *target)
Atomic clear.
This routine atomically sets target to zero and returns its previous value. (Hence, it is equivalent to atomic_set(target, 0).)

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.

Returns
Previous value of target.

static inline atomic_ptr_val_t atomic_ptr_clear(atomic_ptr_t *target)
Atomic clear of a pointer value.
This routine atomically sets target to zero and returns its previous value. (Hence, it is equivalent to atomic_set(target, 0).)
Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.

Returns
Previous value of target.

static inline atomic_val_t atomic_or(atomic_t *target, atomic_val_t value)
Atomic bitwise inclusive OR.
This routine atomically sets target to the bitwise inclusive OR of target and value.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to OR.

Returns
Previous value of target.

static inline atomic_val_t atomic_xor(atomic_t *target, atomic_val_t value)
Atomic bitwise exclusive OR (XOR).
This routine atomically sets target to the bitwise exclusive OR (XOR) of target and value.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters
• target – Address of atomic variable.
• value – Value to XOR.

Returns
Previous value of target.

static inline atomic_val_t atomic_and(atomic_t *target, atomic_val_t value)
Atomic bitwise AND.
This routine atomically sets target to the bitwise AND of target and value.

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).
static inline atomic_val_t atomic_nand(atomic_t *target, atomic_val_t value)
    Atomic bitwise NAND.
    This routine atomically sets target to the bitwise NAND of target and value. (This operation is equivalent to target = ~(target & value).)

Note: As for all atomic APIs, includes a full/sequentially-consistent memory barrier (where applicable).

Parameters

- target – Address of atomic variable.
- value – Value to NAND.

Returns

Previous value of target.

Floating Point Services

The kernel allows threads to use floating point registers on board configurations that support these registers.

Note: Floating point services are currently available only for boards based on ARM Cortex-M SoCs supporting the Floating Point Extension, the Intel x86 architecture, the SPARC architecture and ARCv2 SoCs supporting the Floating Point Extension. The services provided are architecture specific.

The kernel does not support the use of floating point registers by ISRs.

Concepts

- No FP registers mode
- Unshared FP registers mode
- Shared FP registers mode

Implementation

- Performing Floating Point Arithmetic

Suggested Uses

Configuration Options

API Reference

Concepts The kernel can be configured to provide only the floating point services required by an application. Three modes of operation are supported, which are described below. In addition, the kernel's support for the SSE registers can be included or omitted, as desired.
No FP registers mode  This mode is used when the application has no threads that use floating point registers. It is the kernel’s default floating point services mode.

If a thread uses any floating point register, the kernel generates a fatal error condition and aborts the thread.

Unshared FP registers mode  This mode is used when the application has only a single thread that uses floating point registers.

On x86 platforms, the kernel initializes the floating point registers so they can be used by any thread (initialization in skipped on ARM Cortex-M platforms and ARCv2 platforms). The floating point registers are left unchanged whenever a context switch occurs.

Note: The behavior is undefined, if two or more threads attempt to use the floating point registers, as the kernel does not attempt to detect (or prevent) multiple threads from using these registers.

Shared FP registers mode  This mode is used when the application has two or more threads that use floating point registers. Depending upon the underlying CPU architecture, the kernel supports one or more of the following thread sub-classes:

- non-user: A thread that cannot use any floating point registers
- FPU user: A thread that can use the standard floating point registers
- SSE user: A thread that can use both the standard floating point registers and SSE registers

The kernel initializes and enables access to the floating point registers, so they can be used by any thread, then saves and restores these registers during context switches to ensure the computations performed by each FPU user or SSE user are not impacted by the computations performed by the other users.

ARM Cortex-M architecture (with the Floating Point Extension)

Note: The Shared FP registers mode is the default Floating Point Services mode in ARM Cortex-M.

On the ARM Cortex-M architecture with the Floating Point Extension, the kernel treats all threads as FPU users when shared FP registers mode is enabled. This means that any thread is allowed to access the floating point registers. The ARM kernel automatically detects that a given thread is using the floating point registers the first time the thread accesses them.

Pretag a thread that intends to use the FP registers by using one of the techniques listed below.

- A statically-created ARM thread can be pretagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.
- A dynamically-created ARM thread can be pretagged by passing the `K_FP_REGS` option to `k_thread_create()`.

Pretagging a thread with the `K_FP_REGS` option instructs the MPU-based stack protection mechanism to properly configure the size of the thread’s guard region to always guarantee stack overflow detection, and enable lazy stacking for the given thread upon thread creation.

During thread context switching the ARM kernel saves the callee-saved floating point registers, if the switched-out thread has been using them. Additionally, the caller-saved floating point registers are saved on the thread’s stack. If the switched-in thread has been using the floating point registers, the kernel restores the callee-saved FP registers of the switched-in thread and the caller-saved FP context is restored from the thread’s stack. Thus, the kernel does not save or restore the FP context of threads that are not using the FP registers.

Each thread that intends to use the floating point registers must provide an extra 72 bytes of stack space where the callee-saved FP context can be saved.
Lazy Stacking is currently enabled in Zephyr applications on ARM Cortex-M architecture, minimizing interrupt latency, when the floating point context is active.

When the MPU-based stack protection mechanism is not enabled, lazy stacking is always active in the Zephyr application. When the MPU-based stack protection is enabled, the following rules apply with respect to lazy stacking:

- Lazy stacking is activated by default on threads that are pretagged with `K_FP_REGS`
- Lazy stacking is activated dynamically on threads that are not pretagged with `K_FP_REGS`, as soon as the kernel detects that they are using the floating point registers.

If an ARM thread does not require use of the floating point registers any more, it can call `k_float_disable()`. This instructs the kernel not to save or restore its FP context during thread context switching.

**ARM64 architecture**

Note: The Shared FP registers mode is the default Floating Point Services mode on ARM64. The compiler is free to optimize code using FP/SIMD registers, and library functions such as memcpy are known to make use of them.

On the ARM64 (Aarch64) architecture the kernel treats each thread as a FPU user on a case-by-case basis. A “lazy save” algorithm is used during context switching which updates the floating point registers only when it is absolutely necessary. For example, the registers are not saved when switching from an FPU user to a non-user thread, and then back to the original FPU user.

FPU register usage by ISRs is supported although not recommended. When an ISR uses floating point or SIMD registers, then the access is trapped, the current FPU user context is saved in the thread object and the ISR is resumed with interrupts disabled so to prevent another IRQ from interrupting the ISR and potentially requesting FPU usage. Because ISR don’t have a persistent register context, there are no provision for saving an ISR’s FPU context either, hence the IRQ disabling.

Each thread object becomes 512 bytes larger when Shared FP registers mode is enabled.

**ARCv2 architecture**

On the ARCv2 architecture, the kernel treats each thread as a non-user or FPU user and the thread must be tagged by one of the following techniques.

- A statically-created ARC thread can be tagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.
- A dynamically-created ARC thread can be tagged by passing the `K_FP_REGS` to `k_thread_create()`.

If an ARC thread does not require use of the floating point registers any more, it can call `k_float_disable()`. This instructs the kernel not to save or restore its FP context during thread context switching.

During thread context switching the ARC kernel saves the callee-saved floating point registers, if the switched-out thread has been using them. Additionally, the caller-saved floating point registers are saved on the thread’s stack. If the switched-in thread has been using the floating point registers, the kernel restores the callee-saved FP registers of the switched-in thread and the caller-saved FP context is restored from the thread’s stack. Thus, the kernel does not save or restore the FP context of threads that are not using the FP registers. An extra 16 bytes (single floating point hardware) or 32 bytes (double floating point hardware) of stack space is required to load and store floating point registers.

**RISC-V architecture**

On the RISC-V architecture, the kernel treats each thread as a non-user or FPU user and the thread must be tagged by one of the following techniques:

- A statically-created RISC-V thread can be tagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.
• A dynamically-created RISC-V thread can be tagged by passing the `K_FP_REGS` to `k_thread_create()`.

• A running RISC-V thread can be tagged by calling `k_float_enable()`. This function can only be called from the thread itself.

If a RISC-V thread no longer requires the use of the floating point registers, it can call `k_float_disable()`. This instructs the kernel not to save or restore its FP context during thread context switching. This function can only be called from the thread itself.

During thread context switching the RISC-V kernel saves the callee-saved floating point registers, if the switched-out thread is tagged with `K_FP_REGS`. Additionally, the caller-saved floating point registers are saved on the thread's stack. If the switched-in thread has been tagged with `K_FP_REGS`, then the kernel restores the callee-saved FP registers of the switched-in thread and the caller-saved FP context is restored from the thread’s stack. Thus, the kernel does not save or restore the FP context of threads that are not using the FP registers. An extra 84 bytes (single floating point hardware) or 164 bytes (double floating point hardware) of stack space is required to load and store floating point registers.

**SPARC architecture**  On the SPARC architecture, the kernel treats each thread as a non-user or FPU user and the thread must be tagged by one of the following techniques:

• A statically-created thread can be tagged by passing the `K_FP_REGS` option to `K_THREAD_DEFINE`.

• A dynamically-created thread can be tagged by passing the `K_FP_REGS` to `k_thread_create()`.

During thread context switch at exit from interrupt handler, the SPARC kernel saves all floating point registers, if the FPU was enabled in the switched-out thread. Floating point registers are saved on the thread’s stack. Floating point registers are restored when a thread context is restored iff they were saved at the context save. Saving and restoring of the floating point registers is synchronous and thus not lazy. The FPU is always disabled when an ISR is called (independent of `CONFIG_FPU_SHARING`).

Floating point disabling with `k_float_disable()` is not implemented.

When `CONFIG_FPU_SHARING` is used, then 136 bytes of stack space is required for each FPU user thread to load and store floating point registers. No extra stack is required if `CONFIG_FPU_SHARING` is not used.

**x86 architecture**  On the x86 architecture the kernel treats each thread as a non-user, FPU user or SSE user on a case-by-case basis. A “lazy save” algorithm is used during context switching which updates the floating point registers only when it is absolutely necessary. For example, the registers are *not* saved when switching from an FPU user to a non-user thread, and then back to the original FPU user. The following table indicates the amount of additional stack space a thread must provide so the registers can be saved properly.

<table>
<thead>
<tr>
<th>Thread type</th>
<th>FP register use</th>
<th>Extra stack space required</th>
</tr>
</thead>
<tbody>
<tr>
<td>cooperative</td>
<td>any</td>
<td>0 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>none</td>
<td>0 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>FPU</td>
<td>108 bytes</td>
</tr>
<tr>
<td>preemptive</td>
<td>SSE</td>
<td>464 bytes</td>
</tr>
</tbody>
</table>

The x86 kernel automatically detects that a given thread is using the floating point registers the first time the thread accesses them. The thread is tagged as an SSE user if the kernel has been configured to support the SSE registers, or as an FPU user if the SSE registers are not supported. If this would result in a thread that is an FPU user being tagged as an SSE user, or if the application wants to avoid the exception handling overhead involved in auto-tagging threads, it is possible to pretag a thread using one of the techniques listed below.

• A statically-created x86 thread can be pretagged by passing the `K_FP_REGS` or `K_SSE_REGS` option to `K_THREAD_DEFINE`.

• A dynamically-created x86 thread can be pretagged by passing the `K_FP_REGS` or `K_SSE_REGS` option to `k_thread_create()`.
• An already-created x86 thread can pretag itself once it has started by passing the \texttt{K_FP_REGS} or \texttt{K_SSE_REGS} option to \texttt{k_float_enable()}. If an x86 thread uses the floating point registers infrequently it can call \texttt{k_float_disable()} to remove its tagging as an FPU user or SSE user. This eliminates the need for the kernel to take steps to preserve the contents of the floating point registers during context switches when there is no need to do so. When the thread again needs to use the floating point registers it can re-tag itself as an FPU user or SSE user by calling \texttt{k_float_enable()}.

\textbf{Implementation}

\textbf{Performing Floating Point Arithmetic} \hspace{1em} No special coding is required for a thread to use floating point arithmetic if the kernel is properly configured.

The following code shows how a routine can use floating point arithmetic to avoid overflow issues when computing the average of a series of integer values.

```c
int average(int *values, int num_values) {
    double sum;
    int i;

    sum = 0.0;

    for (i = 0; i < num_values; i++) {
        sum += *values;
        values++;
    }

    return (int)((sum / num_values) + 0.5);
}
```

\textbf{Suggested Uses} \hspace{1em} Use the kernel floating point services when an application needs to perform floating point operations.

\textbf{Configuration Options} \hspace{1em} To configure unshared FP registers mode, enable the \texttt{CONFIG_FPU} configuration option and leave the \texttt{CONFIG_FPU_SHARING} configuration option disabled.

To configure shared FP registers mode, enable both the \texttt{CONFIG_FPU} configuration option and the \texttt{CONFIG_FPU_SHARING} configuration option. Also, ensure that any thread that uses the floating point registers has sufficient added stack space for saving floating point register values during context switches, as described above.

For x86, use the \texttt{CONFIG_X86_SSE} configuration option to enable support for SSEx instructions.

\textbf{API Reference}

\textit{group float APIs}

\textbf{Version}

Kernel version handling and APIs related to kernel version being used.
API Reference

```c
uint32_t sys_kernel_version_get(void)
```

Returns the kernel version of the present build.

The kernel version is a four-byte value, whose format is described in the file “kernel_version.h”.

Returns

- `kernel version`
- `SYS_KERNEL_VER_MAJOR(ver)`
- `SYS_KERNEL_VER_MINOR(ver)`
- `SYS_KERNEL_VER_PATCHLEVEL(ver)`

Fatal Errors

Software Errors Triggered in Source Code

Zephyr provides several methods for inducing fatal error conditions through either build-time checks, conditionally compiled assertions, or deliberately invoked panic or oops conditions.

Runtime Assertions

Zephyr provides some macros to perform runtime assertions which may be conditionally compiled. Their definitions may be found in include/zephyr/sys/__assert.h.

Assertions are enabled by setting the `__ASSERT_ON` preprocessor symbol to a non-zero value. There are two ways to do this:

- Use the `CONFIG_ASSERT` and `CONFIG_ASSERT_LEVEL` kconfig options.
- Add `-D__ASSERT_ON=<level>` to the project’s CFLAGS, either on the build command line or in a CMakeLists.txt.

The `__ASSERT_ON` method takes precedence over the kconfig option if both are used.

Specifying an assertion level of 1 causes the compiler to issue warnings that the kernel contains debug-type `__ASSERT()` statements; this reminder is issued since assertion code is not normally present in a final product. Specifying assertion level 2 suppresses these warnings.

Assertions are enabled by default when running Zephyr test cases, as configured by the `CONFIG_TEST` option.

The policy for what to do when encountering a failed assertion is controlled by the implementation of `assert_post_action()`. Zephyr provides a default implementation with weak linkage which invokes a kernel oops if the thread that failed the assertion was running in user mode, and a kernel panic otherwise.

`__ASSERT()`

The `__ASSERT()` macro can be used inside kernel and application code to perform optional runtime checks which will induce a fatal error if the check does not pass. The macro takes a string message which will be printed to provide context to the assertion. In addition, the kernel will print a text representation of the expression code that was evaluated, and the file and line number where the assertion can be found.

For example:

```c
__ASSERT(foo == 0xF0CACC1A, "Invalid value of foo, got 0x%x", foo);
```

If at runtime `foo` had some unexpected value, the error produced may look like the following:

```
ASSERTION FAIL [foo == 0xF0CACC1A] @ ZEPHYR_BASE/tests/kernel/fatal/src/main.c:367
   Invalid value of foo, got 0xdeadbeef
   [0:00:00.000,000] <err> os: r0/a1: 0x00000004 r1/a2: 0x0000016f r2/a3: 0x00000000
```

(continues on next page)
The __ASSERT_EVAL() macro can also be used inside kernel and application code, with special semantics for the evaluation of its arguments. It makes use of the __ASSERT() macro, but has some extra flexibility. It allows the developer to specify different actions depending whether the __ASSERT() macro is enabled or not. This can be particularly useful to prevent the compiler from generating comments (errors, warnings or remarks) about variables that are only used with __ASSERT() being assigned a value, but otherwise unused when the __ASSERT() macro is disabled.

Consider the following example:

```c
int x;
x = foo();
__ASSERT(x != 0, "foo() returned zero!");
```

If __ASSERT() is disabled, then 'x' is assigned a value, but never used. This type of situation can be resolved using the __ASSERT_EVAL() macro.

```c
__ASSERT_EVAL ((void) foo(),
    int x = foo(),
    x != 0,
    "foo() returned zero!");
```

The first parameter tells __ASSERT_EVAL() what to do if __ASSERT() is disabled. The second parameter tells __ASSERT_EVAL() what to do if __ASSERT() is enabled. The third and fourth parameters are the parameters it passes to __ASSERT().

__ASSERT NO MSG() The __ASSERT NO MSG() macro can be used to perform an assertion that reports the failed test and its location, but lacks additional debugging information provided to assist the user in diagnosing the problem; its use is discouraged.

Build Assertions Zephyr provides two macros for performing build-time assertion checks. These are evaluated completely at compile-time, and are always checked.

BUILD_ASSERT() This has the same semantics as C's _Static_assert or C++’s static_assert. If the evaluation fails, a build error will be generated by the compiler. If the compiler supports it, the provided message will be printed to provide further context.

Unlike __ASSERT(), the message must be a static string, without printf()-like format codes or extra arguments.

For example, suppose this check fails:

```c
BUILD_ASSERT(FOO == 2000, "Invalid value of FOO");
```

With GCC, the output resembles:
Kernel Oops  A kernel oops is a software triggered fatal error invoked by koops(). This should be used to indicate an unrecoverable condition in application logic.

The fatal error reason code generated will be K_ERR_KERNEL_OOPS.

Kernel Panic  A kernel panic is a software triggered fatal error invoked by k_panic(). This should be used to indicate that the Zephyr kernel is in an unrecoverable state. Implementations of k_sys_fatal_error_handler() should not return if the kernel encounters a panic condition, as the entire system needs to be reset.

Threads running in user mode are not permitted to invoke k_panic(), and doing so will generate a kernel oops instead. Otherwise, the fatal error reason code generated will be K_ERR_KERNEL_PANIC.

Exceptions

Spurious Interrupts  If the CPU receives a hardware interrupt on an interrupt line that has not had a handler installed with IRQ_CONNECT() or irq_connect_dynamic(), then the kernel will generate a fatal error with the reason code K_ERR_SPURIOUS_IRQ().

Stack Overflows  In the event that a thread pushes more data onto its execution stack than its stack buffer provides, the kernel may be able to detect this situation and generate a fatal error with a reason code of K_ERR_STACK_CHK_FAIL.

If a thread is running in user mode, then stack overflows are always caught, as the thread will simply not have permission to write to adjacent memory addresses outside of the stack buffer. Because this is enforced by the memory protection hardware, there is no risk of data corruption to memory that the thread would not otherwise be able to write to.

If a thread is running in supervisor mode, or if CONFIG_USERSPACE is not enabled, depending on configuration stack overflows may or may not be caught. CONFIG_HW_STACK_PROTECTION is supported on some architectures and will catch stack overflows in supervisor mode, including when handling a system call on behalf of a user thread. Typically this is implemented via dedicated CPU features, or read-only MMU/MPU guard regions placed immediately adjacent to the stack buffer. Stack overflows caught in this way can detect the overflow, but cannot guarantee against data corruption and should be treated as a very serious condition impacting the health of the entire system.

If a platform lacks memory management hardware support, CONFIG_STACK_SENTINEL is a software-only stack overflow detection feature which periodically checks if a sentinel value at the end of the stack buffer has been corrupted. It does not require hardware support, but provides no protection against data corruption. Since the checks are typically done at interrupt exit, the overflow may be detected a nontrivial amount of time after the stack actually overflowed.

Finally, Zephyr supports GCC compiler stack canaries via CONFIG_STACK_CANARIES. If enabled, the compiler will insert a canary value randomly generated at boot into function stack frames, checking that the canary has not been overwritten at function exit. If the check fails, the compiler invokes __stack_chk_fail(), whose Zephyr implementation invokes a fatal stack overflow error. An error in this case does not indicate that the entire stack buffer has overflowed, but instead that the current function stack frame has been corrupted. See the compiler documentation for more details.
Other Exceptions  Any other type of unhandled CPU exception will generate an error code of K_ERR_CPU_EXCEPTION.

Fatal Error Handling  The policy for what to do when encountering a fatal error is determined by the implementation of the \texttt{k.sys.fatal_error_handler()} function. This function has a default implementation with weak linkage that calls \texttt{LOG_PANIC()} to dump all pending logging messages and then unconditionally halts the system with \texttt{k.fatal.halt()}.

Applications are free to implement their own error handling policy by overriding the implementation of \texttt{k.sys.fatal_error_handler()}. If the implementation returns, the faulting thread will be aborted and the system will otherwise continue to function. See the documentation for this function for additional details and constraints.

API Reference

\texttt{group fatal_apis}

Enums

\texttt{enum k_fatal_error_reason}

\texttt{Values:}

\texttt{enumerator K_ERR_CPU_EXCEPTION}

\texttt{Generic CPU exception, not covered by other codes}

\texttt{enumerator K_ERR_SPURIOUS_IRQ}

\texttt{Unhandled hardware interrupt}

\texttt{enumerator K_ERR_STACK_CHK_FAIL}

\texttt{Faulting context overflowed its stack buffer}

\texttt{enumerator K_ERR_KERNEL_OOPS}

\texttt{Moderate severity software error}

\texttt{enumerator K_ERR_KERNEL_PANIC}

\texttt{High severity software error}

Functions

\texttt{FUNC_NORETURN void k_fatal_halt(unsigned int reason)}

\texttt{Halt the system on a fatal error.}

\texttt{Invokes architecture-specific code to power off or halt the system in a low power state. Lacking that, lock interrupts and sit in an idle loop.}

\texttt{Parameters}

\texttt{• reason – Fatal exception reason code}
void k_sys_fatal_error_handler(unsigned int reason, const z_arch_esf_t *esf)
    Fatal error policy handler.

This function is not invoked by application code, but is declared as a weak symbol so that
applications may introduce their own policy.

The default implementation of this function halts the system unconditionally. Depending on
architecture support, this may be a simple infinite loop, power off the hardware, or exit an
emulator.

If this function returns, then the currently executing thread will be aborted.

A few notes for custom implementations:

- If the error is determined to be unrecoverable, LOG_PANIC() should be invoked to flush
  any pending logging buffers.
- K_ERR_KERNEL_PANIC indicates a severe unrecoverable error in the kernel itself, and
  should not be considered recoverable. There is an assertion in z_fatal_error() to enforce
  this.
- Even outside of a kernel panic, unless the fault occurred in user mode, the kernel it-
  self may be in an inconsistent state, with API calls to kernel objects possibly exhibiting
  undefined behavior or triggering another exception.

Fatal error policy handler.

Test Objective:

- To verify architecture layer provides a mechanism to issue an interprocessor interrupt
to all other CPUs in the system that calls the scheduler IPI. We simply add a hook in
z_sched_ipi(), in order to check if it has been called once in another CPU except the
caller, when arch_sched_ipi() is called.

Testing techniques:

- Interface testing, function and block box testing, dynamic analysis and testing

Prerequisite Conditions:

- CONFIG_SMP=y , and the HW platform must support SMP.
- CONFIG_TRACE_SCHED_IPI=y was set.

Input Specifications:

- N/A

Test Procedure:

a. In main thread, given a global variable sched_ipi_has_called equaled zero.
b. Call arch_sched_ipi() then sleep for 100ms.
c. In z_sched_ipi() handler, increment the sched_ipi_has_called.
d. In main thread, check the sched_ipi_has_called is not equaled to zero.
e. Repeat step 1 to 4 for 3 times.

Expected Test Result:

- The pointer of current cpu data that we got from function call is correct.

Pass/Fail Criteria:

- Successful if the check of step 4 are all passed.
- Failure if one of the check of step 4 is failed.
Assumptions and Constraints:

- This test using for the platform that support SMP, in our current scenario, only x86_64 and arc supported.

**See also:**

*arch_sched_ipt()*

**Parameters**

- `reason` – The reason for the fatal error
- `esf` – Exception context, with details and partial or full register state when the error occurred. May in some cases be NULL.

**Thread Local Storage (TLS)**

Thread Local Storage (TLS) allows variables to be allocated on a per-thread basis. These variables are stored in the thread stack which means every thread has its own copy of these variables.

Zephyr currently requires toolchain support for TLS.

**Configuration** To enable thread local storage in Zephyr, `CONFIG_THREAD_LOCAL_STORAGE` needs to be enabled. Note that this option may not be available if the architecture or the SoC does not have the hidden option `CONFIG_ARCH_HAS_THREAD_LOCAL_STORAGE` enabled, which means the architecture or the SoC does not have the necessary code to support thread local storage and/or the toolchain does not support TLS.

`CONFIG_ERRNO_IN_TLS` can be enabled together with `CONFIG_ERRNO` to let the variable `errno` be a thread local variable. This allows user threads to access the value of `errno` without making a system call.

**Declaring and Using Thread Local Variables** The keyword `__thread` can be used to declare thread local variables.

For example, to declare a thread local variable in header files:

```c
extern __thread int i;
```

And to declare the actual variable in source files:

```c
__thread int i;
```

Keyword `static` can also be used to limit the variable within a source file:

```c
static __thread int j;
```

Using the thread local variable is the same as using other variable, for example:

```c
void testing(void) {
    i = 10;
}
```

### 3.2 Device Driver Model
3.2.1 Introduction

The Zephyr kernel supports a variety of device drivers. Whether a driver is available depends on the board and the driver.

The Zephyr device model provides a consistent device model for configuring the drivers that are part of a system. The device model is responsible for initializing all the drivers configured into the system.

Each type of driver (e.g. UART, SPI, I2C) is supported by a generic type API.

In this model the driver fills in the pointer to the structure containing the function pointers to its API functions during driver initialization. These structures are placed into the RAM section in initialization level order.

3.2.2 Standard Drivers

Device drivers which are present on all supported board configurations are listed below.

- **Interrupt controller**: This device driver is used by the kernel’s interrupt management subsystem.
- **Timer**: This device driver is used by the kernel’s system clock and hardware clock subsystem.
- **Serial communication**: This device driver is used by the kernel’s system console subsystem.
- **Entropy**: This device driver provides a source of entropy numbers for the random number generator subsystem.

**Important**: Use the random API functions for random values. Entropy functions should not be directly used as a random number generator source as some hardware implementations are designed to be an entropy seed source for random number generators and will not provide cryptographically secure random number streams.

3.2.3 Synchronous Calls

Zephyr provides a set of device drivers for multiple boards. Each driver should support an interrupt-based implementation, rather than polling, unless the specific hardware does not provide any interrupt.
High-level calls accessed through device-specific APIs, such as i2c.h or spi.h, are usually intended as synchronous. Thus, these calls should be blocking.

### 3.2.4 Driver APIs

The following APIs for device drivers are provided by device.h. The APIs are intended for use in device drivers only and should not be used in applications.

- **DEVICE_DEFINE()**: Create device object and related data structures including setting it up for boot-time initialization.
- **DEVICE_NAME_GET()**: Converts a device identifier to the global identifier for a device object.
- **DEVICE_GET()**: Obtain a pointer to a device object by name.
- **DEVICE_DECLARE()**: Declare a device object. Use this when you need a forward reference to a device that has not yet been defined.

### 3.2.5 Driver Data Structures

The device initialization macros populate some data structures at build time which are split into read-only and runtime-mutable parts. At a high level we have:

```c
struct device {
    const char *name;
    const void *config;
    const void *api;
    void *const data;
};
```

The `config` member is for read-only configuration data set at build time. For example, base memory mapped IO addresses, IRQ line numbers, or other fixed physical characteristics of the device. This is the `config` pointer passed to `DEVICE_DEFINE()` and related macros.

The `data` struct is kept in RAM, and is used by the driver for per-instance runtime housekeeping. For example, it may contain reference counts, semaphores, scratch buffers, etc.

The `api` struct maps generic subsystem APIs to the device-specific implementations in the driver. It is typically read-only and populated at build time. The next section describes this in more detail.

### 3.2.6 Subsystems and API Structures

Most drivers will be implementing a device-independent subsystem API. Applications can simply program to that generic API, and application code is not specific to any particular driver implementation.

A subsystem API definition typically looks like this:

```c
typedef int (*subsystem_do_this_t)(const struct device *dev, int foo, int bar);
typedef void (*subsystem_do_that_t)(const struct device *dev, void *baz);

struct subsystem_api {
    subsystem_do_this_t do_this;
    subsystem_do_that_t do_that;
};
```

(continues on next page)
static inline int subsystem_do_this(const struct device *dev, int foo, int bar)
{
    struct subsystem_api *api;
    api = (struct subsystem_api *)dev->api;
    return api->do_this(dev, foo, bar);
}

static inline void subsystem_do_that(const struct device *dev, void *baz)
{
    struct subsystem_api *api;
    api = (struct subsystem_api *)dev->api;
    api->do_that(dev, baz);
}

A driver implementing a particular subsystem will define the real implementation of these APIs, and populate an instance of subsystem_api structure:

static int my_driver_do_this(const struct device *dev, int foo, int bar)
{
    ...
}

static void my_driver_do_that(const struct device *dev, void *baz)
{
    ...
}

static struct subsystem_api my_driver_api_funcs = {
    .do_this = my_driver_do_this,
    .do_that = my_driver_do_that
};

The driver would then pass my_driver_api_funcs as the api argument to DEVICE_DEFINE().

Note: Since pointers to the API functions are referenced in the api struct, they will always be included in the binary even if unused; gc-sections linker option will always see at least one reference to them. Providing for link-time size optimizations with driver APIs in most cases requires that the optional feature be controlled by a Kconfig option.

3.2.7 Device-Specific API Extensions

Some devices can be cast as an instance of a driver subsystem such as GPIO, but provide additional functionality that cannot be exposed through the standard API. These devices combine subsystem operations with device-specific APIs, described in a device-specific header.

A device-specific API definition typically looks like this:

#include <zephyr/drivers/subsystem.h>

/* When extensions need not be invoked from user mode threads */
int specific_do_that(const struct device *dev, int foo);

/* When extensions must be invokable from user mode threads */

(continues on next page)
A driver implementing extensions to the subsystem will define the real implementation of both the subsystem API and the specific APIs:

```c
static int generic_do_this(const struct device *dev, void *arg)
{
  ...
}

static struct generic_api api {
  ...
  .do_this = generic_do_this,
  ...
};

/* supervisor-only API is globally visible */
int specific_do_that(const struct device *dev, int foo)
{
  ...
}

/* syscall API passes through a translation */
int z_impl_specific_from_user(const struct device *dev, int bar)
{
  ...
}

#ifdef CONFIG_USERSPACE
  #include <zephyr/syscall_handler.h>

  int z_vrfy_specific_from_user(const struct device *dev, int bar)
  {
    Z_OOPS(Z_SYSCALL_SPECIFIC_DRIVER(dev, K_OBJ_DRIVER_GENERIC, &api));
    return z_impl_specific_do_that(dev, bar)
  }
  #include <syscalls/specific_from_user_mrsh.c>
#endif /* CONFIG_USERSPACE */
```

Applications use the device through both the subsystem and specific APIs.

**Note:** Public API for device-specific extensions should be prefixed with the compatible for the device to which it applies. For example, if adding special functions to support the Maxim DS3231 the identifier fragment `specific` in the examples above would be `maxim_ds3231`.

### 3.2.8 Single Driver, Multiple Instances

Some drivers may be instantiated multiple times in a given system. For example there can be multiple GPIO banks, or multiple UARTs. Each instance of the driver will have a different `config` struct and data
struct.

Configuring interrupts for multiple drivers instances is a special case. If each instance needs to configure a different interrupt line, this can be accomplished through the use of per-instance configuration functions, since the parameters to IRQ_CONNECT() need to be resolvable at build time.

For example, let's say we need to configure two instances of my_driver, each with a different interrupt line. In drivers/subsystem/subsystem_my_driver.h:

```c
typedef void (*my_driver_config_irq_t)(const struct device *dev);

struct my_driver_config {
    DEVICE_MMIO_ROM;
    my_driver_config_irq_t config_func;
};
```

In the implementation of the common init function:

```c
void my_driver_isr(const struct device *dev)
{
    /* Handle interrupt */
    ...
}

int my_driver_init(const struct device *dev)
{
    const struct my_driver_config *config = dev->config;
    DEVICE_MMIO_MAP(dev, K_MEM_CACHE_NONE);
    /* Do other initialization stuff */
    ...
    config->config_func(dev);
    return 0;
}
```

Then when the particular instance is declared:

```c
#if CONFIG_MY DRIVER_0
DEVICE_DECLARE(my_driver_0);

static void my_driver_config_irq_0(void)
{
    IRQ_CONNECT(MY_DRIVER_0_IRQ, MY_DRIVER_0_PRI, my_driver_isr,
                DEVICE_GET(my_driver_0), MY_DRIVER_0_FLAGS);
}

const static struct my_driver_config my_driver_config_0 = {
    DEVICE_MMIO_ROM_INIT(DT_DRV_INST(0)),
    .config_func = my_driver_config_irq_0
}

static struct my_data_0;

DEVICE_DEFINE(my_driver_0, MY_DRIVER_0_NAME, my_driver_init,
              NULL, &my_data_0, &my_driver_config_0,
```
Note the use of `DEVICE_DECLARE()` to avoid a circular dependency on providing the IRQ handler argument and the definition of the device itself.

### 3.2.9 Initialization Levels

Drivers may depend on other drivers being initialized first, or require the use of kernel services. `DEVICE_DEFINE()` and related APIs allow the user to specify at what time during the boot sequence the init function will be executed. Any driver will specify one of four initialization levels:

**EARLY**

Used very early in the boot process, right after entering the C domain (`z_cstart()`). This can be used in architectures and SoCs that extend or implement architecture code and use drivers or system services that have to be initialized before the Kernel calls any architecture specific initialization code.

**PRE_KERNEL_1**

Used for devices that have no dependencies, such as those that rely solely on hardware present in the processor/SOC. These devices cannot use any kernel services during configuration, since the kernel services are not yet available. The interrupt subsystem will be configured however so it’s OK to set up interrupts. Init functions at this level run on the interrupt stack.

**PRE_KERNEL_2**

Used for devices that rely on the initialization of devices initialized as part of the **PRE_KERNEL_1 level**. These devices cannot use any kernel services during configuration, since the kernel services are not yet available. Init functions at this level run on the interrupt stack.

**POST_KERNEL**

Used for devices that require kernel services during configuration. Init functions at this level run in context of the kernel main task.

**APPLICATION**

Used for application components (i.e. non-kernel components) that need automatic configuration. These devices can use all services provided by the kernel during configuration. Init functions at this level run on the kernel main task.

Within each initialization level you may specify a priority level, relative to other devices in the same initialization level. The priority level is specified as an integer value in the range 0 to 99; lower values indicate earlier initialization. The priority level must be a decimal integer literal without leading zeroes or sign (e.g. 32), or an equivalent symbolic name (e.g. `#define MY_INIT_PRIO 32`); symbolic expressions are not permitted (e.g. `CONFIG_KERNEL_INIT_PRIORITY_DEFAULT + 5`).

Drivers and other system utilities can determine whether startup is still in pre-kernel states by using the `k_is_pre_kernel()` function.

### 3.2.10 System Drivers

In some cases you may just need to run a function at boot. For such cases, the `SYS_INIT` can be used. This macro does not take any config or runtime data structures and there isn’t a way to later get a device pointer by name. The same device policies for initialization level and priority apply.
3.2.11 Error handling

In general, it’s best to use `__ASSERT()` macros instead of propagating return values unless the failure is expected to occur during the normal course of operation (such as a storage device full). Bad parameters, programming errors, consistency checks, pathological/unrecoverable failures, etc., should be handled by assertions.

When it is appropriate to return error conditions for the caller to check, 0 should be returned on success and a POSIX `errno.h` code returned on failure. See https://github.com/zephyrproject-rtos/zephyr/wiki/Naming-Conventions#return-codes for details about this.

3.2.12 Memory Mapping

On some systems, the linear address of peripheral memory-mapped I/O (MMIO) regions cannot be known at build time:

- The I/O ranges must be probed at runtime from the bus, such as with PCI express
- A memory management unit (MMU) is active, and the physical address of the MMIO range must be mapped into the page tables at some virtual memory location determined by the kernel.

These systems must maintain storage for the MMIO range within RAM and establish the mapping within the driver’s init function. Other systems do not care about this and can use MMIO physical addresses directly from DTS and do not need any RAM-based storage for it.

For drivers that may need to deal with this situation, a set of APIs under the DEVICE_MMIO scope are defined, along with a mapping function `device_map()`.

Device Model Drivers with one MMIO region

The simplest case is for drivers which need to maintain one MMIO region. These drivers will need to use the `DEVICE_MMIO_ROM` and `DEVICE_MMIO_RAM` macros in the definitions for their `config_info` and `driver_data` structures, with initialization of the `config_info` from DTS using `DEVICE_MMIO_ROM_INIT`.

A call to `DEVICE_MMIO_MAP()` is made within the init function:

```c
#include <device.h>

struct my_driver_config {
    DEVICE_MMIO_ROM; /* Must be first */
    ...
};

struct my_driver_dev_data {
    DEVICE_MMIO_RAM; /* Must be first */
    ...
};

const static struct my_driver_config my_driver_config_0 = {
    DEVICE_MMIO_ROM_INIT(DT_DRV_INST(...)),
    ...
};

int my_driver_init(const struct device *dev)
{
    ...
    DEVICE_MMIO_MAP(dev, K_MEM_CACHE_NONE);
    ...
}

int my_driver_some_function(const struct device *dev)
{
    ...
}
```

(continues on next page)
The particular expansion of these macros depends on configuration. On a device with no MMU or PCI-e, DEVICE_MMIO_MAP and DEVICE_MMIO_RAM expand to nothing.

Device Model Drivers with multiple MMIO regions

Some drivers may have multiple MMIO regions. In addition, some drivers may already be implementing a form of inheritance which requires some other data to be placed first in the config_info and driver_data structures.

This can be managed with the DEVICE_MMIO_NAMED variant macros. These require that DEV_CFG() and DEV_DATA() macros be defined to obtain a properly typed pointer to the driver's config_info or dev_data structs. For example:

```c
struct my_driver_config {
    ...
    DEVICE_MMIO_NAMED_ROM(corge);
    DEVICE_MMIO_NAMED_ROM(grault);
    ...
}

struct my_driver_dev_data {
    ...
    DEVICE_MMIO_NAMED_RAM(corge);
    DEVICE_MMIO_NAMED_RAM(grault);
    ...
}

#define DEV_CFG(_dev) \ 
    ((const struct my_driver_config *)((_dev)->config))

#define DEV_DATA(_dev) \ 
    ((struct my_driver_dev_data *)((_dev)->data))

const static struct my_driver_config my_driver_config_0 = {
    ...
    DEVICE_MMIO_NAMED_ROM_INIT(corge, DT_DRV_INST(...)),
    DEVICE_MMIO_NAMED_ROM_INIT(grault, DT_DRV_INST(...)),
    ...
}

int my_driver_init(const struct device *dev)
{
    ...
    DEVICE_MMIO_NAMED_MAP(dev, corge, K_MEM_CACHE_NONE);
    DEVICE_MMIO_NAMED_MAP(dev, grault, K_MEM_CACHE_NONE);
    ...
}

int my_driver_some_function(const struct device *dev)
```
Device Model Drivers with multiple MMIO regions in the same DT node

Some drivers may have multiple MMIO regions defined into the same DT device node using the `reg-names` property to differentiate them, for example:

```
/dts-v1/;
/
{
    a-driver@40000000 {
        reg = <0x40000000 0x1000>,
              <0x40001000 0x1000>;
        reg-names = "corge", "grault";
    }
};
```

This can be managed as seen in the previous section but this time using the `DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME` macro instead. So the only difference would be in the driver config struct:

```
const static struct my_driver_config my_driver_config_0 = {
    ...
    DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME(corge, DT_DRV_INST(...)),
    DEVICE_MMIO_NAMED_ROM_INIT_BY_NAME(grault, DT_DRV_INST(...)),
    ...
}
```

Drivers that do not use Zephyr Device Model

Some drivers or driver-like code may not use Zephyr’s device model, and alternative storage must be arranged for the MMIO data. An example of this are timer drivers, or interrupt controller code. This can be managed with the `DEVICE_MMIO_TOLEVEL` set of macros, for example:

```
DEVICE_MMIO_TOLEVEL_STATIC(my_regs, DT_DRV_INST(...));

void some_init_code(...) {
    ...
    DEVICE_MMIO_TOLEVEL_MAP(my_regs, K_MEM_CACHE_NONE);
    ...
}

void some_function(...) {
    ...
    sys_write32(DEVICE_MMIO_TOLEVEL_GET(my_regs), 0xDEADBEEF);
    ...
}
```
Drivers that do not use DTS

Some drivers may not obtain the MMIO physical address from DTS, such as is the case with PCI-E. In this case the `device_map()` function may be used directly:

```c
void some_init_code(...) {
    ...
    struct pcie_bar mbar;
    bool bar_found = pcie_get_mbar(bdf, index, &mbar);
    device_map(DEVICE_MMIO_RAM_PTR(dev), mbar.phys_addr, mbar.size, K_MEM_CACHE_NONE);
    ...
}
```

For these cases, `DEVICE_MMIO_ROM` directives may be omitted.

### 3.2.13 API Reference

**group device_model**

Device Model.

**Defines**

**DEVICE_HANDLE_SEP**

Flag value used in lists of device handles to separate distinct groups.

This is the minimum value for the `device_handle_t` type.

**DEVICE_HANDLE_ENDS**

Flag value used in lists of device handles to indicate the end of the list.

This is the maximum value for the `device_handle_t` type.

**DEVICE_HANDLE_NULL**

Flag value used to identify an unknown device.

**DEVICE_NAME_GET(dev_id)**

Expands to the name of a global device object.

Return the full name of a device object symbol created by `DEVICE_DEFINE()`, using the `dev_id` provided to `DEVICE_DEFINE()`. This is the name of the global variable storing the device structure, not a pointer to the string in the `device::name` field.

It is meant to be used for declaring extern symbols pointing to device objects before using the `DEVICE_GET` macro to get the device object.

This macro is normally only useful within device driver source code. In other situations, you are probably looking for `device_get_binding()`.

**Parameters**

- `dev_id` – Device identifier.

**Returns**

The full name of the device object defined by device definition macros.
DEVICE_DEFINE(dev_id, name, init_fn, pm, data, config, level, prio, api)

Create a device object and set it up for boot time initialization.

This macro defines a `device` that is automatically configured by the kernel during system initialization. This macro should only be used when the device is not being allocated from a devicetree node. If you are allocating a device from a devicetree node, use `DEVICE_DT_DEFINE()` or `DEVICE_DT_INST_DEFINE()` instead.

**Parameters**

- **dev_id** – A unique token which is used in the name of the global device structure as a C identifier.
- **name** – A string name for the device, which will be stored in `device::name`. This name can be used to look up the device with `device_get_binding()`. This must be less than `Z_DEVICE_MAX_NAME_LEN` characters (including terminating NULL) in order to be looked up from user mode.
- **init_fn** – Pointer to the device's initialization function, which will be run by the kernel during system initialization.
- **pm** – Pointer to the device's power management resources, a `pm_device`, which will be stored in `device::pm` field. Use NULL if the device does not use PM.
- **data** – Pointer to the device's private mutable data, which will be stored in `device::data`.
- **config** – Pointer to the device's private constant data, which will be stored in `device::config`.
- **level** – The device's initialization level. See System Initialization for details.
- **prio** – The device's priority within its initialization level. See SYS_INIT() for details.
- **api** – Pointer to the device's API structure. Can be NULL.

DEVICE_DT_NAME(node_id)

Return a string name for a devicetree node.

This macro returns a string literal usable as a device's name from a devicetree node identifier.

**Parameters**

- **node_id** – The devicetree node identifier.

**Returns**

The value of the node's `label` property, if it has one. Otherwise, the node's full name in `node-name@unit-address` form.

DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)

Create a device object from a devicetree node identifier and set it up for boot time initialization.

This macro defines a `device` that is automatically configured by the kernel during system initialization. The global device object's name as a C identifier is derived from the node's dependency ordinal. `device::name` is set to `DEVICE_DT_NAME(node_id)`.

The device is declared with extern visibility, so a pointer to a global device object can be obtained with `DEVICE_DT_GET(node_id)` from any source file that includes `<zephyr/device.h>`. Before using the pointer, the referenced object should be checked using `device_is_ready()`.

**Parameters**

- **node_id** – The devicetree node identifier.
- **init_fn** – Pointer to the device's initialization function, which will be run by the kernel during system initialization.
• pm – Pointer to the device's power management resources, a pm_device, which will be stored in device::pm. Use NULL if the device does not use PM.

• data – Pointer to the device's private mutable data, which will be stored in device::data.

• config – Pointer to the device's private constant data, which will be stored in device::config field.

• level – The device's initialization level. See SYS_INIT() for details.

• prio – The device's priority within its initialization level. See SYS_INIT() for details.

• api – Pointer to the device's API structure. Can be NULL.

DEVICE_DT_INST_DEFINE(inst, ...
)

Like DEVICE_DT_DEFINE(), but uses an instance of a DT_DRV_COMPAT compatible instead of a node identifier.

Parameters

• inst – Instance number. The node_id argument to DEVICE_DT_DEFINE() is set to DT_DRV_INST(inst).

• ... – Other parameters as expected by DEVICE_DT_DEFINE().

DEVICE_DT_NAME_GET(node_id)

The name of the global device object for node_id.

Returns the name of the global device structure as a C identifier. The device must be allocated using DEVICE_DT_DEFINE() or DEVICE_DT_INST_DEFINE() for this to work.

This macro is normally only useful within device driver source code. In other situations, you are probably looking for DEVICE_DT_GET().

Parameters

• node_id – Devicetree node identifier

Returns

The name of the device object as a C identifier

DEVICE_DT_GET(node_id)

Get a device reference from a devicetree node identifier.

Returns a pointer to a device object created from a devicetree node, if any device was allocated by a driver.

If no such device was allocated, this will fail at linker time. If you get an error that looks like undefined reference to __device_dts_ord_<N>, that is what happened. Check to make sure your device driver is being compiled, usually by enabling the Kconfig options it requires.

Parameters

• node_id – A devicetree node identifier

Returns

A pointer to the device object created for that node

DEVICE_DT_INST_GET(inst)

Get a device reference for an instance of a DT_DRV_COMPAT compatible.

This is equivalent to DEVICE_DT_GET(DT_DRV_INST(inst)).

Parameters

• inst – DT_DRV_COMPAT instance number
Returns
A pointer to the device object created for that instance

DEVICE_DT_GET_ANY(compat)
Get a device reference from a devicetree compatible.
If an enabled devicetree node has the given compatible and a device object was created from it, this returns a pointer to that device.
If there no such devices, this returns NULL.
If there are multiple, this returns an arbitrary one.
If this returns non-NULL, the device must be checked for readiness before use, e.g. with device_is_ready().

Parameters
• compat – lowercase-and-underscores devicetree compatible

Returns
a pointer to a device, or NULL

DEVICE_DT_GET_ONE(compat)
Get a device reference from a devicetree compatible.
If an enabled devicetree node has the given compatible and a device object was created from it, this returns a pointer to that device.
If there no such devices, this will fail at compile time.
If there are multiple, this returns an arbitrary one.
If this returns non-NULL, the device must be checked for readiness before use, e.g. with device_is_ready().

Parameters
• compat – lowercase-and-underscores devicetree compatible

Returns
a pointer to a device

DEVICE_DT_GET_OR_NULL(node_id)
Utility macro to obtain an optional reference to a device.
If the node identifier refers to a node with status okay, this returns DEVICE_DT_GET(node_id).
Otherwise, it returns NULL.

Parameters
• node_id – devicetree node identifier

Returns
a device reference for the node identifier, which may be NULL.

DEVICE_GET(dev_id)
Obtain a pointer to a device object by name.
Return the address of a device object created by DEVICE_DEFINE(), using the dev_id provided to DEVICE_DEFINE().

Parameters
• dev_id – Device identifier.

Returns
A pointer to the device object created by DEVICE_DEFINE()
DEVICE_DECLARE(dev_id)
Declare a static device object.

This macro can be used at the top-level to declare a device, such that DEVICE_GET() may be used before the full declaration in DEVICE_DEFINE().

This is often useful when configuring interrupts statically in a device's init or per-instance config function, as the init function itself is required by DEVICE_DEFINE() and use of DEVICE_GET() inside it creates a circular dependency.

Parameters
- dev_id – Device identifier.

DEVICE_INIT_DT_GET(node_id)
Get a init_entry reference from a devicetree node.

Parameters
- node_id – A devicetree node identifier

Returns
A pointer to the init_entry object created for that node

DEVICE_INIT_GET(dev_id)
Get a init_entry reference from a device identifier.

Parameters
- dev_id – Device identifier.

Returns
A pointer to the init_entry object created for that device

Typedefs

typedef int16_t device_handle_t
Type used to represent a “handle” for a device.

Every device has an associated handle. You can get a pointer to a device from its handle and vice versa, but the handle uses less space than a pointer. The device.h API mainly uses handles to store lists of multiple devices in a compact way.

The extreme values and zero have special significance. Negative values identify functionality that does not correspond to a Zephyr device, such as the system clock or a SYS_INIT() function.

See also:
device_handle_get()

See also:
device_from_handle()

typedef int (*device_visitor_callback_t)(const struct device *dev, void *context)
Prototype for functions used when iterating over a set of devices.

Such a function may be used in API that identifies a set of devices and provides a visitor API supporting caller-specific interaction with each device in the set.

The visit is said to succeed if the visitor returns a non-negative value.
See also:

device_required_foreach()

See also:

device_supported_foreach()

Param dev

a device in the set being iterated

Param context

state used to support the visitor function

Return

A non-negative number to allow walking to continue, and a negative error code to case the iteration to stop.

Functions

static inline device_handle_t device_handle_get(const struct device *dev)

Get the handle for a given device.

Parameters

• dev – the device for which a handle is desired.

Returns

the handle for the device, or DEVICE_HANDLE_NULL if the device does not have an associated handle.

static inline const struct device *device_from_handle(device_handle_t dev_handle)

Get the device corresponding to a handle.

Parameters

• dev_handle – the device handle

Returns

the device that has that handle, or a null pointer if dev_handle does not identify a device.

static inline const device_handle_t *device_required_handles_get(const struct device *dev, size_t *count)

Get the device handles for devicetree dependencies of this device.

This function returns a pointer to an array of device handles. The length of the array is stored in the count parameter.

The array contains a handle for each device that dev requires directly, as determined from the devicetree. This does not include transitive dependencies; you must recursively determine those.

Parameters

• dev – the device for which dependencies are desired.

• count – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if the device has no devicetree dependencies.

Returns

a pointer to a sequence of count device handles, or a null pointer if dev does not have any dependency data.
static inline const device_handle_t *device_injected_handles_get(const struct device *dev, size_t *count)

Get the device handles for injected dependencies of this device.

This function returns a pointer to an array of device handles. The length of the array is stored in the count parameter.

The array contains a handle for each device that dev manually injected as a dependency, via providing extra arguments to ZDEVICE_DEFINE. This does not include transitive dependencies; you must recursively determine those.

Parameters

• dev – the device for which injected dependencies are desired.

• count – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if the device has no devicetree dependencies.

Returns

a pointer to a sequence of *count device handles, or a null pointer if dev does not have any dependency data.

static inline const device_handle_t *device_supported_handles_get(const struct device *dev, size_t *count)

Get the set of handles that this device supports.

This function returns a pointer to an array of device handles. The length of the array is stored in the count parameter.

The array contains a handle for each device that dev “supports” — that is, devices that require dev directly — as determined from the devicetree. This does not include transitive dependencies; you must recursively determine those.

Parameters

• dev – the device for which supports are desired.

• count – pointer to where this function should store the length of the returned array. No value is stored if the call returns a null pointer. The value may be set to zero if nothing in the devicetree depends on dev.

Returns

a pointer to a sequence of *count device handles, or a null pointer if dev does not have any dependency data.

int device_required_foreach(const struct device *dev, device_visitor_callback_t visitor_cb, void *context)

Visit every device that dev directly requires.

Zephyr maintains information about which devices are directly required by another device; for example an I2C-based sensor driver will require an I2C controller for communication. Required devices can derive from statically-defined devicetree relationships or dependencies registered at runtime.

This API supports operating on the set of required devices. Example uses include making sure required devices are ready before the requiring device is used, and releasing them when the requiring device is no longer needed.

There is no guarantee on the order in which required devices are visited.

If the visitor function returns a negative value iteration is halted, and the returned value from the visitor is returned from this function.

Note: This API is not available to unprivileged threads.
Parameters

- **dev** – a device of interest. The devices that this device depends on will be used as the set of devices to visit. This parameter must not be null.
- **visitor_cb** – the function that should be invoked on each device in the dependency set. This parameter must not be null.
- **context** – state that is passed through to the visitor function. This parameter may be null if visitor tolerates a null context.

Returns

The number of devices that were visited if all visits succeed, or the negative value returned from the first visit that did not succeed.

```c
int device_supported_foreach(const struct device *dev, device_visitor_callback_t visitor_cb, void *context)
```

Visit every device that dev directly supports.

Zephyr maintains information about which devices are directly supported by another device; for example an I2C controller will support an I2C-based sensor driver. Supported devices can derive from statically-defined devicetree relationships.

This API supports operating on the set of supported devices. Example uses include iterating over the devices connected to a regulator when it is powered on.

There is no guarantee on the order in which required devices are visited.

If the visitor function returns a negative value iteration is halted, and the returned value from the visitor is returned from this function.

**Note:** This API is not available to unprivileged threads.

Parameters

- **dev** – a device of interest. The devices that this device supports will be used as the set of devices to visit. This parameter must not be null.
- **visitor_cb** – the function that should be invoked on each device in the support set. This parameter must not be null.
- **context** – state that is passed through to the visitor function. This parameter may be null if visitor tolerates a null context.

Returns

The number of devices that were visited if all visits succeed, or the negative value returned from the first visit that did not succeed.

```c
const struct device *device_get_binding(const char *name)
```

Get a device reference from its device::name field.

This function iterates through the devices on the system. If a device with the given name field is found, and that device initialized successfully at boot time, this function returns a pointer to the device.

If no device has the given name, this function returns NULL.

This function also returns NULL when a device is found, but it failed to initialize successfully at boot time. (To troubleshoot this case, set a breakpoint on your device driver's initialization function.)

Parameters

- **name** – device name to search for. A null pointer, or a pointer to an empty string, will cause NULL to be returned.
Returns

pointer to device structure with the given name; NULL if the device is not found
or if the device with that name's initialization function failed.

bool device_is_ready(const struct device *dev)

Verify that a device is ready for use.

Indicates whether the provided device pointer is for a device known to be in a state where it
can be used with its standard API.

This can be used with device pointers captured from DEVICE_DT_GET(), which does not in-
clude the readiness checks of device_get_binding(). At minimum this means that the device
has been successfully initialized.

Parameters

• dev – pointer to the device in question.

Return values

• true – If the device is ready for use.
• false – If the device is not ready for use or if a NULL device pointer is passed
as argument.

struct device_state

#include <device.h> Runtime device dynamic structure (in RAM) per driver instance.

Fields in this are expected to be default-initialized to zero. The kernel driver infrastructure
and driver access functions are responsible for ensuring that any non-zero initialization is
done before they are accessed.

Public Members

uint8_t init_res

Device initialization return code (positive errno value).

Device initialization functions return a negative errno code if they fail. In Zephyr, errno
values do not exceed 255, so we can store the positive result value in a uint8_t type.

bool initialized

Indicates the device initialization function has been invoked.

struct device

#include <device.h> Runtime device structure (in ROM) per driver instance.

Public Members

const char *name

Name of the device instance

const void *config

Address of device instance config information

const void *api

Address of the API structure exposed by the device instance
struct device_state *state
   Address of the common device state

void *data
   Address of the device instance private data

const device_handle_t *handles
   Optional pointer to handles associated with the device.
   This encodes a sequence of sets of device handles that have some relationship to this node. The individual sets are extracted with dedicated API, such as device_required_handles_get().

struct pm_device *pm
   Reference to the device PM resources (only available if CONFIG_PM_DEVICE is enabled).

3.3 User Mode

Zephyr offers the capability to run threads at a reduced privilege level which we call user mode. The current implementation is designed for devices with MPU hardware.

For details on creating threads that run in user mode, please see Lifecycle.

3.3.1 Overview

Threat Model

User mode threads are considered to be untrusted by Zephyr and are therefore isolated from other user mode threads and from the kernel. A flawed or malicious user mode thread cannot leak or modify the private data/resources of another thread or the kernel, and cannot interfere with or control another user mode thread or the kernel.

Example use-cases of Zephyr’s user mode features:

- The kernel can protect against many unintentional programming errors which could otherwise silently or spectacularly corrupt the system.
- The kernel can sandbox complex data parsers such as interpreters, network protocols, and file systems such that malicious third-party code or data cannot compromise the kernel or other threads.
- The kernel can support the notion of multiple logical “applications”, each with their own group of threads and private data structures, which are isolated from each other if one crashes or is otherwise compromised.

Design Goals  For threads running in a non-privileged CPU state (hereafter referred to as ‘user mode’) we aim to protect against the following:

- We prevent access to memory not specifically granted, or incorrect access to memory that has an incompatible policy, such as attempting to write to a read-only area.
  - Access to thread stack buffers will be controlled with a policy which partially depends on the underlying memory protection hardware.
    * A user thread will by default have read/write access to its own stack buffer.
    * A user thread will never by default have access to user thread stacks that are not members of the same memory domain.
* A user thread will never by default have access to thread stacks owned by a supervisor thread, or thread stacks used to handle system call privilege elevations, interrupts, or CPU exceptions.

* A user thread may have read/write access to the stacks of other user threads in the same memory domain, depending on hardware.
  
  · On MPU systems, threads may only access their own stack buffer.
  
  · On MMU systems, threads may access any user thread stack in the same memory domain. Portable code should not assume this.

  − By default, program text and read-only data are accessible to all threads on read-only basis, kernel-wide. This policy may be adjusted.

  − User threads by default are not granted default access to any memory except what is noted above.

  · We prevent use of device drivers or kernel objects not specifically granted, with the permission granularity on a per object or per driver instance basis.

  · We validate kernel or driver API calls with incorrect parameters that would otherwise cause a crash or corruption of data structures private to the kernel. This includes:
    
    − Using the wrong kernel object type.

    − Using parameters outside of proper bounds or with nonsensical values.

    − Passing memory buffers that the calling thread does not have sufficient access to read or write, depending on the semantics of the API.

    − Use of kernel objects that are not in a proper initialization state.

  · We ensure the detection and safe handling of user mode stack overflows.

  · We prevent invoking system calls to functions excluded by the kernel configuration.

  · We prevent disabling of or tampering with kernel-defined and hardware-enforced memory protections.

  · We prevent re-entry from user to supervisor mode except through the kernel-defined system calls and interrupt handlers.

  · We prevent the introduction of new executable code by user mode threads, except to the extent to which this is supported by kernel system calls.

We are specifically not protecting against the following attacks:

  · The kernel itself, and any threads that are executing in supervisor mode, are assumed to be trusted.

  · The toolchain and any supplemental programs used by the build system are assumed to be trusted.

  · The kernel build is assumed to be trusted. There is considerable build-time logic for creating the tables of valid kernel objects, defining system calls, and configuring interrupts. The .elf binary files that are worked with during this process are all assumed to be trusted code.

  · We can’t protect against mistakes made in memory domain configuration done in kernel mode that exposes private kernel data structures to a user thread. RAM for kernel objects should always be configured as supervisor-only.

  · It is possible to make top-level declarations of user mode threads and assign them permissions to kernel objects. In general, all C and header files that are part of the kernel build producing zephyr.elf are assumed to be trusted.

  · We do not protect against denial of service attacks through thread CPU starvation. Zephyr has no thread priority aging and a user thread of a particular priority can starve all threads of lower priority, and also other threads of the same priority if time-slicing is not enabled.

  · There are build-time defined limits on how many threads can be active simultaneously, after which creation of new user threads will fail.
• Stack overflows for threads running in supervisor mode may be caught, but the integrity of the system cannot be guaranteed.

High-level Policy Details

Broadly speaking, we accomplish these thread-level memory protection goals through the following mechanisms:

• Any user thread will only have access to a subset of memory: typically its stack, program text, read-only data, and any partitions configured in the Memory Protection Design it belongs to. Access to any other RAM must be done on the thread’s behalf through system calls, or specifically granted by a supervisor thread using the memory domain APIs. Newly created threads inherit the memory domain configuration of the parent. Threads may communicate with each other by having shared membership of the same memory domains, or via kernel objects such as semaphores and pipes.

• User threads cannot directly access memory belonging to kernel objects. Although pointers to kernel objects are used to reference them, actual manipulation of kernel objects is done through system call interfaces. Device drivers and threads stacks are also considered kernel objects. This ensures that any data inside a kernel object that is private to the kernel cannot be tampered with.

• User threads by default have no permission to access any kernel object or driver other than their own thread object. Such access must be granted by another thread that is either in supervisor mode or has permission on both the receiving thread object and the kernel object being granted access to. The creation of new threads has an option to automatically inherit permissions of all kernel objects granted to the parent, except the parent thread itself.

• For performance and footprint reasons Zephyr normally does little or no parameter error checking for kernel object or device driver APIs. Access from user mode through system calls involves an extra layer of handler functions, which are expected to rigorously validate access permissions and type of the object, check the validity of other parameters through bounds checking or other means, and verify proper read/write access to any memory buffers involved.

• Thread stacks are defined in such a way that exceeding the specified stack space will generate a hardware fault. The way this is done specifically varies per architecture.

Constraints

All kernel objects, thread stacks, and device driver instances must be defined at build time if they are to be used from user mode. Dynamic use-cases for kernel objects will need to go through pre-defined pools of available objects.

There are some constraints if additional application binary data is loaded for execution after the kernel starts:

• Loaded object code will not be able to define any kernel objects that will be recognized by the kernel. This code will instead need to use APIs for requesting kernel objects from pools.

• Similarly, since the loaded object code will not be part of the kernel build process, this code will not be able to install interrupt handlers, instantiate device drivers, or define system calls, regardless of what mode it runs in.

• Loaded object code that does not come from a verified source should always be entered with the CPU already in user mode.

3.3.2 Memory Protection Design

Zephyr’s memory protection design is geared towards microcontrollers with MPU (Memory Protection Unit) hardware. We do support some architectures, such as x86, which have a paged MMU (Memory Management Unit), but in that case the MMU is used like an MPU with an identity page table.
All of the discussion below will be using MPU terminology; systems with MMUs can be considered to have an MPU with an unlimited number of programmable regions.

There are a few different levels on how memory access is configured when Zephyr memory protection features are enabled, which we will describe here:

**Boot Time Memory Configuration**

This is the configuration of the MPU after the kernel has started up. It should contain the following:

- Any configuration of memory regions which need to have special caching or write-back policies for basic hardware and driver function. Note that most MPUs have the concept of a default memory access policy map, which can be enabled as a “background” mapping for any area of memory that doesn’t have an MPU region configuring it. It is strongly recommended to use this to maximize the number of available MPU regions for the end user. On ARMv7-M/ARMv8-M this is called the System Address Map, other CPUs may have similar capabilities.

- A read-only, executable region or regions for program text and ro-data, that is accessible to user mode. This could be further sub-divided into a read-only region for ro-data, and a read-only, executable region for text, but this will require an additional MPU region. This is required so that threads running in user mode can read ro-data and fetch instructions.

- Depending on configuration, user-accessible read-write regions to support extra features like GCOV, HEP, etc.

Assuming there is a background map which allows supervisor mode to access any memory it needs, and regions are defined which grant user mode access to text/ro-data, this is sufficient for the boot time configuration.

**Hardware Stack Overflow**

CONFIG_HW_STACK_PROTECTION is an optional feature which detects stack buffer overflows when the system is running in supervisor mode. This catches issues when the entire stack buffer has overflowed, and not individual stack frames, use compiler-assisted CONFIG_STACK_CANARIES for that.

Like any crash in supervisor mode, no guarantees can be made about the overall health of the system after a supervisor mode stack overflow, and any instances of this should be treated as a serious error. However it’s still very useful to know when these overflows happen, as without robust detection logic the system will either crash in mysterious ways or behave in an undefined manner when the stack buffer overflows.

Some systems implement this feature by creating at runtime a ‘guard’ MPU region which is set to be read-only and is at either the beginning or immediately preceding the supervisor mode stack buffer. If the stack overflows an exception will be generated.

This feature is optional and is not required to catch stack overflows in user mode; disabling this may free 1-2 MPU regions depending on the MPU design.

Other systems may have dedicated CPU support for catching stack overflows and no extra MPU regions will be required.

**Thread Stack**

Any thread running in user mode will need access to its own stack buffer. On context switch into a user mode thread, a dedicated MPU region will be programmed with the bounds of the stack buffer. A thread exceeding its stack buffer will start pushing data onto memory it doesn’t have access to and a memory access violation exception will be generated.
Thread Resource Pools

A small subset of kernel APIs, invoked as system calls, require heap memory allocations. This memory is used only by the kernel and is not accessible directly by user mode. In order to use these system calls, invoking threads must assign themselves to a resource pool, which is a k_heap object. Memory is drawn from a thread's resource pool using `z_thread_malloc()` and freed with `k_free()`.

The APIs which use resource pools are as follows, with any alternatives noted for users who do not want heap allocations within their application:

- `k_stack_alloc_init()` sets up a k_stack with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare k_stacks that are automatically initialized at boot with `K_STACK_DEFINE()`, or to initialize the k_stack in supervisor mode with `k_stack_init()`.

- `k_pipe_alloc_init()` sets up a k_pipe object with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare k_pipes that are automatically initialized at boot with `K_PIPE_DEFINE()`, or to initialize the k_pipe in supervisor mode with `k_pipe_init()`.

- `k_msgq_alloc_init()` sets up a k_msgq object with its storage buffer allocated out of a resource pool instead of a buffer provided by the user. An alternative is to declare a k_msgq that is automatically initialized at boot with `K_MSGQ_DEFINE()`, or to initialize the k_msgq in supervisor mode with `k_msgq_init()`.

- `k_poll()` when invoked from user mode, needs to make a kernel-side copy of the provided events array while waiting for an event. This copy is freed when `k_poll()` returns for any reason.

- `k_queue_alloc_prepend()` and `k_queue_alloc_append()` allocate a container structure to place the data in, since the internal bookkeeping information that defines the queue cannot be placed in the memory provided by the user.

- `k_object_alloc()` allows for entire kernel objects to be dynamically allocated at runtime and a usable pointer to them returned to the caller.

The relevant API is `k_thread_heap_assign()` which assigns a k_heap to draw these allocations from for the target thread.

If the system heap is enabled, then the system heap may be used with `k_thread_system_pool_assign()`, but it is preferable for different logical applications running on the system to have their own pools.

Memory Domains

The kernel ensures that any user thread will have access to its own stack buffer, plus program text and read-only data. The memory domain APIs are the way to grant access to additional blocks of memory to a user thread.

Conceptually, a memory domain is a collection of some number of memory partitions. The maximum number of memory partitions in a domain is limited by the number of available MPU regions. This is why it is important to minimize the number of boot-time MPU regions.

Memory domains are not intended to control access to memory from supervisor mode. In some cases this may be unavoidable; for example some architectures do not allow for the definition of regions which are read-only to user mode but read-write to supervisor mode. A great deal of care must be taken when working with such regions to not unintentionally cause the kernel to crash when accessing such a region. Any attempt to use memory domain APIs to control supervisor mode access is at best undefined behavior; supervisor mode access policy is only intended to be controlled by boot-time memory regions.

Memory domain APIs are only available to supervisor mode. The only control user mode has over memory domains is that any user thread's child threads will automatically become members of the parent's domain.
All threads are members of a memory domain, including supervisor threads (even though this has no implications on their memory access). There is a default domain `k_mem_domain_default` which will be assigned to threads if they have not been specifically assigned to a domain, or inherited a memory domain membership from their parent thread. The main thread starts as a member of the default domain.

**Memory Partitions** Each memory partition consists of a memory address, a size, and access attributes. It is intended that memory partitions are used to control access to system memory. Defining memory partitions are subject to the following constraints:

- The partition must represent a memory region that can be programmed by the underlying memory management hardware, and needs to conform to any underlying hardware constraints. For example, many MPU-based systems require that partitions be sized to some power of two, and aligned to their own size. For MMU-based systems, the partition must be aligned to a page and the size some multiple of the page size.

- Partitions within the same memory domain may not overlap each other. There is no notion of precedence among partitions within a memory domain. Partitions within a memory domain are assumed to have a higher precedence than any boot-time memory regions, however whether a memory domain partition can overlap a boot-time memory region is architecture specific.

- The same partition may be specified in multiple memory domains. For example there may be a shared memory area that multiple domains grant access to.

- Care must be taken in determining what memory to expose in a partition. It is not appropriate to provide direct user mode access to any memory containing private kernel data.

- Memory domain partitions are intended to control access to system RAM. Configuration of memory partitions which do not correspond to RAM may not be supported by the architecture; this is true for MMU-based systems.

There are two ways to define memory partitions: either manually or automatically.

**Manual Memory Partitions** The following code declares a global array `buf`, and then declares a read-write partition for it which may be added to a domain:

```c
uint8_t __aligned(32) buf[32];
K_MEM_PARTITION_DEFINE(my_partition, buf, sizeof(buf), K_MEM_PARTITION_P_RW_U_RW);
```

This does not scale particularly well when we are trying to contain multiple objects spread out across several C files into a single partition.

**Automatic Memory Partitions** Automatic memory partitions are created by the build system. All globals which need to be placed inside a partition are tagged with their destination partition. The build system will then coalesce all of these into a single contiguous block of memory, zero any BSS variables at boot, and define a memory partition of appropriate base address and size which contains all the tagged data.

Automatic memory partitions are only configured as read-write regions. They are defined with `K_APPMEM_PARTITION_DEFINE()`. Global variables are then routed to this partition using `K_APP_DMEM()` for initialized data and `K_APP_BMEM()` for BSS.

```c
#include <zephyr/app_memory/app_memdomain.h>

/* Declare a k_mem_partition "my_partition" that is read-write to * user mode. Note that we do not specify a base address or size. */
K_APPMEM_PARTITION_DEFINE(my_partition);
```

(continues on next page)
/* The global variable var1 will be inside the bounds of my_partition * and be initialized with 37 at boot. */

K_APP_DMEM(my_partition) int var1 = 37;

/* The global variable var2 will be inside the bounds of my_partition * and be zeroed at boot size K_APP_BMEM() was used, indicating a BSS * variable. */

K_APP_BMEM(my_partition) int var2;

The build system will ensure that the base address of my_partition will be properly aligned, and the total size of the region conforms to the memory management hardware requirements, adding padding if necessary.

If multiple partitions are being created, a variadic preprocessor macro can be used as provided in app_macro_support.h:

FOR_EACH(K_APPMEM_PARTITION_DEFINE, part0, part1, part2);

**Automatic Partitions for Static Library Globals** The build-time logic for setting up automatic memory partitions is in scripts/build/gen_app_partitions.py. If a static library is linked into Zephyr, it is possible to route all the globals in that library to a specific memory partition with the --library argument.

For example, if the Newlib C library is enabled, the Newlib globals all need to be placed in z_libc_partition. The invocation of the script in the top-level CMakeLists.txt adds the following:

```bash
gen_app_partitions.py ... --library libc.a z_libc_partition...
```

For pre-compiled libraries there is no support for expressing this in the project-level configuration or build files; the toplevel CMakeLists.txt must be edited.

For Zephyr libraries created using zephyr_library or zephyr_library_named the zephyr_library_app_memory function can be used to specify the memory partition where all
globals in the library should be placed.

Pre-defined Memory Partitions  There are a few memory partitions which are pre-defined by the system:

- **z_malloc_partition** - This partition contains the system-wide pool of memory used by libc malloc(). Due to possible starvation issues, it is not recommended to draw heap memory from a global pool, instead it is better to define various sys_heap objects and assign them to specific memory domains.

- **z_libc_partition** - Contains globals required by the C library and runtime. Required when using either the Minimal C library or the Newlib C Library. Required when CONFIG_STACK_CANARIES is enabled.

Library-specific partitions are listed in include/app_memory/partitions.h. For example, to use theMBEDTLS library from user mode, the k_mbedtls_partition must be added to the domain.

Memory Domain Usage

Create a Memory Domain  A memory domain is defined using a variable of type k_mem_domain. It must then be initialized by calling k_mem_domain_init().

The following code defines and initializes an empty memory domain.

```c
struct k_mem_domain app0_domain;

k_mem_domain_init(&app0_domain, 0, NULL);
```

Add Memory Partitions into a Memory Domain  There are two ways to add memory partitions into a memory domain.

This first code sample shows how to add memory partitions while creating a memory domain.

```c
/* the start address of the MPU region needs to align with its size */
uint8_t __aligned(32) app0_buf[32];
uint8_t __aligned(32) app1_buf[32];

K_MEM_PARTITION_DEFINE(app0_part0, app0_buf, sizeof(app0_buf),
                         K_MEM_PARTITION_P_RW_U_RW);
K_MEM_PARTITION_DEFINE(app0_part1, app1_buf, sizeof(app1_buf),
                         K_MEM_PARTITION_P_RW_U_RO);

struct k_mem_partition *app0_parts[] = {
    app0_part0,
    app0_part1
};

k_mem_domain_init(&app0_domain, ARRAY_SIZE(app0_parts), app0_parts);
```

This second code sample shows how to add memory partitions into an initialized memory domain one by one.

```c
/* the start address of the MPU region needs to align with its size */
uint8_t __aligned(32) app0_buf[32];
uint8_t __aligned(32) app1_buf[32];
```

(continues on next page)
K_MEM_PARTITION_DEFINE(app0_part0, app0_buf, sizeof(app0_buf),
    K_MEM_PARTITION_P_RW_U_RW);
K_MEM_PARTITION_DEFINE(app0_part1, app1_buf, sizeof(app1_buf),
    K_MEM_PARTITION_P_RW_U_RO);

k_mem_domain_add_partition(&app0_domain, &app0_part0);
k_mem_domain_add_partition(&app0_domain, &app0_part1);

Note: The maximum number of memory partitions is limited by the maximum number of MPU regions
or the maximum number of MMU tables.

Memory Domain Assignment Any thread may join a memory domain, and any memory domain may
have multiple threads assigned to it. Threads are assigned to memory domains with an API call:
k_mem_domain_add_thread(&app0_domain, app_thread_id);

If the thread was already a member of some other domain (including the default domain), it will be
removed from it in favor of the new one.
In addition, if a thread is a member of a memory domain, and it creates a child thread, that thread will
belong to the domain as well.

Remove a Memory Partition from a Memory Domain The following code shows how to remove a
memory partition from a memory domain.
k_mem_domain_remove_partition(&app0_domain, &app0_part1);

The k_mem_domain_remove_partition() API finds the memory partition that matches the given param-
er and removes that partition from the memory domain.

Available Partition Attributes When defining a partition, we need to set access permission attributes
to the partition. Since the access control of memory partitions relies on either an MPU or MMU, the
available partition attributes would be architecture dependent.
The complete list of available partition attributes for a specific architecture is found in the architecture-
specific include file include/arch/<arch name>/arch.h, (for example, include/arch/arm/aarch32/
arch.h.) Some examples of partition attributes are:

/* Denote partition is privileged read/write, unprivileged read/write */
K_MEM_PARTITION_P_RW_U_RW
/* Denote partition is privileged read/write, unprivileged read-only */
K_MEM_PARTITION_P_RW_U_RO

In almost all cases K_MEM_PARTITION_P_RW_U_RW is the right choice.

Configuration Options

Related configuration options:

- CONFIG_MAX_DOMAIN_PARTITIONS
API Reference

The following memory domain APIs are provided by include/zephyr/kernel.h:

**group mem_domain_apis**

**Defines**

```c
K_MEM_PARTITION_DEFINE(name, start, size, attr)
```

Statically declare a memory partition.

**Functions**

```c
int k_mem_domain_init(struct k_mem_domain *domain, uint8_t num_parts, struct k_mem_partition *parts[])
```

Initialize a memory domain.

Initialize a memory domain with given name and memory partitions.

See documentation for `k_mem_domain_add_partition()` for details about partition constraints.

Do not call `k_mem_domain_init()` on the same memory domain more than once, doing so is undefined behavior.

**Parameters**

- `domain` – The memory domain to be initialized.
- `num_parts` – The number of array items of “parts” parameter.
- `parts` – An array of pointers to the memory partitions. Can be NULL if `num_parts` is zero.

**Return values**

- 0 – if successful
- -EINVAL – if invalid parameters supplied
- -ENOMEM – if insufficient memory

```c
int k_mem_domain_add_partition(struct k_mem_domain *domain, struct k_mem_partition *part)
```

Add a memory partition into a memory domain.

Add a memory partition into a memory domain. Partitions must conform to the following constraints:

- Partitions in the same memory domain may not overlap each other.
- Partitions must not be defined which expose private kernel data structures or kernel objects.
- The starting address alignment, and the partition size must conform to the constraints of the underlying memory management hardware, which varies per architecture.
- Memory domain partitions are only intended to control access to memory from user mode threads.
- If CONFIG_EXECUTE_XOR_WRITE is enabled, the partition must not allow both writes and execution.

Violating these constraints may lead to CPU exceptions or undefined behavior.
Parameters

- domain – The memory domain to be added a memory partition.
- part – The memory partition to be added

Return values

- 0 – if successful
- EINVAL – if invalid parameters supplied
- ENOSPC – if no free partition slots available

int k_mem_domain_remove_partition(struct k_mem_domain *domain, struct k_mem_partition *part)

Remove a memory partition from a memory domain.

Parameters

- domain – The memory domain to be removed a memory partition.
- part – The memory partition to be removed

Return values

- 0 – if successful
- EINVAL – if invalid parameters supplied
- ENOENT – if no matching partition found

int k_mem_domain_add_thread(struct k_mem_domain *domain, k_tid_t thread)

Add a thread into a memory domain.

Parameters

- domain – The memory domain that the thread is going to be added into.
- thread – ID of thread going to be added into the memory domain.

Returns

0 if successful, fails otherwise.

Variables

struct k_mem_domain k_mem_domain_default

Default memory domain

All threads are a member of some memory domain, even if running in supervisor mode. Threads belong to this default memory domain if they haven't been added to or inherited membership from some other domain.

This memory domain has the z_libc_partition partition for the C library added to it if exists.

struct k_mem_partition

#include <mem_domain.h> Memory Partition.

A memory partition is a region of memory in the linear address space with a specific access policy.
The alignment of the starting address, and the alignment of the size value may have varying requirements based on the capabilities of the underlying memory management hardware; arbitrary values are unlikely to work.

Public Members

```c
uintptr_t start
    start address of memory partition
size_t size
    size of memory partition
k_mem_partition_attr_t attr
    attribute of memory partition
```

```c
struct k_mem_domain
    #include <mem_domain.h> Memory Domain.
A memory domain is a collection of memory partitions, used to represent a user thread's access policy for the linear address space. A thread may be a member of only one memory domain, but any memory domain may have multiple threads that are members.
Supervisor threads may also be a member of a memory domain; this has no implications on their memory access but can be useful as any child threads inherit the memory domain membership of the parent.
A user thread belonging to a memory domain with no active partitions will have guaranteed access to its own stack buffer, program text, and read-only data.

Public Members

```c
struct k_mem_partition partitions[CONFIG_MAX_DOMAIN_PARTITIONS]
    partitions in the domain
sys_dlist_t mem_domain_q
    Doubly linked list of member threads
uint8_t num_partitions
    number of active partitions in the domain
```

3.3.3 Kernel Objects

A kernel object can be one of three classes of data:

- A core kernel object, such as a semaphore, thread, pipe, etc.
- A thread stack, which is an array of `z_thread_stack_element` and declared with `K_THREAD_STACK_DEFINE()`
- A device driver instance (const struct device) that belongs to one of a defined set of subsystems
The set of known kernel objects and driver subsystems is defined in include/kernel.h as `k_objects`.

Kernel objects are completely opaque to user threads. User threads work with addresses to kernel objects when making API calls, but may never dereference these addresses, doing so will cause a memory protection fault. All kernel objects must be placed in memory that is not accessible by user threads.

Since user threads may not directly manipulate kernel objects, all use of them must go through system calls. In order to perform a system call on a kernel object, checks are performed by system call handler functions that the kernel object address is valid and that the calling thread has sufficient permissions to work with it.

Permission on an object also has the semantics of a reference to an object. This is significant for certain object APIs which do temporary allocations, or objects which themselves have been allocated from a runtime memory pool.

If an object loses all references, two events may happen:

- If the object has an associated cleanup function, the cleanup function may be called to release any runtime-allocated buffers the object was using.
- If the object itself was dynamically allocated, the memory for the object will be freed.

### Object Placement

Kernel objects that are only used by supervisor threads have no restrictions and can be located anywhere in the binary, or even declared on stacks. However, to prevent accidental or intentional corruption by user threads, they must not be located in any memory that user threads have direct access to.

In order for a static kernel object to be usable by a user thread via system call APIs, several conditions must be met on how the kernel object is declared:

- The object must be declared as a top-level global at build time, such that it appears in the ELF symbol table. It is permitted to declare kernel objects with static scope. The post-build script `scripts/build/gen_kobject_list.py` scans the generated ELF file to find kernel objects and places their memory addresses in a special table of kernel object metadata. Kernel objects may be members of arrays or embedded within other data structures.
- Kernel objects must be located in memory reserved for the kernel. They must not be located in any memory partitions that are user-accessible.
- Any memory reserved for a kernel object must be used exclusively for that object. Kernel objects may not be members of a union data type.

Kernel objects that are found but do not meet the above conditions will not be included in the generated table that is used to validate kernel object pointers passed in from user mode.

The debug output of the `scripts/build/gen_kobject_list.py` script may be useful when debugging why some object was unexpectedly not being tracked. This information will be printed if the script is run with the `--verbose` flag, or if the build system is invoked with verbose output.

### Dynamic Objects

Kernel objects may also be allocated at runtime if `CONFIG_DYNAMIC_OBJECTS` is enabled. In this case, the `k_object_alloc()` API may be used to instantiate an object from the calling thread’s resource pool. Such allocations may be freed in two ways:

- Supervisor threads may call `k_object_free()` to force a dynamic object to be released.
- If an object’s references drop to zero (which happens when no threads have permissions on it) the object will be automatically freed. User threads may drop their own permission on an object with `k_object_release()`, and their permissions are automatically cleared when a thread terminates. Supervisor threads may additionally revoke references for another thread using `k_object_access_revoke()`. 

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Because permissions are also used for reference counting, it is important for supervisor threads to acquire permissions on objects they are using even though the access control aspects of the permission system are not enforced.

**Implementation Details**  The `scripts/build/gen_kobject_list.py` script is a post-build step which finds all the valid kernel object instances in the binary. It accomplishes this by parsing the DWARF debug information present in the generated ELF file for the kernel.

Any instances of structs or arrays corresponding to kernel objects that meet the object placement criteria will have their memory addresses placed in a special perfect hash table of kernel objects generated by the ‘gperf’ tool. When a system call is made and the kernel is presented with a memory address of what may or may not be a valid kernel object, the address can be validated with a constant-time lookup in this table.

Drivers are a special case. All drivers are instances of `device`, but it is important to know what subsystem a driver belongs to so that incorrect operations, such as calling a UART API on a sensor driver object, can be prevented. When a device struct is found, its API pointer is examined to determine what subsystem the driver belongs to.

The table itself maps kernel object memory addresses to instances of `z_object`, which has all the metadata for that object. This includes:

- A bitfield indicating permissions on that object. All threads have a numerical ID assigned to them at build time, used to index the permission bitfield for an object to see if that thread has permission on it. The size of this bitfield is controlled by the `CONFIG_MAX_THREAD_BYTES` option and the build system will generate an error if this value is too low.
- A type field indicating what kind of object this is, which is some instance of `k_objects`.
- A set of flags for that object. This is currently used to track initialization state and whether an object is public or not.
- An extra data field. The semantics of this field vary by object type, see the definition of `z_object_data`.

Dynamic objects allocated at runtime are tracked in a runtime red/black tree which is used in parallel to the gperf table when validating object pointers.

**Supervisor Thread Access Permission**

Supervisor threads can access any kernel object. However, permissions for supervisor threads are still tracked for two reasons:

- If a supervisor thread calls `k_thread_user_mode_enter()`, the thread will then run in user mode with any permissions it had been granted (in many cases, by itself) when it was a supervisor thread.
- If a supervisor thread creates a user thread with the `K_INHERIT_PERMS` option, the child thread will be granted the same permissions as the parent thread, except the parent thread object.

**User Thread Access Permission**

By default, when a user thread is created, it will only have access permissions on its own thread object. Other kernel objects by default are not usable. Access to them needs to be explicitly or implicitly granted. There are several ways to do this.

- If a thread is created with the `K_INHERIT_PERMS`, that thread will inherit all the permissions of the parent thread, except the parent thread object.
- A thread that has permission on an object, or is running in supervisor mode, may grant permission on that object to another thread via the `k_object_access_grant()` API. The convenience pseudo-function `k_thread_access_grant()` may also be used, which accepts an arbitrary number
of pointers to kernel objects and calls `k_object_access_grant()` on each of them. The thread being granted permission, or the object whose access is being granted, do not need to be in an initialized state. If the caller is from user mode, the caller must have permissions on both the kernel object and the target thread object.

- Supervisor threads may declare a particular kernel object to be a public object, usable by all current and future threads with the `k_object_access_all_grant()` API. You must assume that any untrusted or exploited code will then be able to access the object. Use this API with caution!

- If a thread was declared statically with `K_THREAD_DEFINE()`, then the `K_THREAD_ACCESS_GRANT()` may be used to grant that thread access to a set of kernel objects at boot time.

Once a thread has been granted access to an object, such access may be removed with the `k_object_access_revoke()` API. This API is not available to user threads, however user threads may use `k_object_release()` to relinquish their own permissions on an object.

API calls from supervisor mode to set permissions on kernel objects that are not being tracked by the kernel will be no-ops. Doing the same from user mode will result in a fatal error for the calling thread.

Objects allocated with `k_object_alloc()` implicitly grant permission on the allocated object to the calling thread.

**Initialization State**

Most operations on kernel objects will fail if the object is considered to be in an uninitialized state. The appropriate init function for the object must be performed first.

Some objects will be implicitly initialized at boot:

- Kernel objects that were declared with static initialization macros (such as `K_SEM_DEFINE` for semaphores) will be in an initialized state at build time.

- Device driver objects are considered initialized after their init function is run by the kernel early in the boot process.

If a kernel object is initialized with a private static initializer, the object must have `z_object_init()` called on it at some point by a supervisor thread, otherwise the kernel will consider the object uninitialized if accessed by a user thread. This is very uncommon, typically only for kernel objects that are embedded within some larger struct and initialized statically.

```c
struct foo {
    struct k_sem sem;
    ...
};

struct foo my_foo = {
    .sem = Z_SEM_INITIALIZER(my_foo.sem, 0, 1),
    ...
};

... z_object_init(&my_foo.sem);
...
```

**Creating New Kernel Object Types**

When implementing new kernel features or driver subsystems, it may be necessary to define some new kernel object types. There are different steps needed for creating core kernel objects and new driver subsystems.
Creating New Core Kernel Objects

- In scripts/build/gen_kobject_list.py, add the name of the struct to the kobjects list.

Instances of the new struct should now be tracked.

Creating New Driver Subsystem Kernel Objects

All driver instances are device. They are differentiated by what API struct they are set to.

- In scripts/build/gen_kobject_list.py, add the name of the API struct for the new subsystem to the subsystems list.

Driver instances of the new subsystem should now be tracked.

Configuration Options

Related configuration options:

- CONFIG_USERSPACE
- CONFIG_MAX_THREAD_BYTES

API Reference

group usermode_apis

Defines

K_THREAD_ACCESS_GRANT(name_, ...)
  Grant a static thread access to a list of kernel objects.
  For threads declared with K_THREAD_DEFINE(), grant the thread access to a set of kernel objects. These objects do not need to be in an initialized state. The permissions will be granted when the threads are initialized in the early boot sequence.
  All arguments beyond the first must be pointers to kernel objects.

Parameters

- name_ – Name of the thread, as passed to K_THREAD_DEFINE()

K_OBJ_FLAG_INITIALIZED
  Object initialized

K_OBJ_FLAG_PUBLIC
  Object is Public

K_OBJ_FLAG_ALLOC
  Object allocated

K_OBJ_FLAG_DRIVER
  Driver Object
Functions

void k_object_access_grant(const void *object, struct k_thread *thread)
Grant a thread access to a kernel object

The thread will be granted access to the object if the caller is from supervisor mode, or the
caller is from user mode AND has permissions on both the object and the thread whose access
is being granted.

Parameters
• object – Address of kernel object
• thread – Thread to grant access to the object

void k_object_access_revoke(const void *object, struct k_thread *thread)
Revoke a thread’s access to a kernel object

The thread will lose access to the object if the caller is from supervisor mode, or the caller is
from user mode AND has permissions on both the object and the thread whose access is being
revoked.

Parameters
• object – Address of kernel object
• thread – Thread to remove access to the object

void k_object_release(const void *object)
Release an object.

Allows user threads to drop their own permission on an object Their permissions are automat-
ically cleared when a thread terminates.

Parameters
• object – The object to be released

void k_object_access_all_grant(const void *object)
Grant all present and future threads access to an object

If the caller is from supervisor mode, or the caller is from user mode and have sufficient
permissions on the object, then that object will have permissions granted to it for all current
and future threads running in the system, effectively becoming a public kernel object.

Use of this API should be avoided on systems that are running untrusted code as it is possible
for such code to derive the addresses of kernel objects and perform unwanted operations on
them.

It is not possible to revoke permissions on public objects; once public, any thread may use it.

Parameters
• object – Address of kernel object

static inline void k_object_free(void *obj)
Free an object.

Parameters
• obj –

3.3.4 System Calls

User threads run with a reduced set of privileges than supervisor threads: certain CPU instructions may
not be used, and they have access to only a limited part of the memory map. System calls (may) allow
user threads to perform operations not directly available to them.
When defining system calls, it is very important to ensure that access to the API's private data is done exclusively through system call interfaces. Private kernel data should never be made available to user mode threads directly. For example, the \texttt{k\_queue} APIs were intentionally not made available as they store bookkeeping information about the queue directly in the queue buffers which are visible from user mode.

APIs that allow the user to register callback functions that run in supervisor mode should never be exposed as system calls. Reserve these for supervisor-mode access only.

This section describes how to declare new system calls and discusses a few implementation details relevant to them.

**Components**

All system calls have the following components:

- A \texttt{C prototype} prefixed with \texttt{\_\_syscall} for the API. It will be declared in some header under \texttt{include} or in another \texttt{SYSCALL\_INCLUDE\_DIRS} directory. This prototype is never implemented manually, instead it gets created by the \texttt{scripts\_build\_gen\_syscalls.py} script. What gets generated is an inline function which either calls the implementation function directly (if called from supervisor mode) or goes through privilege elevation and validation steps (if called from user mode).

- An \texttt{implementation function}, which is the real implementation of the system call. The implementation function may assume that all parameters passed in have been validated if it was invoked from user mode.

- A \texttt{verification function}, which wraps the implementation function and does validation of all the arguments passed in.

- An \texttt{unmarshalling function}, which is an automatically generated handler that must be included by user source code.

**C Prototype**

The \texttt{C prototype} represents how the API is invoked from either user or supervisor mode. For example, to initialize a semaphore:

\begin{verbatim}
\_\_syscall void k\_sem\_init(struct k\_sem \*sem, unsigned int initial\_count, 
unsigned int limit);
\end{verbatim}

The \texttt{\_\_syscall} attribute is very special. To the C compiler, it simply expands to `static inline`. However to the post-build \texttt{scripts\_build\_parse\_syscalls.py} script, it indicates that this API is a system call. The \texttt{scripts\_build\_parse\_syscalls.py} script does some parsing of the function prototype, to determine the data types of its return value and arguments, and has some limitations:

- Array arguments must be passed in as pointers, not arrays. For example, \texttt{int foo[]} or \texttt{int foo[12]} is not allowed, but should instead be expressed as \texttt{int \*foo}.

- Function pointers horribly confuse the limited parser. The workaround is to typedef them first, and then express in the argument list in terms of that typedef.

- \texttt{\_\_syscall} must be the first thing in the prototype.

The preprocessor is intentionally not used when determining the set of system calls to generate. However, any generated system calls that don't actually have a verification function defined (because the related feature is not enabled in the kernel configuration) will instead point to a special verification for unimplemented system calls. Data type definitions for APIs should not have conditional visibility to the compiler.

Any header file that declares system calls must include a special generated header at the very bottom of the header file. This header follows the naming convention \texttt{syscalls/<name of header file>}. For example, at the bottom of \texttt{include/sensor.h}:
C prototype functions must be declared in one of the directories listed in the CMake variable SYSCALL_INCLUDE_DIRS. This list always contains ${ZEPHYR_BASE}/include, but will also contain APPLICATION_SOURCE_DIR when CONFIG_APPLICATION_DEFINED_SYSCALL is set, or ${ZEPHYR_BASE}/subsys/testsuite/ztest/include when CONFIG_ZTEST is set. Additional paths can be added to the list through the CMake command line or in CMake code that is run before ${ZEPHYR_BASE}/cmake/app/boilerplate.cmake is run.

Invocation Context  Source code that uses system call APIs can be made more efficient if it is known that all the code inside a particular C file runs exclusively in user mode, or exclusively in supervisor mode. The system will look for the definition of macros __ZEPHYR_SUPERVISOR__ or __ZEPHYR_USER__, typically these will be added to the compiler flags in the build system for the related files.

- If CONFIG_USERSPACE is not enabled, all APIs just directly call the implementation function.
- Otherwise, the default case is to make a runtime check to see if the processor is currently running in user mode, and either make the system call or directly call the implementation function as appropriate.
- If __ZEPHYR_SUPERVISOR__ is defined, then it is assumed that all the code runs in supervisor mode and all APIs just directly call the implementation function. If the code was actually running in user mode, there will be a CPU exception as soon as it tries to do something it isn't allowed to do.
- If __ZEPHYR_USER__ is defined, then it is assumed that all the code runs in user mode and system calls are unconditionally made.

Implementation Details  Declaring an API with __syscall causes some code to be generated in C and header files by the scripts/build/gen_syscalls.py script, all of which can be found in the project out directory under include/generated/:

- The system call is added to the enumerated type of system call IDs, which is expressed in include/generated/syscall_list.h. It is the name of the API in uppercase, prefixed with K_SYSCALL_.
- An entry for the system call is created in the dispatch table _k_syscall_table, expressed in include/generated/syscall_dispatch.c
- A weak verification function is declared, which is just an alias of the ‘unimplemented system call’ verifier. This is necessary since the real verification function may or may not be built depending on the kernel configuration. For example, if a user thread makes a sensor subsystem API call, but the sensor subsystem is not enabled, the weak verifier will be invoked instead.
- An unmarshalling function is defined in include/generated/<name>_mrsh.c

The body of the API is created in the generated system header. Using the example of k_sem_init(), this API is declared in include/kernel.h. At the bottom of include/kernel.h is:

```c
#include <syscalls/kernel.h>

Inside this header is the body of k_sem_init():
```

```c
static inline void k_sem_init(struct k_sem * sem, unsigned int initial_count, unsigned int limit) {

#define CONFIG_USERSPACE

    if (z_syscall_trap()) {
        arch_syscall_invoke3(*(uintptr_t *)&sem, *(uintptr_t *)&initial_count,
            *(uintptr_t *)&limit, K_SYSCALL_K_SEM_INIT);
        return;
    }

    (continues on next page)
```
This generates an inline function that takes three arguments with void return value. Depending on context it will either directly call the implementation function or go through a system call elevation. A prototype for the implementation function is also automatically generated.

The final layer is the invocation of the system call itself. All architectures implementing system calls must implement the seven inline functions _arch_syscall_invoke0() through _arch_syscall_invoke6(). These functions marshal arguments into designated CPU registers and perform the necessary privilege elevation. Parameters of API inline function, before being passed as arguments to system call, are C casted to uintptr_t which matches size of register. Exception to above is passing 64-bit parameters on 32-bit systems, in which case 64-bit parameters are split into lower and higher part and passed as two consecutive arguments. There is always a uintptr_t type return value, which may be neglected if not needed.

Fig. 3.3: System Call execution flow

Some system calls may have more than six arguments, but number of arguments passed via registers is limited to six for all architectures. Additional arguments will need to be passed in an array in the source memory space, which needs to be treated as untrusted memory in the verification function. This code (packing, unpacking and validation) is generated automatically as needed in the stub above and in the unmarshalling function.

System calls return uintptr_t type value that is C casted, by wrapper, to a return type of API prototype declaration. This means that 64-bit value may not be directly returned, from a system call to its wrapper, on 32-bit systems. To solve the problem the automatically generated wrapper function defines 64-bit intermediate variable, which is considered untrusted buffer, on its stack and passes pointer to that variable to the system call, as a final argument. Upon return from the system call the value written to that buffer will be returned by the wrapper function. The problem does not exist on 64-bit systems which are able to return 64-bit values directly.

Implementation Function

The implementation function is what actually does the work for the API. Zephyr normally does little to no error checking of arguments, or does this kind of checking with assertions. When writing the implementation function, validation of any parameters is optional and should be done with assertions.

All implementation functions must follow the naming convention, which is the name of the API prefixed with z_impl_. Implementation functions may be declared in the same header as the API as a static inline
function or declared in some C file. There is no prototype needed for implementation functions, these are automatically generated.

Verification Function

The verification function runs on the kernel side when a user thread makes a system call. When the user thread makes a software interrupt to elevate to supervisor mode, the common system call entry point uses the system call ID provided by the user to look up the appropriate unmarshalling function for that system call and jump into it. This in turn calls the verification function.

Verification and unmarshalling functions only run when system call APIs are invoked from user mode. If an API is invoked from supervisor mode, the implementation is simply called and there is no software trap.

The purpose of the verification function is to validate all the arguments passed in. This includes:

- Any kernel object pointers provided. For example, the semaphore APIs must ensure that the semaphore object passed in is a valid semaphore and that the calling thread has permission on it.
- Any memory buffers passed in from user mode. Checks must be made that the calling thread has read or write permissions on the provided buffer.
- Any other arguments that have a limited range of valid values.

Verification functions involve a great deal of boilerplate code which has been made simpler by some macros in include/zephyr/syscall_handler.h. Verification functions should be declared using these macros.

Argument Validation  Several macros exist to validate arguments:

- Z_SYSCALL_OBJ() Checks a memory address to assert that it is a valid kernel object of the expected type, that the calling thread has permissions on it, and that the object is initialized.
- Z_SYSCALL_OBJ_INIT() is the same as Z_SYSCALL_OBJ(), except that the provided object may be uninitialized. This is useful for verifiers of object init functions.
- Z_SYSCALL_OBJ_NEVER_INIT() is the same as Z_SYSCALL_OBJ(), except that the provided object must be uninitialized. This is not used very often, currently only for k_thread_create().
- Z_SYSCALL_MEMORY_READ() validates a memory buffer of a particular size. The calling thread must have read permissions on the entire buffer.
- Z_SYSCALL_MEMORY_WRITE() is the same as Z_SYSCALL_MEMORY_READ() but the calling thread must additionally have write permissions.
- Z_SYSCALL_MEMORY_ARRAY_READ() validates an array whose total size is expressed as separate arguments for the number of elements and the element size. This macro correctly accounts for multiplication overflow when computing the total size. The calling thread must have read permissions on the total size.
- Z_SYSCALL_MEMORY_ARRAY_WRITE() is the same as Z_SYSCALL_MEMORY_ARRAY_READ() but the calling thread must additionally have write permissions.
- Z_SYSCALL_VERIFY_MSG() does a runtime check of some boolean expression which must evaluate to true otherwise the check will fail. A variant Z_SYSCALL_VERIFY exists which does not take a message parameter, instead printing the expression tested if it fails. The latter should only be used for the most obvious of tests.
- Z_SYSCALL_DRIVER_OP() checks at runtime if a driver instance is capable of performing a particular operation. While this macro can be used by itself, it's mostly a building block for macros that are automatically generated for every driver subsystem. For instance, to validate the GPIO driver, one could use the Z_SYSCALL_DRIVER_GPIO() macro.
• Z_SYSCALL_SPECIFIC_DRIVER() is a runtime check to verify that a provided pointer is a valid instance of a specific device driver, that the calling thread has permissions on it, and that the driver has been initialized. It does this by checking the API structure pointer that is stored within the driver instance and ensuring that it matches the provided value, which should be the address of the specific driver's API structure.

If any check fails, the macros will return a nonzero value. The macro Z_OOPS() can be used to induce a kernel oops which will kill the calling thread. This is done instead of returning some error condition to keep the APIs the same when calling from supervisor mode.

Verifier Definition All system calls are dispatched to a verifier function with a prefixed z_vrfy_ name based on the system call. They have exactly the same return type and argument types as the wrapped system call. Their job is to execute the system call (generally by calling the implementation function) after having validated all arguments.

The verifier is itself invoked by an automatically generated unmarshaller function which takes care of unpacking the register arguments from the architecture layer and casting them to the correct type. This is defined in a header file that must be included from user code, generally somewhere after the definition of the verifier in a translation unit (so that it can be inlined).

For example:

```c
static int z_vrfy_k_sem_take(struct k_sem *sem, int32_t timeout)
{
    Z_OOPS(Z_SYSCALL_OBJ(sem, K_OBJ_SEM));
    return z_impl_k_sem_take(sem, timeout);
}
#include <syscalls/k_sem_take_mrsh.c>
```

Verification Memory Access Policies Parameters passed to system calls by reference require special handling, because the value of these parameters can be changed at any time by any user thread that has access to the memory that parameter points to. If the kernel makes any logical decisions based on the contents of this memory, this can open up the kernel to attacks even if checking is done. This is a class of exploits known as TOCTOU (Time Of Check to Time Of Use).

The proper procedure to mitigate these attacks is to make a copies in the verification function, and only perform parameter checks on the copies, which user threads will never have access to. The implementation functions get passed the copy and not the original data sent by the user. The z_user_to_copy() and z_user_from_copy() APIs exist for this purpose.

There is one exception in place, with respect to large data buffers which are only used to provide a memory area that is either only written to, or whose contents are never used for any validation or control flow. Further discussion of this later in this section.

As a first example, consider a parameter which is used as an output parameter for some integral value:

```c
int z_vrfy_some_syscall(int *out_param)
{
    int local_out_param;
    int ret;

    ret = z_impl_some_syscall(&local_out_param);
    Z_OOPS(z_user_to_copy(out_param, &local_out_param, sizeof(*out_param)));
    return ret;
}
```

Here we have allocated local_out_param on the stack, passed its address to the implementation function, and then used z_user_to_copy() to fill in the memory passed in by the caller.

It might be tempting to do something more concise:

```c
int z_vrfy_some_syscall(int *out_param)
{
    ret = z_impl_some_syscall(out_param);
    Z_OOPS(z_user_to_copy(out_param, sizeof(*out_param)));
    return ret;
}
```
int z_vrfy_some_syscall(int *out_param)
{
    Z_OOPS(Z_SYSCALL_MEMORY_WRITE(out_param, sizeof(*out_param)));
    return z_impl_some_syscall(out_param);
}

However, this is unsafe if the implementation ever does any reads to this memory as part of its logic. For example, it could be used to store some counter value, and this could be meddled with by user threads that have access to its memory. It is by far safest for small integral values to do the copying as shown in the first example.

Some parameters may be input/output. For instance, it’s not uncommon to see APIs which pass in a pointer to some size_t which is a maximum allowable size, which is then updated by the implementation to reflect the actual number of bytes processed. This too should use a stack copy:

int z_vrfy_in_out_syscall(size_t *size_ptr)
{
    size_t size;
    int ret;
    Z_OOPS(z_user_from_copy(&size, size_ptr, sizeof(size));
    ret = z_impl_in_out_syscall(&size);
    Z_OOPS(z_user_to_copy(size_ptr, &size, sizeof(size));
    return ret;
}

Many system calls pass in structures or even linked data structures. All should be copied. Typically this is done by allocating copies on the stack:

struct bar {
    ...
};

struct foo {
    ...
    struct bar *bar_left;
    struct bar *bar_right;
};

int z_vrfy_must_alloc(struct foo *foo)
{
    int ret;
    struct foo foo_copy;
    struct bar bar_right_copy;
    struct bar bar_left_copy;
    Z_OOPS(z_user_from_copy(&foo_copy, foo, sizeof(*foo)));
    Z_OOPS(z_user_from_copy(&bar_right_copy, foo_copy.bar_right, sizeof(struct bar)));
    foo_copy.bar_right = &bar_right_copy;
    Z_OOPS(z_user_from_copy(&bar_left_copy, foo_copy.bar_left, sizeof(struct bar)));
    foo_copy.bar_left = &bar_left_copy;
    return z_impl_must_alloc(&foo_copy);
}

In some cases the amount of data isn’t known at compile time or may be too large to allocate on the stack. In this scenario, it may be necessary to draw memory from the caller’s resource pool via
z_thread_malloc(). This should always be considered last resort. Functional safety programming
guidelines heavily discourage usage of heap and the fact that a resource pool is used must be clearly
documented. Any issues with allocation must be reported, to a caller, with returning the -ENOMEM. The
Z_OOPS() should never be used to verify if resource allocation has been successful.

```c
struct bar {
    ...
};

struct foo {
    size_t count;
    struct bar *bar_list; /* array of struct bar of size count */
};

int z_vrfy_must_alloc(struct foo *foo)
{
    int ret;
    struct foo foo_copy;
    struct bar *bar_list_copy;
    size_t bar_list_bytes;

    /* Safely copy foo into foo_copy */
    Z_OOPS(z_user_from_copy(&foo_copy, foo, sizeof(*foo)));

    /* Bounds check the count member, in the copy we made */
    if (foo_copy.count > 32) {
        return -EINVAL;
    }

    /* Allocate RAM for the bar_list, replace the pointer in
    * foo_copy */
    bar_list_bytes = foo_copy.count * sizeof(struct_bar);
    bar_list_copy = z_thread_malloc(bar_list_bytes);
    if (bar_list_copy == NULL) {
        return -ENOMEM;
    }
    Z_OOPS(z_user_from_copy(bar_list_copy, foo_copy.bar_list,
                        bar_list_bytes));
    foo_copy.bar_list = bar_list_copy;

    ret = z_impl_must_alloc(&foo_copy);

    /* All done with the memory, free it and return */
    k_free(foo_copy.bar_list_copy);
    return ret;
}
```

Finally, we must consider large data buffers. These represent areas of user memory which either have
data copied out of, or copied into. It is permitted to pass these pointers to the implementation function
directly. The caller's access to the buffer still must be validated with Z_SYSCALL_MEMORY APIs. The
following constraints need to be met:

- If the buffer is used by the implementation function to write data, such as data captured from some
  MMIO region, the implementation function must only write this data, and never read it.
- If the buffer is used by the implementation function to read data, such as a block of memory to
  write to some hardware destination, this data must be read without any processing. No conditional
  logic can be implemented due to the data buffer's contents. If such logic is required a copy must
  be made.
• The buffer must only be used synchronously with the call. The implementation must not ever save the buffer address and use it asynchronously, such as when an interrupt fires.

```c
int z_vrfy_get_data_from_kernel(void *buf, size_t size)
{
    Z_OOPS(Z_SYSCALL_MEMORY_WRITE(buf, size));
    return z_impl_get_data_from_kernel(buf, size);
}
```

**Verification Return Value Policies** When verifying system calls, it’s important to note which kinds of verification failures should propagate a return value to the caller, and which should simply invoke `Z_OOPS()` which kills the calling thread. The current conventions are as follows:

1. For system calls that are defined but not compiled, invocations of these missing system calls are routed to `handler_no_syscall()` which invokes `Z_OOPS()`.

2. Any invalid access to memory found by the set of `Z_SYSCALL_MEMORY` APIs, `z_user_from_copy()`, `z_user_to_copy()` should trigger a `Z_OOPS`. This happens when the caller doesn’t have appropriate permissions on the memory buffer or some size calculation overflowed.

3. Most system calls take kernel object pointers as an argument, checked either with one of the `Z_SYSCALL_OBJ` functions, `Z_SYSCALL_DRIVER_0000`, or manually using `z_object_validate()`. These can fail for a variety of reasons: missing driver API, bad kernel object pointer, wrong kernel object type, or improper initialization state. These issues should always invoke `Z_OOPS()`.

4. Any error resulting from a failed memory heap allocation, often from invoking `z_thread_malloc()`, should propagate `-ENOMEM` to the caller.

5. General parameter checks should be done in the implementation function, in most cases using `CHECKIF()`.
   - The behavior of `CHECKIF()` depends on the kernel configuration, but if user mode is enabled, `CONFIG_RUNTIME_ERROR_CHECKS` is enforced, which guarantees that these checks will be made and a return value propagated.

6. It is totally forbidden for any kind of kernel mode callback function to be registered from user mode. APIs which simply install callbacks shall not be exposed as system calls. Some driver subsystem APIs may take optional function callback pointers. User mode verification functions for these APIs must enforce that these are NULL and should invoke `Z_OOPS()` if not.

7. Some parameter checks are enforced only from user mode. These should be checked in the verification function and propagate a return value to the caller if possible.

There are some known exceptions to these policies currently in Zephyr:

- `k_thread_join()` and `k_thread_abort()` are no-ops if the thread object isn’t initialized. This is because for threads, the initialization bit pulls double-duty to indicate whether a thread is running, cleared upon exit. See #23030.
- `k_thread_create()` invokes `Z_OOPS()` for parameter checks, due to a great deal of existing code ignoring the return value. This will also be addressed by #23030.
- `k_thread_abort()` invokes `Z_OOPS()` if an essential thread is aborted, as the function has no return value.
- Various system calls related to logging invoke `Z_OOPS()` when bad parameters are passed in as they do not propagate errors.

**Configuration Options**

Related configuration options:

- `CONFIG_USERSPACE`
APIs

Helper macros for creating system call verification functions are provided in `include/zephyr/syscall_handler.h`:

- `Z_SYSCALL_OBJ()`
- `Z_SYSCALL_OBJ_INIT()`
- `Z_SYSCALL_OBJ_NEVER_INIT()`
- `Z_OOPS()`
- `Z_SYSCALL_MEMORY_READ()`
- `Z_SYSCALL_MEMORY_WRITE()`
- `Z_SYSCALL_MEMORY_ARRAY_READ()`
- `Z_SYSCALL_MEMORY_ARRAY_WRITE()`
- `Z_SYSCALL_VERIFY_MSG()`
- `Z_SYSCALL_VERIFY`

Functions for invoking system calls are defined in `include/zephyr/syscall.h`:

- `_arch_syscall_invoke0()`
- `_arch_syscall_invoke1()`
- `_arch_syscall_invoke2()`
- `_arch_syscall_invoke3()`
- `_arch_syscall_invoke4()`
- `_arch_syscall_invoke5()`
- `_arch_syscall_invoke6()`

3.3.5 MPU Stack Objects

Thread Stack Creation

Thread stacks are declared statically with `K_THREAD_STACK_DEFINE()` or embedded within structures using `K_THREAD_STACK_MEMBER()`.

For architectures which utilize memory protection unit (MPU) hardware, stacks are physically contiguous allocations. This contiguous allocation has implications for the placement of stacks in memory, as well as the implementation of other features such as stack protection and userspace. The implications for placement are directly attributed to the alignment requirements for MPU regions. This is discussed in the memory placement section below.

Stack Guards

Stack protection mechanisms require hardware support that can restrict access to memory. Memory protection units can provide this kind of support. The MPU provides a fixed number of regions. Each region contains information about the start, end, size, and access attributes to be enforced on that particular region.

Stack guards are implemented by using a single MPU region and setting the attributes for that region to not allow write access. If invalid accesses occur, a fault ensues. The stack guard is defined at the bottom (the lowest address) of the stack.
Memory Placement

During stack creation, a set of constraints are enforced on the allocation of memory. These constraints include determining the alignment of the stack and the correct sizing of the stack. During linking of the binary, these constraints are used to place the stacks properly.

The main source of the memory constraints is the MPU design for the SoC. The MPU design may require specific constraints on the region definition. These can include alignment of beginning and end addresses, sizes of allocations, or even interactions between overlapping regions.

Some MPUs require that each region be aligned to a power of two. These SoCs will have CONFIG_MPU.Requires.Power.Of.Two.Alignment defined. This means that a 1500 byte stack should be aligned to a 2kB boundary and the stack size should also be adjusted to 2kB to ensure that nothing else is placed in the remainder of the region. SoCs which include the unmodified ARM v7m MPU will have these constraints.

Some ARM MPUs use start and end addresses to define MPU regions and both the start and end addresses require 32 byte alignment. An example of this kind of MPU is found in the NXP FRDM K64F.

MPUs may have a region priority mechanisms that use the highest priority region that covers the memory access to determine the enforcement policy. Others may logically OR regions to determine enforcement policy.

Size and alignment constraints may result in stack allocations being larger than the requested size. Region priority mechanisms may result in some added complexity when implementing stack guards.

3.3.6 MPU Backed Userspace

The MPU backed userspace implementation requires the creation of a secondary set of stacks. These stacks exist in a 1:1 relationship with each thread stack defined in the system. The privileged stacks are created as a part of the build process.

A post-build script scripts/build/gen_kobject_list.py scans the generated ELF file and finds all of the thread stack objects. A set of privileged stacks, a lookup table, and a set of helper functions are created and added to the image.

During the process of dropping a thread to user mode, the privileged stack information is filled in and later used by the swap and system call infrastructure to configure the MPU regions properly for the thread stack and guard (if applicable).

During system calls, the user mode thread’s access to the system call and the passed-in parameters are all validated. The user mode thread is then elevated to privileged mode, the stack is switched to use the privileged stack, and the call is made to the specified kernel API. On return from the kernel API, the thread is set back to user mode and the stack is restored to the user stack.

3.4 Memory Management

The following contains various topics regarding memory management.

3.4.1 Memory Heaps

Zephyr provides a collection of utilities that allow threads to dynamically allocate memory.

Synchronized Heap Allocator

Creating a Heap The simplest way to define a heap is statically, with the K_HEAP_DEFINE macro. This creates a static k_heap variable with a given name that manages a memory region of the specified size.
Heaps can also be created to manage arbitrary regions of application-controlled memory using `k_heap_init()`.

**Allocating Memory** Memory can be allocated from a heap using `k_heap_alloc()`, passing it the address of the heap object and the number of bytes desired. This function similarly to standard C `malloc()`, returning a NULL pointer on an allocation failure.

The heap supports blocking operation, allowing threads to go to sleep until memory is available. The final argument is a `k_timeout_t` timeout value indicating how long the thread may sleep before returning, or else one of the constant timeout values `K_NO_WAIT` or `K_FOREVER`.

**Releasing Memory** Memory allocated with `k_heap_alloc()` must be released using `k_heap_free()`. Similar to standard C `free()`, the pointer provided must be either a NULL value or a pointer previously returned by `k_heap_alloc()` for the same heap. Freeing a NULL value is defined to have no effect.

**Low Level Heap Allocator**

The underlying implementation of the `k_heap` abstraction is provided a data structure named `sys_heap`. This implements exactly the same allocation semantics, but provides no kernel synchronization tools. It is available for applications that want to manage their own blocks of memory in contexts (for example, userspace) where synchronization is unavailable or more complicated. Unlike `k_heap`, all calls to any `sys_heap` functions on a single heap must be serialized by the caller. Simultaneous use from separate threads is disallowed.

**Implementation** Internally, the `sys_heap` memory block is partitioned into “chunks” of 8 bytes. All allocations are made out of a contiguous region of chunks. The first chunk of every allocation or unused block is prefixed by a chunk header that stores the length of the chunk, the length of the next lower (“left”) chunk in physical memory, a bit indicating whether the chunk is in use, and chunk-indexed link pointers to the previous and next chunk in a “free list” to which unused chunks are added.

The heap code takes reasonable care to avoid fragmentation. Free block lists are stored in “buckets” by their size, each bucket storing blocks within one power of two (i.e., a bucket for blocks of 3-4 chunks, another for 5-8, 9-16, etc...) this allows new allocations to be made from the smallest/most-fragmented blocks available. Also, as allocations are freed and added to the heap, they are automatically combined with adjacent free blocks to prevent fragmentation.

All metadata is stored at the beginning of the contiguous block of heap memory, including the variable-length list of bucket list heads (which depend on heap size). The only external memory required is the `sys_heap` structure itself.

The `sys_heap` functions are unsynchronized. Care must be taken by any users to prevent concurrent access. Only one context may be inside one of the API functions at a time.

The heap code takes care to present high performance and reliable latency. All `sys_heap` API functions are guaranteed to complete within constant time. On typical architectures, they will all complete within 1-200 cycles. One complexity is that the search of the minimum bucket size for an allocation (the set of free blocks that “might fit”) has a compile-time upper bound of iterations to prevent unbounded list searches, at the expense of some fragmentation resistance. This `CONFIG_SYS_HEAP_ALLOC_LOOPS` value may be chosen by the user at build time, and defaults to a value of 3.

**Multi-Heap Wrapper Utility**

The `sys_heap` utility requires that all managed memory be in a single contiguous block. It is common for complicated microcontroller applications to have more complicated memory setups that they still want to manage dynamically as a “heap”. For example, the memory might exist as separate discontiguous...
regions, different areas may have different cache, performance or power behavior, peripheral devices may only be able to perform DMA to certain regions, etc...

For those situations, Zephyr provides a `sys_multi_heap` utility. Effectively this is a simple wrapper around a set of one or more `sys_heap` objects. It should be initialized after its child heaps via `sys_multi_heap_init()`, after which each heap can be added to the managed set via `sys_multi_heap_add_heap()`. No destruction utility is provided; just as for `sys_heap`, applications that want to destroy a multi heap should simply ensure all allocated blocks are freed (or at least will never be used again) and repurpose the underlying memory for another usage.

It has a single pair of allocation entry points, `sys_multi_heap_alloc()` and `sys_multi_heap_aligned_alloc()`. These behave identically to the `sys_heap` functions with similar names, except that they also accept an opaque “configuration” parameter. This pointer is uninspected by the multi heap code itself; instead it is passed to a callback function provided at initialization time. This application-provided callback is responsible for doing the underlying allocation from one of the managed heaps, and may use the configuration parameter in any way it likes to make that decision.

When unused, a multi heap may be freed via `sys_multi_heap_free()`. The application does not need to pass a configuration parameter. Memory allocated from any of the managed `sys_heap` objects may be freed with in the same way.

**System Heap**

The system heap is a predefined memory allocator that allows threads to dynamically allocate memory from a common memory region in a `malloc()`-like manner.

Only a single system heap is defined. Unlike other heaps or memory pools, the system heap cannot be directly referenced using its memory address.

The size of the system heap is configurable to arbitrary sizes, subject to space availability.

A thread can dynamically allocate a chunk of heap memory by calling `k_malloc()`. The address of the allocated chunk is guaranteed to be aligned on a multiple of pointer sizes. If a suitable chunk of heap memory cannot be found `NULL` is returned.

When the thread is finished with a chunk of heap memory it can release the chunk back to the system heap by calling `k_free()`.

**Defining the Heap Memory Pool** The size of the heap memory pool is specified using the `CONFIG_HEAP_MEM_POOL_SIZE` configuration option.

By default, the heap memory pool size is zero bytes. This value instructs the kernel not to define the heap memory pool object. The maximum size is limited by the amount of available memory in the system. The project build will fail in the link stage if the size specified can not be supported.

**Allocating Memory** A chunk of heap memory is allocated by calling `k_malloc()`.

The following code allocates a 200 byte chunk of heap memory, then fills it with zeros. A warning is issued if a suitable chunk is not obtained.

```c
char *mem_ptr;

mem_ptr = k_malloc(200);
if (mem_ptr != NULL) {
    memset(mem_ptr, 0, 200);
    ...
} else {
    printf("Memory not allocated");
}
```
Releasing Memory  A chunk of heap memory is released by calling \texttt{k.free()}. The following code allocates a 75 byte chunk of memory, then releases it once it is no longer needed.

\begin{verbatim}
char *mem_ptr;
mem_ptr = k_malloc(75);
... /* use memory block */
k_free(mem_ptr);
\end{verbatim}

Suggested Uses  Use the heap memory pool to dynamically allocate memory in a \texttt{malloc()}-like manner.

Configuration Options  Related configuration options:

- \texttt{CONFIG_HEAP_MEM_POOL_SIZE}

API Reference

\texttt{group heap_apis}

Defines

\texttt{K_HEAP_DEFINE(name, bytes)}

Define a static \texttt{k_heap}. This macro defines and initializes a static memory region and \texttt{k_heap} of the requested size. After kernel start, &name can be used as if \texttt{k_heap_init()} had been called.

Note that this macro enforces a minimum size on the memory region to accommodate metadata requirements. Very small heaps will be padded to fit.

Parameters

- \texttt{name} – Symbol name for the struct \texttt{k_heap} object
- \texttt{bytes} – Size of memory region, in bytes

\texttt{K_HEAP_DEFINE_NOCACHE(name, bytes)}

Define a static \texttt{k_heap} in uncached memory.

This macro defines and initializes a static memory region and \texttt{k_heap} of the requested size in uncached memory. After kernel start, &name can be used as if \texttt{k_heap_init()} had been called.

Note that this macro enforces a minimum size on the memory region to accommodate metadata requirements. Very small heaps will be padded to fit.

Parameters

- \texttt{name} – Symbol name for the struct \texttt{k_heap} object
- \texttt{bytes} – Size of memory region, in bytes

Functions

\texttt{void k_heap_init(struct k_heap *h, void *mem, size_t bytes)}

Initialize a \texttt{k_heap}.

This constructs a synchronized \texttt{k_heap} object over a memory region specified by the user. Note that while any alignment and size can be passed as valid parameters, internal alignment
restrictions inside the inner sys_heap mean that not all bytes may be usable as allocated memory.

Parameters
• h – Heap struct to initialize
• mem – Pointer to memory.
• bytes – Size of memory region, in bytes

`void *k_heap_aligned_alloc(struct k_heap *h, size_t align, size_t bytes, k_timeout_t timeout)`
Allocate aligned memory from a `k_heap`.

Behaves in all ways like `k_heap_alloc()`, except that the returned memory (if available) will have a starting address in memory which is a multiple of the specified power-of-two alignment value in bytes. The resulting memory can be returned to the heap using `k_heap_free()`.

Function properties (list may not be complete)

**isr-ok**

Note: `timeout` must be set to `K_NO_WAIT` if called from ISR.

Note: When `CONFIG_MULTITHREADING=n` any `timeout` is treated as `K_NO_WAIT`.

Parameters
• h – Heap from which to allocate
• align – Alignment in bytes, must be a power of two
• bytes – Number of bytes requested
• timeout – How long to wait, or `K_NO_WAIT`

Returns
Pointer to memory the caller can now use

`void *k_heap_alloc(struct k_heap *h, size_t bytes, k_timeout_t timeout)`
Allocate memory from a `k_heap`.

Allocates and returns a memory buffer from the memory region owned by the heap. If no memory is available immediately, the call will block for the specified timeout (constructed via the standard timeout API, or `K_NO_WAIT` or `K_FOREVER`) waiting for memory to be freed. If the allocation cannot be performed by the expiration of the timeout, NULL will be returned. Allocated memory is aligned on a multiple of pointer sizes.

Function properties (list may not be complete)

**isr-ok**

Note: `timeout` must be set to `K_NO_WAIT` if called from ISR.

Note: When `CONFIG_MULTITHREADING=n` any `timeout` is treated as `K_NO_WAIT`.

Parameters
• **h** – Heap from which to allocate

• **bytes** – Desired size of block to allocate

• **timeout** – How long to wait, or K_NO_WAIT

**Returns**
A pointer to valid heap memory, or NULL.

```c
void k_heap_free(struct k_heap *h, void *mem)
```
Free memory allocated by `k_heap_alloc()`

Returns the specified memory block, which must have been returned from `k_heap_alloc()`, to the heap for use by other callers. Passing a NULL block is legal, and has no effect.

**Parameters**

• **h** – Heap to which to return the memory

• **mem** – A valid memory block, or NULL

```c
void *k_aligned_alloc(size_t align, size_t size)
```
Allocate memory from the heap with a specified alignment.

This routine provides semantics similar to `aligned_alloc();` memory is allocated from the heap with a specified alignment. However, one minor difference is that `k_aligned_alloc()` accepts any non-zero `size`, whereas `aligned_alloc()` only accepts a `size` that is an integral multiple of `align`.

Above, `aligned_alloc()` refers to: C11 standard (ISO/IEC 9899:2011): 7.22.3.1 The `aligned_alloc` function (p: 347-348)

**Parameters**

• **align** – Alignment of memory requested (in bytes).

• **size** – Amount of memory requested (in bytes).

**Returns**
Address of the allocated memory if successful; otherwise NULL.

```c
void *k_malloc(size_t size)
```
Allocate memory from the heap.

This routine provides traditional `malloc()` semantics. Memory is allocated from the heap memory pool. Allocated memory is aligned on a multiple of pointer sizes.

**Parameters**

• **size** – Amount of memory requested (in bytes).

**Returns**
Address of the allocated memory if successful; otherwise NULL.

```c
void k_free(void *ptr)
```
Free memory allocated from heap.

This routine provides traditional `free()` semantics. The memory being returned must have been allocated from the heap memory pool.

If `ptr` is NULL, no operation is performed.

**Parameters**

• **ptr** – Pointer to previously allocated memory.
void *k_calloc(size_t nmemb, size_t size)
Allocate memory from heap, array style.
This routine provides traditional calloc() semantics. Memory is allocated from the heap memory pool and zeroed.

Parameters
• nmemb – Number of elements in the requested array
• size – Size of each array element (in bytes).

Returns
Address of the allocated memory if successful; otherwise NULL.

struct k_heap
#include <kernel.h>

Heap listener
group heap_listener_apis

Defines

HEAP_ID_FROM_POINTER(heap_pointer)
Construct heap identifier from heap pointer.
Construct a heap identifier from a pointer to the heap object, such as sys_heap.

Parameters
• heap_pointer – Pointer to the heap object

HEAP_ID_LIBC
Libc heap identifier.
Identifier of the global libc heap.

HEAP_LISTENER_ALLOC_DEFINE(name, _heap_id, _alloc_cb)
Define heap event listener node for allocation event.
Sample usage:
void on_heap_alloc(uintptr_t heap_id, void *mem, size_t bytes)
{
    LOG_INF("Memory allocated at %p, size %ld", heap_id, mem, bytes);
}

HEAP_LISTENER_ALLOC_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_alloc);

Parameters
• name – Name of the heap event listener object
• _heap_id – Identifier of the heap to be listened
• _alloc_cb – Function to be called for allocation event
HEAP_LISTENER_FREE_DEFINE(name, _heap_id, _free_cb)
Define heap event listener node for free event.
Sample usage:

```c
void on_heap_free(uintptr_t heap_id, void *mem, size_t bytes)
{
    LOG_INF("Memory freed at %p, size %ld", heap_id, mem, bytes);
}
HEAP_LISTENER_FREE_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_free);
```

**Parameters**
- `name` – Name of the heap event listener object
- `_heap_id` – Identifier of the heap to be listened
- `_free_cb` – Function to be called for free event

HEAP_LISTENER_RESIZE_DEFINE(name, _heap_id, _resize_cb)
Define heap event listener node for resize event.
Sample usage:

```c
void on_heap_resized(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)
{
    LOG_INF("Libc heap end moved from %p to %p", old_heap_end, new_heap_end);
}
HEAP_LISTENER_RESIZE_DEFINE(my_listener, HEAP_ID_LIBC, on_heap_resized);
```

**Parameters**
- `name` – Name of the heap event listener object
- `_heap_id` – Identifier of the heap to be listened
- `_resize_cb` – Function to be called when the listened heap is resized

**Typedefs**

typedef void (*heap_listener_resize_cb_t)(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)
Callback used when heap is resized.

**Note:** Minimal C library does not emit this event.

**Param heap_id**
Identifier of heap being resized

**Param old_heap_end**
Pointer to end of heap before resize

**Param new_heap_end**
Pointer to end of heap after resize
typedef void (*heap_listener_alloc_cb_t)(uintptr_t heap_id, void *mem, size_t bytes)
Callback used when there is heap allocation.

**Note:** Heaps managed by libraries outside of code in Zephyr main code repository may not emit this event.

**Note:** The number of bytes allocated may not match exactly to the request to the allocation function. Internal mechanism of the heap may allocate more than requested.

**Param heap_id**
Heap identifier

**Param mem**
Pointer to the allocated memory

**Param bytes**
Size of allocated memory

typedef void (*heap_listener_free_cb_t)(uintptr_t heap_id, void *mem, size_t bytes)
Callback used when memory is freed from heap.

**Note:** Heaps managed by libraries outside of code in Zephyr main code repository may not emit this event.

**Note:** The number of bytes freed may not match exactly to the request to the allocation function. Internal mechanism of the heap dictates how memory is allocated or freed.

**Param heap_id**
Heap identifier

**Param mem**
Pointer to the freed memory

**Param bytes**
Size of freed memory

**Enums**

eenum heap_event_types

**Values:**

enumerator HEAP_EVT_UNKNOWN = 0

enumerator HEAP_RESIZE

enumerator HEAP_ALLOC
enumerator HEAP_FREE

enumerator HEAP_REALLOC

enumerator HEAP_MAX_EVENTS

**Functions**

```c
void heap_listener_register(struct heap_listener *listener)
```

Register heap event listener.

Add the listener to the global list of heap listeners that can be notified by different heap implementations upon certain events related to the heap usage.

**Parameters**

- `listener` – Pointer to the `heap_listener` object

```c
void heap_listener_unregister(struct heap_listener *listener)
```

Unregister heap event listener.

Remove the listener from the global list of heap listeners that can be notified by different heap implementations upon certain events related to the heap usage.

**Parameters**

- `listener` – Pointer to the `heap_listener` object

```c
void heap_listener_notify_alloc(uintptr_t heap_id, void *mem, size_t bytes)
```

Notify listeners of heap allocation event.

Notify registered heap event listeners with matching heap identifier that an allocation has been done on heap.

**Parameters**

- `heap_id` – Heap identifier
- `mem` – Pointer to the allocated memory
- `bytes` – Size of allocated memory

```c
void heap_listener_notify_free(uintptr_t heap_id, void *mem, size_t bytes)
```

Notify listeners of heap free event.

Notify registered heap event listeners with matching heap identifier that memory is freed on heap.

**Parameters**

- `heap_id` – Heap identifier
- `mem` – Pointer to the freed memory
- `bytes` – Size of freed memory

```c
void heap_listener_notify_resize(uintptr_t heap_id, void *old_heap_end, void *new_heap_end)
```

Notify listeners of heap resize event.

Notify registered heap event listeners with matching heap identifier that the heap has been resized.

**Parameters**
heap_id – Heap identifier  
old_heap_end – Address of the heap end before the change  
new_heap_end – Address of the heap end after the change

```c
struct heap_listener
    #include <heap_listener.h>

Public Members

sys_snnode_t node
    Singly linked list node

uintptr_t heap_id
    Identifier of the heap whose events are listened.  
    It can be a heap pointer, if the heap is represented as an object, or 0 in the case of the 
    global libc heap.

dtype heap_event_types event
    The heap event to be notified.

3.4.2 Shared Multi Heap

The shared multi-heap memory pool manager uses the multi-heap allocator to manage a set of reserved 
memory regions with different capabilities / attributes (cacheable, non-cacheable, etc...).

All the different regions can be added at run-time to the shared multi-heap pool providing an opaque 
“attribute” value (an integer or enum value) that can be used by drivers or applications to request 
memory with certain capabilities.

This framework is commonly used as follow:

1. At boot time some platform code initialize the shared multi-heap framework using 
   `shared_multi_heap_pool_init()` and add the memory regions to the pool with 
   `shared_multi_heap_add()`, possibly gathering the needed information for the regions from the 
   DT.

2. Each memory region encoded in a `shared_multi_heap_region` structure. This structure is also 
   carrying an opaque and user-defined integer value that is used to define the region capabilities (for 
   example: cacheability, cpu affinity, etc...)

```c
    // Init the shared multi-heap pool
    shared_multi_heap_pool_init()

    // Fill the struct with the data for cacheable memory
    struct shared_multi_heap_region cacheable_r0 = {
        .addr = addr_r0,
        .size = size_r0,
        .attr = SMH_REG_ATTR_CACHEABLE,
    };

    // Add the region to the pool
    shared_multi_heap_add(&cacheable_r0, NULL);
```

(continues on next page)
// Add another cacheable region
struct shared_multi_heap_region cacheable_r1 = {
    .addr = addr_r1,
    .size = size_r1,
    .attr = SMH_REG_ATTR_CACHEABLE,
};
shared_multi_heap_add(&cacheable_r0, NULL);

// Add a non-cacheable region
struct shared_multi_heap_region non_cacheable_r2 = {
    .addr = addr_r2,
    .size = size_r2,
    .attr = SMH_REG_ATTR_NON_CACHEABLE,
};
shared_multi_heap_add(&non_cacheable_r2, NULL);

3. When a driver or application needs some dynamic memory with a certain capability, it can use
   shared_multi_heap_alloc() (or the aligned version) to request the memory by using the opaque
   parameter to select the correct set of attributes for the needed memory. The framework will take
   care of selecting the correct heap (thus memory region) to carve memory from, based on the
   opaque parameter and the runtime state of the heaps (available memory, heap state, etc...)

// Allocate 4K from cacheable memory
shared_multi_heap_alloc(SMH_REG_ATTR_CACHEABLE, 0x1000);

// Allocate 4K from non-cacheable memory
shared_multi_heap_alloc(SMH_REG_ATTR_NON_CACHEABLE, 0x1000);

Adding new attributes

The API does not enforce any attributes, but at least it defines the two most common ones:
   SMH_REG_ATTR_CACHEABLE and SMH_REG_ATTR_NON_CACHEABLE

group shared_multi_heap
    Shared Multi-Heap (SMH) interface.

    The shared multi-heap manager uses the multi-heap allocator to manage a set of memory regions
    with different capabilities / attributes (cacheable, non-cacheable, etc...).

    All the different regions can be added at run-time to the shared multi-heap pool providing an
    opaque "attribute" value (an integer or enum value) that can be used by drivers or applications to
    request memory with certain capabilities.

    This framework is commonly used as follow:

    • At boot time some platform code initialize the shared multi-heap framework using
      shared_multi_heap_pool_init and add the memory regions to the pool with
      shared_multi_heap_add, possibly gathering the needed information for the regions from the
      DT.

    • Each memory region encoded in a shared_multi_heap_region structure. This structure is also
      carrying an opaque and user-defined integer value that is used to define the region capabilities
      (for example: cacheability, cpu affinity, etc...)

3.4. Memory Management
• When a driver or application needs some dynamic memory with a certain capability, it can use
`shared_multi_heap_alloc` (or the aligned version) to request the memory by using the opaque
parameter to select the correct set of attributes for the needed memory. The framework will
take care of selecting the correct heap (thus memory region) to carve memory from, based
on the opaque parameter and the runtime state of the heaps (available memory, heap state,
etc...)}

**Defines**

`MAX_SHARED_MULTI_HEAP_ATTR`

Maximum number of standard attributes.

** Enums**

```c
enum smh_reg_attr

SMH region attributes enumeration type.

Enumeration type for some common memory region attributes.
```

**Values:**

- `SMH_REG_ATTR_CACHEABLE`
- `SMH_REG_ATTR_NON_CACHEABLE`
- `SMH_REG_ATTR_NUM`

`must be the last item`

**Functions**

```c
int shared_multi_heap_pool_init(void)

Init the pool.
```

This must be the first function to be called to initialize the shared multi-heap pool. All the
individual heaps must be added later with `shared_multi_heap_add`.

**Note:** As for the generic multi-heap allocator the expectation is that this function will be
called at soc- or board-level.

**Return values**

- `0` – on success.
- `-EALREADY` – when the pool was already inited.
- `other` – errno codes
void *shared_multi_heap_alloc(unsigned int attr, size_t bytes)
Allocate memory from the memory shared multi-heap pool.
Allocates a block of memory of the specified size in bytes and with a specified capability / attribute. The opaque attribute parameter is used by the backend to select the correct heap to allocate memory from.

Parameters
• attr – capability / attribute requested for the memory block.
• bytes – requested size of the allocation in bytes.

Return values
• ptr – a valid pointer to heap memory.
• err – NULL if no memory is available.

void *shared_multi_heap_aligned_alloc(unsigned int attr, size_t align, size_t bytes)
Allocate aligned memory from the memory shared multi-heap pool.
Allocates a block of memory of the specified size in bytes and with a specified capability / attribute. Takes an additional parameter specifying a power of two alignment in bytes.

Parameters
• attr – capability / attribute requested for the memory block.
• align – power of two alignment for the returned pointer, in bytes.
• bytes – requested size of the allocation in bytes.

Return values
• ptr – a valid pointer to heap memory.
• err – NULL if no memory is available.

void shared_multi_heap_free(void *block)
Free memory from the shared multi-heap pool.
Used to free the passed block of memory that must be the return value of a previously call to shared_multi_heap_alloc or shared_multi_heap_aligned_alloc.

Parameters
• block – block to free, must be a pointer to a block allocated by shared_multi_heap_alloc or shared_multi_heap_aligned_alloc.

int shared_multi_heap_add(struct shared_multi_heap_region *region, void *user_data)
Add an heap region to the shared multi-heap pool.
This adds a shared multi-heap region to the multi-heap pool.

Parameters
• user_data – pointer to any data for the heap.
• region – pointer to the memory region to be added.

Return values
• 0 – on success.
• -EINVAL – when the region attribute is out-of-bound.
• -ENOMEM – when there are no more heaps available.
• other – errno codes
struct shared_multi_heap_region

#include <shared_multi_heap.h> SMH region struct. This struct is carrying information about the memory region to be added in the multi-heap pool.

Public Members

unsigned int attr
Memory heap attribute

uintptr_t addr
Memory heap starting virtual address

size_t size
Memory heap size in bytes

3.4.3 Memory Slabs

A memory slab is a kernel object that allows memory blocks to be dynamically allocated from a designated memory region. All memory blocks in a memory slab have a single fixed size, allowing them to be allocated and released efficiently and avoiding memory fragmentation concerns.

- Concepts
  - Internal Operation
- Implementation
  - Defining a Memory Slab
  - Allocating a Memory Block
  - Releasing a Memory Block
- Suggested Uses
- Configuration Options
- API Reference

Concepts

Any number of memory slabs can be defined (limited only by available RAM). Each memory slab is referenced by its memory address.

A memory slab has the following key properties:

- The block size of each block, measured in bytes. It must be at least 4N bytes long, where N is greater than 0.
- The number of blocks available for allocation. It must be greater than zero.
- A buffer that provides the memory for the memory slab's blocks. It must be at least “block size” times “number of blocks” bytes long.
The memory slab’s buffer must be aligned to an N-byte boundary, where N is a power of 2 larger than 2
(i.e. 4, 8, 16, ...). To ensure that all memory blocks in the buffer are similarly aligned to this boundary,
the block size must also be a multiple of N.

A memory slab must be initialized before it can be used. This marks all of its blocks as unused.

A thread that needs to use a memory block simply allocates it from a memory slab. When the thread
finishes with a memory block, it must release the block back to the memory slab so the block can be
reused.

If all the blocks are currently in use, a thread can optionally wait for one to become available. Any
number of threads may wait on an empty memory slab simultaneously; when a memory block becomes
available, it is given to the highest-priority thread that has waited the longest.

Unlike a heap, more than one memory slab can be defined, if needed. This allows for a memory slab with
smaller blocks and others with larger-sized blocks. Alternatively, a memory pool object may be used.

**Internal Operation**  A memory slab’s buffer is an array of fixed-size blocks, with no wasted space
between the blocks.

The memory slab keeps track of unallocated blocks using a linked list; the first 4 bytes of each unused
block provide the necessary linkage.

**Implementation**

**Defining a Memory Slab**  A memory slab is defined using a variable of type `k_mem_slab`. It must then
be initialized by calling `k_mem_slab_init()`.

The following code defines and initializes a memory slab that has 6 blocks that are 400 bytes long, each
of which is aligned to a 4-byte boundary.

```c
struct k_mem_slab my_slab;
char __aligned(4) my_slab_buffer[6 * 400];
k_mem_slab_init(&my_slab, my_slab_buffer, 400, 6);
```

Alternatively, a memory slab can be defined and initialized at compile time by calling
`K_MEM_SLAB_DEFINE`.

The following code has the same effect as the code segment above. Observe that the macro defines both
the memory slab and its buffer.

```c
K_MEM_SLAB_DEFINE(my_slab, 400, 6, 4);
```

Similarly, you can define a memory slab in private scope:

```c
K_MEM_SLAB_DEFINE_STATIC(my_slab, 400, 6, 4);
```

**Allocating a Memory Block**  A memory block is allocated by calling `k_mem_slab_alloc()`.

The following code builds on the example above, and waits up to 100 milliseconds for a memory block
to become available, then fills it with zeroes. A warning is printed if a suitable block is not obtained.

```c
char *block_ptr;
if (k_mem_slab_alloc(&my_slab, &block_ptr, 100) == 0)) {
    memset(block_ptr, 0, 400);
    ...
} else {
```
Releasing a Memory Block

A memory block is released by calling `k_mem_slab_free()`.

The following code builds on the example above, and allocates a memory block, then releases it once it is no longer needed.

```c
char *block_ptr;

k_mem_slab_alloc(&my_slab, &block_ptr, K_FOREVER);
...
/* use memory block pointed at by block_ptr */

k_mem_slab_free(&my_slab, &block_ptr);
```

Suggested Uses

Use a memory slab to allocate and free memory in fixed-size blocks.

Use memory slab blocks when sending large amounts of data from one thread to another, to avoid unnecessary copying of the data.

Configuration Options

Related configuration options:
- `CONFIG_MEM_SLAB_TRACE_MAX_UTILIZATION`

API Reference

`group mem_slab_apis`

**Defines**

```c
K_MEM_SLAB_DEFINE(name, slab_block_size, slab_num_blocks, slab_align)
```

Statically define and initialize a memory slab in a public (non-static) scope.

The memory slab's buffer contains `slab_num_blocks` memory blocks that are `slab_block_size` bytes long. The buffer is aligned to a `slab_align`-byte boundary. To ensure that each memory block is similarly aligned to this boundary, `slab_block_size` must also be a multiple of `slab_align`.

The memory slab can be accessed outside the module where it is defined using:

```c
extern struct k_mem_slab <name>;
```

**Note:** This macro cannot be used together with a static keyword. If such a use-case is desired, use `K_MEM_SLAB_DEFINE_STATIC` instead.

**Parameters**

- `name` – Name of the memory slab.
• slab_block_size – Size of each memory block (in bytes).
• slab_num_blocks – Number memory blocks.
• slab_align – Alignment of the memory slab's buffer (power of 2).

\texttt{K\_MEM\_SLAB\_DEFINE\_STATIC(name, slab_block_size, slab_num_blocks, slab_align)}

Statically define and initialize a memory slab in a private (static) scope.

The memory slab's buffer contains \texttt{slab_num_blocks} memory blocks that are \texttt{slab_block_size} bytes long. The buffer is aligned to a \texttt{slab_align} -byte boundary. To ensure that each memory block is similarly aligned to this boundary, \texttt{slab_block_size} must also be a multiple of \texttt{slab_align}.

**Parameters**

• \texttt{name} – Name of the memory slab.
• \texttt{slab_block_size} – Size of each memory block (in bytes).
• \texttt{slab_num_blocks} – Number memory blocks.
• \texttt{slab_align} – Alignment of the memory slab's buffer (power of 2).

**Functions**

\texttt{int k\_mem\_slab\_init(struct k\_mem\_slab *slab, void *buffer, size\_t block\_size, uint32\_t num\_blocks)}

Initialize a memory slab.

Initializes a memory slab, prior to its first use.

The memory slab's buffer contains \texttt{slab_num_blocks} memory blocks that are \texttt{slab_block_size} bytes long. The buffer must be aligned to an N-byte boundary matching a word boundary, where N is a power of 2 (i.e. 4 on 32-bit systems, 8, 16, ...). To ensure that each memory block is similarly aligned to this boundary, \texttt{slab_block_size} must also be a multiple of N.

**Parameters**

• \texttt{slab} – Address of the memory slab.
• \texttt{buffer} – Pointer to buffer used for the memory blocks.
• \texttt{block\_size} – Size of each memory block (in bytes).
• \texttt{num\_blocks} – Number of memory blocks.

**Return values**

• 0 – on success
• -EINVAL – invalid data supplied

\texttt{int k\_mem\_slab\_alloc(struct k\_mem\_slab *slab, void **mem, k\_timeout\_t timeout)}

Allocate memory from a memory slab.

This routine allocates a memory block from a memory slab.

**Function properties (list may not be complete)**

\texttt{isr-ok}

---

**Note:** \texttt{timeout} must be set to \texttt{K\_NO\_WAIT} if called from ISR.

---

**Note:** When \texttt{CONFIG\_MULTITHREADING=n} any \texttt{timeout} is treated as \texttt{K\_NO\_WAIT}.
Parameters

- **slab** – Address of the memory slab.
- **mem** – Pointer to block address area.
- **timeout** – Non-negative waiting period to wait for operation to complete. Use K_NO_WAIT to return without waiting, or K_FOREVER to wait as long as necessary.

Return values

- **0** – Memory allocated. The block address area pointed at by **mem** is set to the starting address of the memory block.
- **-ENOMEM** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.
- **-EINVAL** – Invalid data supplied

```c
void k_mem_slab_free(struct k_mem_slab *slab, void **mem)
```
Free memory allocated from a memory slab.

This routine releases a previously allocated memory block back to its associated memory slab.

Parameters

- **slab** – Address of the memory slab.
- **mem** – Pointer to block address area (as set by `k_mem_slab_alloc()`).

```c
static inline uint32_t k_mem_slab_num_used_get(struct k_mem_slab *slab)
```
Get the number of used blocks in a memory slab.

This routine gets the number of memory blocks that are currently allocated in `slab`.

Parameters

- **slab** – Address of the memory slab.

Returns

Number of allocated memory blocks.

```c
static inline uint32_t k_mem_slab_max_used_get(struct k_mem_slab *slab)
```
Get the number of maximum used blocks so far in a memory slab.

This routine gets the maximum number of memory blocks that were allocated in `slab`.

Parameters

- **slab** – Address of the memory slab.

Returns

Maximum number of allocated memory blocks.

```c
static inline uint32_t k_mem_slab_num_free_get(struct k_mem_slab *slab)
```
Get the number of unused blocks in a memory slab.

This routine gets the number of memory blocks that are currently unallocated in `slab`.

Parameters

- **slab** – Address of the memory slab.

Returns

Number of unallocated memory blocks.
int k_mem_slab_runtime_stats_get(struct k_mem_slab *slab, struct sys_memory_stats *stats)
Get the memory stats for a memory slab.

This routine gets the runtime memory usage stats for the slab \textit{slab}.

**Parameters**
- \textit{slab} – Address of the memory slab
- \textit{stats} – Pointer to memory into which to copy memory usage statistics

**Return values**
- 0 – Success
- -EINVAL – Any parameter points to NULL

int k_mem_slab_runtime_stats_reset_max(struct k_mem_slab *slab)
Reset the maximum memory usage for a slab.

This routine resets the maximum memory usage for the slab \textit{slab} to its current usage.

**Parameters**
- \textit{slab} – Address of the memory slab

**Return values**
- 0 – Success
- -EINVAL – Memory slab is NULL

### 3.4.4 Memory Blocks Allocator

The Memory Blocks Allocator allows memory blocks to be dynamically allocated from a designated memory region, where:

- All memory blocks have a single fixed size.
- Multiple blocks can be allocated or freed at the same time.
- A group of blocks allocated together may not be contiguous. This is useful for operations such as scatter-gather DMA transfers.
- Bookkeeping of allocated blocks is done outside of the associated buffer (unlike memory slab). This allows the buffer to reside in memory regions where these can be powered down to conserve energy.

- **Concepts**
  - \textit{Internal Operation}
- **Memory Blocks Allocator**
- **Multi Memory Blocks Allocator Group**
- **Usage**
  - \textit{Defining a Memory Blocks Allocator}
  - \textit{Allocating Memory Blocks}
  - \textit{Releasing a Memory Block}
  - \textit{Using Multi Memory Blocks Allocator Group}
- **API Reference**
Concepts

Any number of Memory Blocks Allocator can be defined (limited only by available RAM). Each allocator is referenced by its memory address.

A memory blocks allocator has the following key properties:

- The block size of each block, measured in bytes. It must be at least $4N$ bytes long, where $N$ is greater than 0.
- The number of blocks available for allocation. It must be greater than zero.
- A buffer that provides the memory for the memory slab's blocks. It must be at least “block size” times “number of blocks” bytes long.
- A blocks bitmap to keep track of which block has been allocated.

The buffer must be aligned to an $N$-byte boundary, where $N$ is a power of 2 larger than 2 (i.e. 4, 8, 16, ...). To ensure that all memory blocks in the buffer are similarly aligned to this boundary, the block size must also be a multiple of $N$.

Due to the use of internal bookkeeping structures and their creation, each memory blocks allocator must be declared and defined at compile time.

Internal Operation

Each buffer associated with an allocator is an array of fixed-size blocks, with no wasted space between the blocks.

The memory blocks allocator keeps track of unallocated blocks using a bitmap.

Memory Blocks Allocator

Internally, the memory blocks allocator uses a bitmap to keep track of which blocks have been allocated. Each allocator, utilizing the sys_bitarray interface, gets memory blocks one by one from the backing buffer up to the requested number of blocks. All the metadata about an allocator is stored outside of the backing buffer. This allows the memory region of the backing buffer to be powered down to conserve energy, as the allocator code never touches the content of the buffer.

Multi Memory Blocks Allocator Group

The Multi Memory Blocks Allocator Group utility functions provide a convenient to manage a group of allocators. A custom allocator choosing function is used to choose which allocator to use among this group.

An allocator group should be initialized at runtime via sys_multi_mem_blocks_init(). Each allocator can then be added via sys_multi_mem_blocks_add_allocator().

To allocate memory blocks from group, sys_multi_mem_blocks_alloc() is called with an opaque “configuration” parameter. This parameter is passed directly to the allocator choosing function so that an appropriate allocator can be chosen. After an allocator is chosen, memory blocks are allocated via sys_mem_blocks_alloc().

Allocated memory blocks can be freed via sys_multi_mem_blocks_free(). The caller does not need to pass a configuration parameter. The allocator code matches the passed in memory addresses to find the correct allocator and then memory blocks are freed via sys_mem_blocks_free().

Usage

Defining a Memory Blocks Allocator A memory blocks allocator is defined using a variable of type sys_mem_blocks_t. It needs to be defined and initialized at compile time by calling SYS_MEM_BLOCKS_DEFINE.
The following code defines and initializes a memory blocks allocator which has 4 blocks that are 64 bytes long, each of which is aligned to a 4-byte boundary:

```c
SYS_MEM_BLOCKS_DEFINE(allocator, 64, 4, 4);
```

Similarly, you can define a memory slab in private scope:

```c
SYS_MEM_BLOCKS_DEFINE_STATIC(static_allocator, 64, 4, 4);
```

A pre-defined buffer can also be provided to the allocator where the buffer can be placed separately. Note that the alignment of the buffer needs to be done at its definition.

```c
uint8_t __aligned(4) backing_buffer[64 * 4];
SYS_MEM_BLOCKS_DEFINE_WITH_EXT_BUF(allocator, 64, 4, backing_buffer);
```

### Allocating Memory Blocks

Memory blocks can be allocated by calling `sys_mem_blocks_alloc()`.

```c
int ret;
uintptr_t blocks[2];
ret = sys_mem_blocks_alloc(allocator, 2, blocks);
```

If `ret == 0`, the array `blocks` will contain an array of memory addresses pointing to the allocated blocks.

### Releasing a Memory Block

Memory blocks are released by calling `sys_mem_blocks_free()`.

The following code builds on the example above which allocates 2 memory blocks, then releases them once they are no longer needed.

```c
int ret;
uintptr_t blocks[2];
ret = sys_mem_blocks_alloc(allocator, 2, blocks);
... /* perform some operations on the allocated memory blocks */
ret = sys_mem_blocks_free(allocator, 2, blocks);
```

### Using Multi Memory Blocks Allocator Group

The following code demonstrates how to initialize an allocator group:

```c
sys_mem_blocks_t *choice_fn(struct sys_multi_mem_blocks *group, void *cfg)
{
    ...
}
SYS_MEM_BLOCKS_DEFINE(allocator0, 64, 4, 4);
SYS_MEM_BLOCKS_DEFINE(allocator1, 64, 4, 4);
static sys_multi_mem_blocks_t alloc_group;
sys_multi_mem_blocks_init(&alloc_group, choice_fn);
sys_multi_mem_blocks_add_allocator(&alloc_group, &allocator0);
sys_multi_mem_blocks_add_allocator(&alloc_group, &allocator1);
```

To allocate and free memory blocks from the group:

```c
```
```
int ret;
uintptr_t blocks[1];
size_t blk_size;

ret = sys_multi_mem_blocks_alloc(&alloc_group, UINT_TO_POINTER(0),
                                 1, blocks, &blk_size);
ret = sys_multi_mem_blocks_free(&alloc_group, 1, blocks);
```

### API Reference

**group mem_blocks_apis**

**Defines**

SYS_MEM_BLOCKS_DEFINE(name, blk_sz, num_blks, buf_align)

Create a memory block object with a new backing buffer.

**Parameters**

- name – Name of the memory block object.
- blk_sz – Size of each memory block (in bytes).
- num_blks – Total number of memory blocks.
- buf_align – Alignment of the memory block buffer (power of 2).

SYS_MEM_BLOCKS_DEFINE_STATIC(name, blk_sz, num_blks, buf_align)

Create a static memory block object with a new backing buffer.

**Parameters**

- name – Name of the memory block object.
- blk_sz – Size of each memory block (in bytes).
- num_blks – Total number of memory blocks.
- buf_align – Alignment of the memory block buffer (power of 2).

SYS_MEM_BLOCKS_DEFINE_WITH_EXT_BUF(name, blk_sz, num_blks, buf)

Create a memory block object with a providing backing buffer.

**Parameters**

- name – Name of the memory block object.
- blk_sz – Size of each memory block (in bytes).
- num_blks – Total number of memory blocks.
- buf – Backing buffer of type uint8_t.

SYS_MEM_BLOCKS_DEFINE_STATIC_WITH_EXT_BUF(name, blk_sz, num_blks, buf)

Create a static memory block object with a providing backing buffer.

**Parameters**

- name – Name of the memory block object.
- blk_sz – Size of each memory block (in bytes).
- num_blks – Total number of memory blocks.
buf – Backing buffer of type uint8_t.

**Typedefs**

typedef struct sys_mem_blocks sys_mem_blocks_t
    Memory Blocks Allocator.

typedef struct sys_multi_mem_blocks sys_multi_mem_blocks_t
    Multi Memory Blocks Allocator.

typedef sys_mem_blocks_t *(sys_multi_mem_blocks_choice_fn_t)(struct sys_multi_mem_blocks *group, void *cfg)
    Multi memory blocks allocator choice function.

    This is a user-provided functions whose responsibility is selecting a specific memory blocks
    allocator based on the opaque cfg value, which is specified by the user as an argument to
    sys_multi_mem_blocks_alloc(). The callback returns a pointer to the chosen allocator where
    the allocation is performed.

    NULL may be returned, which will cause the allocation to fail and a -EINVAL reported to the
    calling code.

    **Param group**
    Multi memory blocks allocator structure.

    **Param cfg**
    An opaque user-provided value. It may be interpreted in any way by the applica-
    tion.

    **Return**
    A pointer to the chosen allocator, or NULL if none is chosen.

**Functions**

int sys_mem_blocks_alloc(sys_mem_blocks_t *mem_block, size_t count, void **out_blocks)
    Allocate multiple memory blocks.

    Allocate multiple memory blocks, and place their pointers into the output array.

    **Parameters**

    • mem_block – Pointer to memory block object.
    • count – [in] Number of blocks to allocate.
    • out_blocks – [out] Output array to be populated by pointers to the memory
      blocks. It must have at least count elements.

    **Return values**

    • 0 – Successful
    • -EINVAL – Invalid argument supplied.
    • -ENOMEM – Not enough blocks for allocation.

int sys_mem_blocks_alloc_contiguous(sys_mem_blocks_t *mem_block, size_t count, void **out_block)
    Allocate a contiguous set of memory blocks.

    Allocate multiple memory blocks, and place their pointers into the output array.
Parameters
- mem_block – Pointer to memory block object.
- count – [in] Number of blocks to allocate.
- out_block – [out] Output pointer to the start of the allocated block set

Return values
- 0 – Successful
- -EINVAL – Invalid argument supplied.
- -ENOMEM – Not enough contiguous blocks for allocation.

```
int sys_mem_blocks_get(sys_mem_blocks_t *mem_block, void *in_block, size_t count)
```

Force allocation of a specified blocks in a memory block object.

Allocate a specified blocks in a memory block object. Note: use caution when mixing sys_mem_blocks_get and sys_mem_blocks_alloc, allocation may take any of the free memory space

Parameters
- mem_block – Pointer to memory block object.
- in_block – [in] Address of the first required block to allocate
- count – [in] Number of blocks to allocate.

Return values
- 0 – Successful
- -EINVAL – Invalid argument supplied.
- -ENOMEM – Some of blocks are taken and cannot be allocated

```
int sys_mem_blocks_is_region_free(sys_mem_blocks_t *mem_block, void *in_block, size_t count)
```

check if the region is free

Parameters
- mem_block – Pointer to memory block object.
- in_block – [in] Address of the first block to check
- count – [in] Number of blocks to check.

Return values
- 1 – All memory blocks are free
- 0 – At least one of the memory blocks is taken

```
int sys_mem_blocks_free(sys_mem_blocks_t *mem_block, size_t count, void **in_blocks)
```

Free multiple memory blocks.

Free multiple memory blocks according to the array of memory block pointers.

Parameters
- mem_block – Pointer to memory block object.
- count – [in] Number of blocks to free.

Return values
- 0 – Successful
Free contiguous multiple memory blocks.

Free contiguous multiple memory blocks

**Parameters**

- `mem_block` – Pointer to memory block object.
- `block` – [in] Pointer to the first memory block
- `count` – [in] Number of blocks to free.

**Return values**

- 0 – Successful
- EINVAL – Invalid argument supplied.
-EFAULT – Invalid pointer supplied.

**void sys_multi_mem_blocks_init(sys_multi_mem_blocks_t *group, sys_multi_mem_blocks_choice_fn_t choice_fn)**

Initialize multi memory blocks allocator group.

Initialize a sys_multi_mem_block struct with the specified choice function. Note that individual allocator must be added later with sys_multi_mem_blocks_add_allocator.

**Parameters**

- `group` – Multi memory blocks allocator structure.
- `choice_fn` – A sys_multi_mem_blocks_choice_fn_t callback used to select the allocator to be used at allocation time

**void sys_multi_mem_blocks_add_allocator(sys_multi_mem_blocks_t *group, sys_mem_blocks_t *alloc)**

Add an allocator to an allocator group.

This adds a known allocator to an existing multi memory blocks allocator group.

**Parameters**

- `group` – Multi memory blocks allocator structure.
- `alloc` – Allocator to add

**int sys_multi_mem_blocks_alloc(sys_multi_mem_blocks_t *group, void *cfg, size_t count, void **out_blocks, size_t *blk_size)**

Allocate memory from multi memory blocks allocator group.

Just as for `sys_mem_blocks_alloc()`, allocates multiple blocks of memory. Takes an opaque configuration pointer passed to the choice function, which is used by integration code to choose an allocator.

**Parameters**

- `cfg` – [in] Opaque configuration parameter, as for `sys_multi_mem_blocks_choice_fn_t`
- `count` – [in] Number of blocks to allocate
- `out_blocks` – [out] Output array to be populated by pointers to the memory blocks. It must have at least `count` elements.
• blk_size – [out] If not NULL, output the block size of the chosen allocator.

Return values
• 0 – Successful
• -EINVAL – Invalid argument supplied, or no allocator chosen.
• -ENOMEM – Not enough blocks for allocation.

int sys_multi_mem_blocks_free(sys_multi_mem_blocks_t *group, size_t count, void ***in_blocks)

Free memory allocated from multi memory blocks allocator group.
Free previous allocated memory blocks from sys_multi_mem_blocks_alloc().
Note that all blocks in in_blocks must be from the same allocator.

Parameters
• count – [in] Number of blocks to free.
• in_blocks – [in] Input array of pointers to the memory blocks.

Return values
• 0 – Successful
• -EINVAL – Invalid argument supplied, or no allocator chosen.
• -EFAULT – Invalid pointer(s) supplied.

3.4.5 Demand Paging

Demand paging provides a mechanism where data is only brought into physical memory as required by current execution context. The physical memory is conceptually divided in page-sized page frames as regions to hold data.

• When the processor tries to access data and the data page exists in one of the page frames, the execution continues without any interruptions.
• When the processor tries to access the data page that does not exist in any page frames, a page fault occurs. The paging code then brings in the corresponding data page from backing store into physical memory if there is a free page frame. If there is no more free page frames, the eviction algorithm is invoked to select a data page to be paged out, thus freeing up a page frame for new data to be paged in. If this data page has been modified after it is first paged in, the data will be written back into the backing store. If no modifications is done or after written back into backing store, the data page is now considered paged out and the corresponding page frame is now free. The paging code then invokes the backing store to page in the data page corresponding to the location of the requested data. The backing store copies that data page into the free page frame. Now the data page is in physical memory and execution can continue.

There are functions where paging in and out can be invoked manually using k_mem_page_in() and k_mem_page_out(). k_mem_page_in() can be used to page in data pages in anticipation that they are required in the near future. This is used to minimize number of page faults as these data pages are already in physical memory, and thus minimizing latency. k_mem_page_out() can be used to page out data pages where they are not going to be accessed for a considerable amount of time. This frees up page frames so that the next page in can be executed faster as the paging code does not need to invoke the eviction algorithm.
Terminology

Data Page
A data page is a page-sized region of data. It may exist in a page frame, or be paged out to some backing store. Its location can always be looked up in the CPU's page tables (or equivalent) by virtual address. The data type will always be void * or in some cases uint8_t * when doing pointer arithmetic.

Page Frame
A page frame is a page-sized physical memory region in RAM. It is a container where a data page may be placed. It is always referred to by physical address. Zephyr has a convention of using uintptr_t for physical addresses. For every page frame, a struct z_page_frame is instantiated to store metadata. Flags for each page frame:

• Z_PAGE_FRAME_PINNED indicates a page frame is pinned in memory and should never be paged out.
• Z_PAGE_FRAME_RESERVED indicates a physical page reserved by hardware and should not be used at all.
• Z_PAGE_FRAME_MAPPED is set when a physical page is mapped to virtual memory address.
• Z_PAGE_FRAME_BUSY indicates a page frame is currently involved in a page-in/out operation.
• Z_PAGEFRAME_BACKED indicates a page frame has a clean copy in the backing store.

Z_SCRATCH_PAGE
The virtual address of a special page provided to the backing store to: * Copy a data page from Z_SCRATCH_PAGE to the specified location; or, * Copy a data page from the provided location to Z_SCRATCH_PAGE. This is used as an intermediate page for page in/out operations. This scratch needs to be mapped read/write for backing store code to access. However the data page itself may only be mapped as read-only in virtual address space. If this page is provided as-is to backing store, the data page must be re-mapped as read/write which has security implications as the data page is no longer read-only to other parts of the application.

Paging Statistics
Paging statistics can be obtained via various function calls when CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM_NUM_BINS is enabled:

• Overall statistics via k_mem_paging_stats_get()

• Per-thread statistics via k_mem_paging_thread_stats_get() if CONFIG_DEMAND_PAGING_THREAD_STATS is enabled

• Execution time histogram can be obtained when CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM is enabled, and CONFIG_DEMAND_PAGING_TIMING_HISTOGRAM_NUM_BINS is defined. Note that the timing is highly dependent on the architecture, SoC or board. It is highly recommended that k_mem_paging_eviction_histogram_bounds[] and k_mem_paging_backing_store_histogram_bounds[] be defined for a particular application.
  – Execution time histogram of eviction algorithm via k_mem_paging_histogram_eviction_get()
  – Execution time histogram of backing store doing page-in via k_mem_paging_histogram_backing_store_page_in_get()
  – Execution time histogram of backing store doing page-out via k_mem_paging_histogram_backing_store_page_out_get()

Eviction Algorithm
The eviction algorithm is used to determine which data page and its corresponding page frame can be paged out to free up a page frame for the next page in operation. There are two functions which are
called from the kernel paging code:

- `k_mem_paging_eviction_init()` is called to initialize the eviction algorithm. This is called at `POST_KERNEL`.
- `k_mem_paging_eviction_select()` is called to select a data page to evict. A function argument `dirty` is written to signal the caller whether the selected data page has been modified since it is first paged in. If the `dirty` bit is returned as set, the paging code signals to the backing store to write the data page back into storage (thus updating its content). The function returns a pointer to the page frame corresponding to the selected data page.

Currently, a NRU (Not-Recently-Used) eviction algorithm has been implemented as a sample. This is a very simple algorithm which ranks each data page on whether they have been accessed and modified. The selection is based on this ranking.

To implement a new eviction algorithm, the two functions mentioned above must be implemented.

**Backing Store**

Backing store is responsible for paging in/out data page between their corresponding page frames and storage. These are the functions which must be implemented:

- `k_mem_paging_backing_store_init()` is called to initialized the backing store at `POST_KERNEL`.
- `k_mem_paging_backing_store_location_get()` is called to reserve a backing store location so a data page can be paged out. This location token is passed to `k_mem_paging_backing_store_page_out()` to perform actual page out operation.
- `k_mem_paging_backing_store_location_free()` is called to free a backing store location (the location token) which can then be used for subsequent page out operation.
- `k_mem_paging_backing_store_page_in()` copies a data page from the backing store location associated with the provided location token to the page pointed by `Z_SCRATCH_PAGE`.
- `k_mem_paging_backing_store_page_out()` copies a data page from `Z_SCRATCH_PAGE` to the backing store location associated with the provided location token.
- `k_mem_paging_backing_store_page_finalize()` is invoked after `k_mem_paging_backing_store_page_in()` so that the page frame struct may be updated for internal accounting. This can be a no-op.

To implement a new backing store, the functions mentioned above must be implemented. `k_mem_paging_backing_store_page_finalize()` can be an empty function if so desired.

**API Reference**

`group mem-demand-paging`

**Functions**

```c
int k_mem_page_out(void *addr, size_t size)
```

Evict a page-aligned virtual memory region to the backing store

Useful if it is known that a memory region will not be used for some time. All the data pages within the specified region will be evicted to the backing store if they weren’t already, with their associated page frames marked as available for mappings or page-ins.

None of the associated page frames mapped to the provided region should be pinned.

Note that there are no guarantees how long these pages will be evicted, they could take page faults immediately.
If CONFIG_DEMAND_PAGING_ALLOW_IRQ is enabled, this function may not be called by ISRs as the backing store may be in-use.

**Parameters**
- `addr` – Base page-aligned virtual address
- `size` – Page-aligned data region size

**Return values**
- `0` – Success
- `-ENOMEM` – Insufficient space in backing store to satisfy request. The region may be partially paged out.

```c
void k_mem_page_in(void *addr, size_t size)
```

Load a virtual data region into memory

After the function completes, all the page frames associated with this function will be paged in. However, they are not guaranteed to stay there. This is useful if the region is known to be used soon.

If CONFIG_DEMAND_PAGING_ALLOW_IRQ is enabled, this function may not be called by ISRs as the backing store may be in-use.

**Parameters**
- `addr` – Base page-aligned virtual address
- `size` – Page-aligned data region size

```c
void k_mem_pin(void *addr, size_t size)
```

Pin an aligned virtual data region, paging in as necessary

After the function completes, all the page frames associated with this region will be resident in memory and pinned such that they stay that way. This is a stronger version of `z_mem_page_in()`.

If CONFIG_DEMAND_PAGING_ALLOW_IRQ is enabled, this function may not be called by ISRs as the backing store may be in-use.

**Parameters**
- `addr` – Base page-aligned virtual address
- `size` – Page-aligned data region size

```c
void k_mem_unpin(void *addr, size_t size)
```

Un-pin an aligned virtual data region

After the function completes, all the page frames associated with this region will be no longer marked as pinned. This does not evict the region, follow this with `z_mem_page_out()` if you need that.

**Parameters**
- `addr` – Base page-aligned virtual address
- `size` – Page-aligned data region size

```c
void k_mem_paging_stats_get(struct k_mem_paging_stats_t *stats)
```

Get the paging statistics since system startup

This populates the paging statistics struct being passed in as argument.

**Parameters**
- `stats` – [inout] Paging statistics struct to be filled.
void k_mem_paging_thread_stats_get(struct k_thread *thread, struct k_mem_paging_stats_t *stats)

Get the paging statistics since system startup for a thread
This populates the paging statistics struct being passed in as argument for a particular thread.

Parameters

- thread – [in] Thread
- stats – [inout] Paging statistics struct to be filled.

void k_mem_paging_histogram_eviction_get(struct k_mem_paging_histogram_t *hist)

Get the eviction timing histogram
This populates the timing histogram struct being passed in as argument.

Parameters

- hist – [inout] Timing histogram struct to be filled.

void k_mem_paging_histogramBacking_store_page_in_get(struct k_mem_paging_histogram_t *hist)

Get the backing store page-in timing histogram
This populates the timing histogram struct being passed in as argument.

Parameters

- hist – [inout] Timing histogram struct to be filled.

void k_mem_paging_histogramBacking_store_page_out_get(struct k_mem_paging_histogram_t *hist)

Get the backing store page-out timing histogram
This populates the timing histogram struct being passed in as argument.

Parameters

- hist – [inout] Timing histogram struct to be filled.

eviction

eviction

eviction

Eviction Algorithm APIs

group mem-demand-paging-eviction

Eviction algorithm APIs

Functions

struct z_page_frame *k_mem_paging_eviction_select(bool *dirty)

Select a page frame for eviction
The kernel will invoke this to choose a page frame to evict if there are no free page frames.
This function will never be called before the initial k_mem_paging_eviction_init().
This function is invoked with interrupts locked.

Parameters

- dirty – [out] Whether the page to evict is dirty

Returns

The page frame to evict
void k_mem_paging_eviction_init(void)
Initialization function
Called at POST_KERNEL to perform any necessary initialization tasks for the eviction algorythm. \textit{k\_mem\_paging\_eviction\_select()} is guaranteed to never be called until this has returned, and this will only be called once.

**Backing Store APIs**

\textit{group mem-demand-paging-backing-store}

Backing store APIs

**Functions**

int k_mem_paging_backing_store_location_get(struct z_page_frame *pf, uintptr_t *location,
bool page_fault)

Reserve or fetch a storage location for a data page loaded into a page frame

The returned location token must be unique to the mapped virtual address. This location will be used in the backing store to page out data page contents for later retrieval. The location value must be page-aligned.

This function may be called multiple times on the same data page. If its page frame has its Z\_PAGE\_FRAME\_BACKED bit set, it is expected to return the previous backing store location for the data page containing a cached clean copy. This clean copy may be updated on page-out, or used to discard clean pages without needing to write out their contents.

If the backing store is full, some other backing store location which caches a loaded data page may be selected, in which case its associated page frame will have the Z\_PAGE\_FRAME\_BACKED bit cleared (as it is no longer cached).

pf->addr will indicate the virtual address the page is currently mapped to. Large, sparse backing stores which can contain the entire address space may simply generate location tokens purely as a function of pf->addr with no other management necessary.

This function distinguishes whether it was called on behalf of a page fault. A free backing store location must always be reserved in order for page faults to succeed. If the page\_fault parameter is not set, this function should return -ENOMEM even if one location is available.

This function is invoked with interrupts locked.

**Parameters**

- \textit{pf} – Virtual address to obtain a storage location
- \textit{location} – [\textbf{out}] storage location token
- \textit{page\_fault} – Whether this request was for a page fault

**Returns**

0 Success

-ENOMEM Backing store is full

void k_mem_paging_backing_store_location_free(uintptr_t location)
Free a backing store location

Any stored data may be discarded, and the location token associated with this address may be re-used for some other data page.

This function is invoked with interrupts locked.

**Parameters**
void k_mem_paging_backing_store_page_out(uintptr_t location)
Copy a data page from Z_SCRATCH_PAGE to the specified location
Immediately before this is called, Z_SCRATCH_PAGE will be mapped read-write to the intended source page frame for the calling context.
Calls to this and k_mem_paging_backing_store_page_in() will always be serialized, but interrupts may be enabled.

Parameters

• location – Location token to free

void k_mem_paging_backing_store_page_in(uintptr_t location)
Copy a data page from the provided location to Z_SCRATCH_PAGE.
Immediately before this is called, Z_SCRATCH_PAGE will be mapped read-write to the intended destination page frame for the calling context.
Calls to this and k_mem_paging_backing_store_page_out() will always be serialized, but interrupts may be enabled.

Parameters

• location – Location token for the data page

void k_mem_paging_backing_store_page_finalize(struct z_page_frame *pf, uintptr_t location)
Update internal accounting after a page-in
This is invoked after k_mem_paging_backing_store_page_in() and interrupts have been re-locked, making it safe to access the z_page_frame data. The location value will be the same passed to k_mem_paging_backing_store_page_in().
The primary use-case for this is to update custom fields for the backing store in the page frame, to reflect where the data should be evicted to if it is paged out again. This may be a no-op in some implementations.
If the backing store caches paged-in data pages, this is the appropriate time to set the Z_PAGE_FRAME_BACKED bit. The kernel only skips paging out clean data pages if they are noted as clean in the page tables and the Z_PAGE_FRAME_BACKED bit is set in their associated page frame.

Parameters

• pf – Page frame that was loaded in
• location – Location of where the loaded data page was retrieved

void k_mem_paging_backing_store_init(void)
Backing store initialization function.
The implementation may expect to receive page in/out calls as soon as this returns, but not before that. Called at POST_KERNEL.
This function is expected to do two things:

• Initialize any internal data structures and accounting for the backing store.

• If the backing store already contains all or some loaded kernel data pages at boot time, Z_PAGE_FRAME_BACKED should be appropriately set for their associated page frames, and any internal accounting set up appropriately.
3.5 Data Structures

Zephyr provides a library of common general purpose data structures used within the kernel, but useful by application code in general. These include list and balanced tree structures for storing ordered data, and a ring buffer for managing “byte stream” data in a clean way.

Note that in general, the collections are implemented as “intrusive” data structures. The “node” data is the only struct used by the library code, and it does not store a pointer or other metadata to indicate what user data is “owned” by that node. Instead, the expectation is that the node will be itself embedded within a user-defined struct. Macros are provided to retrieve a user struct address from the embedded node pointer in a clean way. The purpose behind this design is to allow the collections to be used in contexts where dynamic allocation is disallowed (i.e. there is no need to allocate node objects because the memory is provided by the user).

Note also that these libraries are uniformly unsynchronized; access to them is not threadsafe by default. These are data structures, not synchronization primitives. The expectation is that any locking needed will be provided by the user.

3.5.1 Single-linked List

Zephyr provides a `sys_slist_t` type for storing simple singly-linked list data (i.e. data where each list element stores a pointer to the next element, but not the previous one). This supports constant-time access to the first (head) and last (tail) elements of the list, insertion before the head and after the tail of the list and constant time removal of the head. Removal of subsequent nodes requires access to the “previous” pointer and thus can only be performed in linear time by searching the list.

The `sys_slist_t` struct may be instantiated by the user in any accessible memory. It should be initialized with either `sys_slist_init()` or by static assignment from `SYS_SLIST_STATIC_INIT` before use. Its interior fields are opaque and should not be accessed by user code.

The end nodes of a list may be retrieved with `sys_slist_peek_head()` and `sys_slist_peek_tail()`, which will return NULL if the list is empty, otherwise a pointer to a `sys_snode_t` struct.

The `sys_snode_t` struct represents the data to be inserted. In general, it is expected to be allocated/controlled by the user, usually embedded within a struct which is to be added to the list. The container struct pointer may be retrieved from a list node using `SYS_SLIST_CONTAINER`, passing it the struct name of the containing struct and the field name of the node. Internally, the `sys_snode_t` struct contains only a next pointer, which may be accessed with `sys_slist_peek_next()`.

Lists may be modified by adding a single node at the head or tail with `sys_slist_prepend()` and `sys_slist_append()`. They may also have a node added to an interior point with `sys_slist_insert()`, which inserts a new node after an existing one. Similarly `sys_slist_remove()` will remove a node given a pointer to its predecessor. These operations are all constant time.

Convenience routines exist for more complicated modifications to a list. `sys_slist_merge_slist()` will append an entire list to an existing one. `sys_slist_append_list()` will append a bounded subset of an existing list in constant time. And `sys_slist_find_and_remove()` will search a list (in linear time) for a given node and remove it if present.

Finally the slist implementation provides a set of “for each” macros that allows for iterating over a list in a natural way without needing to manually traverse the next pointers. `SYS_SLIST_FOR_EACH_NODE` will enumerate every node in a list given a local variable to store the node pointer. `SYS_SLIST_FOR_EACH_NODE_SAFE` behaves similarly, but has a more complicated implementation that requires an extra scratch variable for storage and allows the user to delete the iterated node during the iteration. Each of those macros also exists in a “container” variant (`SYS_SLIST_FOR_EACH_CONTAINER` and `SYS_SLIST_FOR_EACH_CONTAINER_SAFE`) which assigns a local variable of a type that matches the user's container struct and not the node struct, performing the required offsets internally. And `SYS_SLIST_ITERATE_FROM_NODE` exists to allow for enumerating a node and all its successors only, without inspecting the earlier part of the list.
Single-linked List Internals

The slist code is designed to be minimal and conventional. Internally, a `sys_slist_t` struct is nothing more than a pair of “head” and “tail” pointer fields. And a `sys_sn ode_t` stores only a single “next” pointer.

![Image of a single-linked list](image1.png)

Fig. 3.4: An slist containing three elements.

![Image of an empty list](image2.png)

Fig. 3.5: An empty slist

The specific implementation of the list code, however, is done with an internal “Z_GENLIST” template API which allows for extracting those fields from arbitrary structures and emits an arbitrarily named set of functions. This allows for implementing more complicated single-linked list variants using the same basic primitives. The genlist implementor is responsible for a custom implementation of the primitive operations only: an “init” step for each struct, and a “get” and “set” primitives for each of head, tail and next pointers on their relevant structs. These inline functions are passed as parameters to the genlist macro expansion.

Only one such variant, sflist, exists in Zephyr at the moment.

Flagged List

The `sys_sflist_t` is implemented using the described genlist template API. With the exception of symbol naming (“sflist” instead of “slist”) and the additional API described next, it operates in all ways identically to the slist API.

It adds the ability to associate exactly two bits of user defined “flags” with each list node. These can be accessed and modified with `sys_sfn ode_flags_get()` and `sys_sfn ode_flags_set()`. Internally, the flags are stored unioned with the bottom bits of the next pointer and incur no SRAM storage overhead when compared with the simpler slist code.

Single-linked List API Reference

`group single-linked-list_apis`

`Defines`
SYS_SLIST_FOR_EACH_NODE(__sl, __sn)
Provide the primitive to iterate on a list Note: the loop is unsafe and thus __sn should not be removed.
User MUST add the loop statement curly braces enclosing its own code:

SYS_SLIST_FOR_EACH_NODE(1, n) {
    <user code>
}

This and other SYS_SLIST_*( ) macros are not thread safe.

Parameters

• __sl – A pointer on a sys_slist_t to iterate on
• __sn – A sys_snode_t pointer to peek each node of the list

SYS_SLIST_ITERATE_FROM_NODE(__sl, __sn)
Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus __sn should not be removed.
User MUST add the loop statement curly braces enclosing its own code:

SYS_SLIST_ITERATE_FROM_NODE(1, n) {
    <user code>
}

Like SYS_SLIST_FOR_EACH_NODE(), but __dn already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.
This and other SYS_SLIST_*( ) macros are not thread safe.

Parameters

• __sl – A pointer on a sys_slist_t to iterate on
• __sn – A sys_snode_t pointer to peek each node of the list it contains the starting node, or NULL to start from the head

SYS_SLIST_FOR_EACH_NODE_SAFE(__sl, __sn, __sns)
Provide the primitive to safely iterate on a list Note: __sn can be removed, it will not break the loop.
User MUST add the loop statement curly braces enclosing its own code:

SYS_SLIST_FOR_EACH_NODE_SAFE(1, n, s) {
    <user code>
}

This and other SYS_SLIST_*( ) macros are not thread safe.

Parameters

• __sl – A pointer on a sys_slist_t to iterate on
• __sn – A sys_snode_t pointer to peek each node of the list
• __sns – A sys_snode_t pointer for the loop to run safely
SYS_SLIST_FOR_EACH_CONTAINER(__sl, __cn, __n)

Provide the primitive to iterate on a list under a container. Note: the loop is unsafe and thus __cn should not be detached.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SLIST_FOR_EACH_CONTAINER(l, c, n) {
  <user code>
}
```

**Parameters**

- __sl – A pointer on a sys_slist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_FOR_EACH_CONTAINER_SAFE(__sl, __cn, __cns, __n)

Provide the primitive to safely iterate on a list under a container. Note: __cn can be detached, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SLIST_FOR_EACH_NODE_SAFE(l, c, cn, n) {
  <user code>
}
```

**Parameters**

- __sl – A pointer on a sys_slist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __cns – A pointer for the loop to run safely
- __n – The field name of sys_node_t within the container struct

SYS_SLIST_STATIC_INIT(ptr_to_list)

**Functions**

**static inline void sys_slist_init(sys_slist_t *list)**

Initialize a list.

**Parameters**

- list – A pointer on the list to initialize

**static inline sys_snode_t *sys_slist_peek_head(sys_slist_t *list)**

Peek the first node from the list.

**Parameters**

- list – A pointer on the list to peek the first node from

**Returns**

A pointer on the first node of the list (or NULL if none)

**static inline sys_snode_t *sys_slist_peek_tail(sys_slist_t *list)**

Peek the last node from the list.

**Parameters**
• list – A point on the list to peek the last node from

Returns
A pointer on the last node of the list (or NULL if none)

static inline bool sys_slist_is_empty(sys_slist_t *list)
Test if the given list is empty.

Parameters
• list – A pointer on the list to test

Returns
a boolean, true if it's empty, false otherwise

static inline sys_snnode_t *sys_slist_peek_next_no_check(sys_snnode_t *node)
Peek the next node from current node, node is not NULL.
Faster then sys_slist_peek_next() if node is known not to be NULL.

Parameters
• node – A pointer on the node where to peek the next node

Returns
a pointer on the next node (or NULL if none)

static inline void sys_slist_prepend(sys_slist_t *list, sys_snnode_t *node)
Prepend a node to the given list.
This and other sys_slist_*() functions are not thread safe.

Parameters
• list – A pointer on the list to affect
• node – A pointer on the node to prepend

static inline void sys_slist_append(sys_slist_t *list, sys_snnode_t *node)
Append a node to the given list.
This and other sys_slist_*() functions are not thread safe.

Parameters
• list – A pointer on the list to affect
• node – A pointer on the node to append

static inline void sys_slist_append_list(sys_slist_t *list, void *head, void *tail)
Append a list to the given list.
Append a singly-linked, NULL-terminated list consisting of nodes containing the pointer to the
next node as the first element of a node, to list. This and other sys_slist_*() functions are not
thread safe.

FIXME: Why are the element parameters void *?

Parameters
• list – A pointer on the list to affect
- head – A pointer to the first element of the list to append
- tail – A pointer to the last element of the list to append

static inline void sys_slist_merge_slist(sys_slist_t *list, sys_slist_t *list_to_append)
merge two slists, appending the second one to the first

When the operation is completed, the appending list is empty. This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- list_to_append – A pointer to the list to append.

static inline void sys_slist_insert(sys_slist_t *list, sys_snodet *prev, sys_snodet *node)
Insert a node to the given list.

This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- prev – A pointer on the previous node
- node – A pointer on the node to insert

static inline sys_snodet *sys_slist_get_not_empty(sys_slist_t *list)
Fetch and remove the first node of the given list.
List must be known to be non-empty. This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect

Returns
A pointer to the first node of the list

static inline sys_snodet *sys_slist_get(sys_slist_t *list)
Fetch and remove the first node of the given list.
This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect

Returns
A pointer to the first node of the list (or NULL if empty)

static inline void sys_slist_remove(sys_slist_t *list, sys_snodet *prev_node, sys_snodet *node)
Remove a node.
This and other sys_slist_*() functions are not thread safe.

Parameters
- list – A pointer on the list to affect
- prev_node – A pointer on the previous node (can be NULL, which means the node is the list’s head)
- node – A pointer on the node to remove
static inline bool sys_slist_find_and_remove(sys_slist_t *list, sys_sn node)
    Find and remove a node from a list.
    This and other sys_slist_() functions are not thread safe.

Parameters

• list – A pointer on the list to affect
• node – A pointer on the node to remove from the list

Returns
    true if node was removed

Flagged List API Reference

group flagged-single-linked-list_apis

Defines

SYS_SFLIST_FOR_EACH_NODE(__sl, __sn)
    Provide the primitive to iterate on a list Note: the loop is unsafe and thus __sn should not be removed.
    User MUST add the loop statement curly braces enclosing its own code:

    SYS_SFLIST_FOR_EACH_NODE(l, n) {
        <user code>
    }

This and other SYS_SFLIST_*() macros are not thread safe.

Parameters

• __sl – A pointer on a sys_sflist_t to iterate on
• __sn – A sys_sfnode_t pointer to peek each node of the list

SYS_SFLIST_ITERATE_FROM_NODE(__sl, __sn)
    Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus __sn should not be removed.
    User MUST add the loop statement curly braces enclosing its own code:

    SYS_SFLIST_ITERATE_FROM_NODE(l, n) {
        <user code>
    }

Like SYS_SFLIST_FOR_EACH_NODE(), but __dn already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.

This and other SYS_SFLIST_*() macros are not thread safe.

Parameters

• __sl – A pointer on a sys_sflist_t to iterate on
• __sn – A sys_sfnode_t pointer to peek each node of the list it contains the starting node, or NULL to start from the head
SYS_SFLIST_FOR_EACH_NODE_SAFE(__sl, __sn, __sns)

Provide the primitive to safely iterate on a list. Note: __sn can be removed, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_NODE_SAFE(1, n, s) {
    <user code>
}
```

This and other SYS_SFLIST_*() macros are not thread safe.

**Parameters**

- __sl – A pointer on a sys_sflist_t to iterate on
- __sn – A sys_sfnode_t pointer to peek each node of the list
- __sns – A sys_sfnode_t pointer for the loop to run safely

---

SYS_SFLIST_CONTAINER(__ln, __cn, __n)
SYS_SFLIST_PEEK_HEAD_CONTAINER(__sl, __cn, __n)
SYS_SFLIST_PEEK_TAIL_CONTAINER(__sl, __cn, __n)
SYS_SFLIST_PEEK_NEXT_CONTAINER(__cn, __n)
SYS_SFLIST_FOR_EACH_CONTAINER(__sl, __cn, __n)

Provide the primitive to iterate on a list under a container. Note: the loop is unsafe and thus __cn should not be detached.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_CONTAINER(1, c, n) {
    <user code>
}
```

**Parameters**

- __sl – A pointer on a sys_sflist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __n – The field name of sys_sfnode_t within the container struct

---

SYS_SFLIST_FOR_EACH_CONTAINER_SAFE(__sl, __cn, __cns, __n)

Provide the primitive to safely iterate on a list under a container. Note: __cn can be detached, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_SFLIST_FOR_EACH_NODE_SAFE(l, c, cn, n) {
    <user code>
}
```

**Parameters**

- __sl – A pointer on a sys_sflist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __cns – A pointer for the loop to run safely
- __n – The field name of sys_sfnode_t within the container struct
SYS_SFLIST_STATIC_INIT(ptr_to_list)

SYS_SFLIST_FLAGS_MASK

Functions

static inline void sys_sflist_init(sys_sflist_t *list)
Initialize a list.

Parameters

- list – A pointer on the list to initialize

static inline uint8_t sys_sfnode_flags_get(sys_sfnode_t *node)
Fetch flags value for a particular sfnode.

Parameters

- node – A pointer to the node to fetch flags from

Returns

The value of flags, which will be between 0 and 3

static inline sys_sfnode_t *sys_sflist_peek_head(sys_sflist_t *list)
Peek the first node from the list.

Parameters

- list – A point on the list to peek the first node from

Returns

A pointer on the first node of the list (or NULL if none)

static inline sys_sfnode_t *sys_sflist_peek_tail(sys_sflist_t *list)
Peek the last node from the list.

Parameters

- list – A point on the list to peek the last node from

Returns

A pointer on the last node of the list (or NULL if none)

static inline void sys_sfnode_init(sys_sfnode_t *node, uint8_t flags)
Initialize an sflist node.

Set an initial flags value for this slist node, which can be a value between 0 and 3. These flags will persist even if the node is moved around within a list, removed, or transplanted to a different slist.

This is ever so slightly faster than sys_sfnode_flags_set() and should only be used on a node that hasn’t been added to any list.

Parameters

- node – A pointer to the node to set the flags on
- flags – A value between 0 and 3 to set the flags value

static inline void sys_sfnode_flags_set(sys_sfnode_t *node, uint8_t flags)
Set flags value for an sfnode.

Set a flags value for this slist node, which can be a value between 0 and 3. These flags will persist even if the node is moved around within a list, removed, or transplanted to a different slist.

Parameters
• node – A pointer to the node to set the flags on
• flags – A value between 0 and 3 to set the flags value

static inline bool sys_sflist_is_empty(sys_sflist_t *list)
Test if the given list is empty.

Parameters
• list – A pointer on the list to test

Returns
a boolean, true if it’s empty, false otherwise

static inline sys_sfnode_t *sys_sflist_peek_next_no_check(sys_sfnode_t *node)
Peek the next node from current node, node is not NULL.
Faster then sys_sflist_peek_next() if node is known not to be NULL.

Parameters
• node – A pointer on the node where to peek the next node

Returns
a pointer on the next node (or NULL if none)

static inline void sys_sflist_prepend(sys_sflist_t *list, sys_sfnode_t *node)
Prepend a node to the given list.
This and other sys_sflist_*() functions are not thread safe.

Parameters
• list – A pointer on the list to affect
• node – A pointer on the node to prepend

static inline void sys_sflist_append(sys_sflist_t *list, sys_sfnode_t *node)
Append a node to the given list.
This and other sys_sflist_*() functions are not thread safe.

Parameters
• list – A pointer on the list to affect
• node – A pointer on the node to append

static inline void sys_sflist_append_list(sys_sflist_t *list, void *head, void *tail)
Append a list to the given list.
Append a singly-linked, NULL-terminated list consisting of nodes containing the pointer to the
next node as the first element of a node, to list. This and other sys_sflist_*() functions are not
thread safe.

FIXME: Why are the element parameters void *?

Parameters
• list – A pointer on the list to affect
• head – A pointer to the first element of the list to append
tail – A pointer to the last element of the list to append

static inline void sys_sflist_merge_sflist(sys_sflist_t *list, sys_sflist_t *list_to_append)
merge two sflists, appending the second one to the first

When the operation is completed, the appending list is empty. This and other sys_sflist_*() functions are not thread safe.

Parameters

• list – A pointer on the list to affect
• list_to_append – A pointer to the list to append.

static inline void sys_sflist_insert(sys_sflist_t *list, sys_sfnode_t *prev, sys_sfnode_t *node)
Insert a node to the given list.

This and other sys_sflist_*() functions are not thread safe.

Parameters

• list – A pointer on the list to affect
• prev – A pointer on the previous node
• node – A pointer on the node to insert

static inline sys_sfnode_t *sys_sflist_get_not_empty(sys_sflist_t *list)
Fetch and remove the first node of the given list.

List must be known to be non-empty. This and other sys_sflist_*() functions are not thread safe.

Parameters

• list – A pointer on the list to affect

Returns

A pointer to the first node of the list

static inline sys_sfnode_t *sys_sflist_get(sys_sflist_t *list)
Fetch and remove the first node of the given list.

This and other sys_sflist_*() functions are not thread safe.

Parameters

• list – A pointer on the list to affect

Returns

A pointer to the first node of the list (or NULL if empty)

static inline void sys_sflist_remove(sys_sflist_t *list, sys_sfnode_t *prev_node, sys_sfnode_t *node)
Remove a node.

This and other sys_sflist_*() functions are not thread safe.

Parameters

• list – A pointer on the list to affect
• prev_node – A pointer on the previous node (can be NULL, which means the node is the list’s head)
• node – A pointer on the node to remove

static inline bool sys_sflist_find_and_remove(sys_sflist_t *list, sys_sfnode_t *node)
Find and remove a node from a list.

This and other sys_sflist_*() functions are not thread safe.
Parameters

- `list` – A pointer on the list to affect
- `node` – A pointer on the node to remove from the list

Returns

true if node was removed

### 3.5.2 Double-linked List

Similar to the single-linked list in many respects, Zephyr includes a double-linked implementation. This provides the same algorithmic behavior for all the existing slist operations, but also allows for constant-time removal and insertion (at all points: before or after the head, tail or any internal node). To do this, the list stores two pointers per node, and thus has somewhat higher runtime code and memory space needs.

A `sys_dlist_t` struct may be instantiated by the user in any accessible memory. It must be initialized with `sys_dlist_init()` or `SYS_DLIST_STATIC_INIT` before use. The `sys_dnode_t` struct is expected to be provided by the user for any nodes added to the list (typically embedded within the struct to be tracked, as described above). It must be initialized in zeroed/bss memory or with `sys_dnode_init()` before use.

Primitive operations may retrieve the head/tail of a list and the next/prev pointers of a node with `sys_dlist_peek_head()`, `sys_dlist_peek_tail()`, `sys_dlist_peek_next()` and `sys_dlist_peek_prev()`. These can all return NULL where appropriate (i.e. for empty lists, or nodes at the endpoints of the list).

A dlist can be modified in constant time by removing a node with `sys_dlist_remove()`, by adding a node to the head or tail of a list with `sys_dlist_prepend()` and `sys_dlist_append()`, or by inserting a node before an existing node with `sys_dlist_insert()`.

As for slist, each node in a dlist can be processed in a natural code block style using `SYS_DLIST_FOR_EACH_NODE`. This macro also exists in a “FROM_NODE” form which allows for iterating from a known starting point, a “SAFE” variant that allows for removing the node being inspected within the code block, a “CONTAINER” style that provides the pointer to a containing struct instead of the raw node, and a “CONTAINER_SAFE” variant that provides both properties.

Convenience utilities provided by dlist include `sys_dlist_insert_at()`, which inserts a node that linearly searches through a list to find the right insertion point, which is provided by the user as a C callback function pointer, and `sys_dnode_is_linked()`, which will affirmatively return whether or not a node is currently linked into a dlist or not (via an implementation that has zero overhead vs. the normal list processing).

**Double-linked List Internals**

Internally, the dlist implementation is minimal: the `sys_dlist_t` struct contains “head” and “tail” pointer fields, the `sys_dnode_t` contains “prev” and “next” pointers, and no other data is stored. But in practice the two structs are internally identical, and the list struct is inserted as a node into the list itself. This allows for a very clean symmetry of operations:

- An empty list has backpointers to itself in the list struct, which can be trivially detected.
- The head and tail of the list can be detected by comparing the prev/next pointers of a node vs. the list struct address.
- An insertion or deletion never needs to check for the special case of inserting at the head or tail. There are never any NULL pointers within the list to be avoided. Exactly the same operations are run, without tests or branches, for all list modification primitives.

Effectively, a dlist of N nodes can be thought of as a “ring” of “N+1” nodes, where one node represents the list tracking struct.
Fig. 3.6: A dlist containing three elements. Note that the list struct appears as a fourth “element” in the list.

Fig. 3.7: An dlist containing just one element.

Fig. 3.8: An empty dlist.
Doubly-linked List API Reference

group doubly-linked-list_apis

Defines

SYS_DLIST_FOR_EACH_NODE(__dl, __dn)

Provide the primitive to iterate on a list Note: the loop is unsafe and thus __dn should not be removed.

User MUST add the loop statement curly braces enclosing its own code:

SYS_DLIST_FOR_EACH_NODE(l, n) {
    <user code>
}

This and other SYS_DLIST_*() macros are not thread safe.

Parameters

- __dl – A pointer on a sys_dlist_t to iterate on
- __dn – A sys_dnode_t pointer to peek each node of the list

SYS_DLIST_ITERATE_FROM_NODE(__dl, __dn)

Provide the primitive to iterate on a list, from a node in the list Note: the loop is unsafe and thus __dn should not be removed.

User MUST add the loop statement curly braces enclosing its own code:

SYS_DLIST_ITERATE_FROM_NODE(l, n) {
    <user code>
}

Like SYS_DLIST_FOR_EACH_NODE(), but __dn already contains a node in the list where to start searching for the next entry from. If NULL, it starts from the head.

This and other SYS_DLIST_*() macros are not thread safe.

Parameters

- __dl – A pointer on a sys_dlist_t to iterate on
- __dn – A sys_dnode_t pointer to peek each node of the list; it contains the starting node, or NULL to start from the head

SYS_DLIST_FOR_EACH_NODE_SAFE(__dl, __dn, __dns)

Provide the primitive to safely iterate on a list Note: __dn can be removed, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

SYS_DLIST_FOR_EACH_NODE_SAFE(l, n, s) {
    <user code>
}

This and other SYS_DLIST_*() macros are not thread safe.

Parameters

- __dl – A pointer on a sys_dlist_t to iterate on
- __dn – A sys_dnode_t pointer to peek each node of the list
• __dns – A sys_dnode_t pointer for the loop to run safely

```c
SYS_DLST_CONTAINER(__dn, __cn, __n)
SYS_DLST_PEEK_HEAD_CONTAINER(__dl, __cn, __n)
SYS_DLST_PEEK_NEXT_CONTAINER(__dl, __cn, __n)
SYS_DLST_FOR_EACH_CONTAINER(__dl, __cn, __n)
```

Provide the primitive to iterate on a list under a container. Note: the loop is unsafe and thus __cn should not be detached.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_DLST_FOR_EACH_CONTAINER(1, c, n) {
    <user code>
}
```

**Parameters**

- __dl – A pointer on a sys_dlist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __n – The field name of sys_dnode_t within the container struct

```c
SYS_DLST_FOR_EACH_CONTAINER_SAFE(__dl, __cn, __cns, __n)
```

Provide the primitive to safely iterate on a list under a container. Note: __cn can be detached, it will not break the loop.

User MUST add the loop statement curly braces enclosing its own code:

```c
SYS_DLST_FOR_EACH_CONTAINER_SAFE(1, c, cn, n) {
    <user code>
}
```

**Parameters**

- __dl – A pointer on a sys_dlist_t to iterate on
- __cn – A pointer to peek each entry of the list
- __cns – A pointer for the loop to run safely
- __n – The field name of sys_dnode_t within the container struct

```c
SYS_DLST_STATIC_INIT(ptr_to_list)
```

**Typedefs**

typedef struct _dnode sys_dlist_t

typedef struct _dnode sys_dnode_t

**Functions**
static inline void sys_dlist_init(sys_dlist_t *list)
initialize list to its empty state

Parameters
• list – the doubly-linked list

static inline void sys_dnode_init(sys_dnode_t *node)
initialize node to its state when not in a list

Parameters
• node – the node

static inline bool sys_dnode_is_linked(const sys_dnode_t *node)
check if a node is a member of any list

Parameters
• node – the node

Returns
true if node is linked into a list, false if it is not

static inline bool sys_dlist_is_head(sys_dlist_t *list, sys_dnode_t *node)
check if a node is the list's head

Parameters
• list – the doubly-linked list to operate on
• node – the node to check

Returns
true if node is the head, false otherwise

static inline bool sys_dlist_is_tail(sys_dlist_t *list, sys_dnode_t *node)
check if a node is the list's tail

Parameters
• list – the doubly-linked list to operate on
• node – the node to check

Returns
true if node is the tail, false otherwise

static inline bool sys_dlist_is_empty(sys_dlist_t *list)
check if the list is empty

Parameters
• list – the doubly-linked list to operate on

Returns
true if empty, false otherwise

static inline bool sys_dlist_has_multiple_nodes(sys_dlist_t *list)
check if more than one node present

This and other sys_dlist_() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on

Returns
ture if multiple nodes, false otherwise
static inline sys_dnode_t *sys_dlist_peek_head(sys_dlist_t *list)
    get a reference to the head item in the list

Parameters
• list – the doubly-linked list to operate on

Returns
a pointer to the head element, NULL if list is empty

static inline sys_dnode_t *sys_dlist_peek_head_not_empty(sys_dlist_t *list)
    get a reference to the head item in the list

The list must be known to be non-empty.

Parameters
• list – the doubly-linked list to operate on

Returns
a pointer to the head element

static inline sys_dnode_t *sys_dlist_peek_next_no_check(sys_dlist_t *list, sys_dnode_t *node)
    get a reference to the next item in the list, node is not NULL.

Faster than sys_dlist_peek_next() if node is known not to be NULL.

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the next element in the list

Returns
a pointer to the next element from a node, NULL if node is the tail

static inline sys_dnode_t *sys_dlist_peek_next(sys_dlist_t *list, sys_dnode_t *node)
    get a reference to the next item in the list

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the next element in the list

Returns
a pointer to the next element from a node, NULL if node is the tail or NULL (when node comes from reading the head of an empty list).

static inline sys_dnode_t *sys_dlist_peek_prev_no_check(sys_dlist_t *list, sys_dnode_t *node)
    get a reference to the previous item in the list, node is not NULL.

Faster than sys_dlist_peek_prev() if node is known not to be NULL.

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the previous element in the list

Returns
a pointer to the previous element from a node, NULL if node is the tail

static inline sys_dnode_t *sys_dlist_peek_prev(sys_dlist_t *list, sys_dnode_t *node)
    get a reference to the previous item in the list

Parameters
• list – the doubly-linked list to operate on
• node – the node from which to get the previous element in the list
Returns
a pointer to the previous element from a node, NULL if node is the tail or NULL
(when node comes from reading the head of an empty list).

static inline sys_dnode_t *sys_dlist_peek_tail(sys_dlist_t *list)
get a reference to the tail item in the list

Parameters
• list – the doubly-linked list to operate on

Returns
a pointer to the tail element, NULL if list is empty

static inline void sys_dlist_append(sys_dlist_t *list, sys_dnode_t *node)
add node to tail of list

This and other sys_dlist_*() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on
• node – the element to append

static inline void sys_dlist_prepend(sys_dlist_t *list, sys_dnode_t *node)
add node to head of list

This and other sys_dlist_*() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on
• node – the element to append

static inline void sys_dlist_insert(sys_dnode_t *successor, sys_dnode_t *node)
Insert a node into a list.

Insert a node before a specified node in a dlist.

Parameters
• successor – the position before which “node” will be inserted
• node – the element to insert

static inline void sys_dlist_insert_at(sys_dlist_t *list, sys_dnode_t *node, int (*cond)(sys_dnode_t *node, void *data), void *data)
insert node at position

Insert a node in a location depending on a external condition. The cond() function checks if
the node is to be inserted before the current node against which it is checked. This and other
sys_dlist_*() functions are not thread safe.

Parameters
• list – the doubly-linked list to operate on
• node – the element to insert
• cond – a function that determines if the current node is the correct insert point
• data – parameter to cond()

static inline void sys_dlist_remove(sys_dnode_t *node)
remove a specific node from a list

The list is implicit from the node. The node must be part of a list. This and other sys_dlist_*() functions are not thread safe.
Parameters

- node – the node to remove

static inline sys_dnode_t *sys_dlist_get(sys_dlist_t *list)

get the first node in a list

This and other sys_dlist_*() functions are not thread safe.

Parameters

- list – the doubly-linked list to operate on

Returns

the first node in the list, NULL if list is empty

3.5.3 Multi Producer Single Consumer Packet Buffer

A Multi Producer Single Consumer Packet Buffer (MPSC_PBUF) is a circular buffer, whose contents are stored in first-in-first-out order. Variable size packets are stored in the buffer. Packet buffer works under assumption that there is a single context that consumes the data. However, it is possible that another context may interfere to flush the data and never come back (panic case). Packet is produced in two steps: first requested amount of data is allocated, producer fills the data and commits it. Consuming a packet is also performed in two steps: consumer claims the packet, gets pointer to it and length and later on packet is freed. This approach reduces memory copying.

A MPSC Packet Buffer has the following key properties:

- Allocate, commit scheme used for packet producing.
- Claim, free scheme used for packet consuming.
- Allocator ensures that contiguous memory of requested length is allocated.
- Following policies can be applied when requested space cannot be allocated:
  - **Overwrite**: oldest entries are dropped until requested amount of memory can be allocated. For each dropped packet user callback is called.
  - **No overwrite**: When requested amount of space cannot be allocated, allocation fails.
- Dedicated, optimized API for storing short packets.
- Allocation with timeout.

Internals

Each packet in the buffer contains MPSC_PBUF specific header which is used for internal management. Header consists of 2 bit flags. In order to optimize memory usage, header can be added on top of the user header using MPSC_PBUF_HDR and remaining bits in the first word can be application specific. Header consists of following flags:

- valid - bit set to one when packet contains valid user packet
- busy - bit set when packet is being consumed (claimed but not free)

Header state:

<table>
<thead>
<tr>
<th>valid</th>
<th>busy</th>
<th>description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>space is free</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>valid packet</td>
</tr>
<tr>
<td>1</td>
<td>1</td>
<td>claimed valid packet</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>internal skip packet</td>
</tr>
</tbody>
</table>

3.5. Data Structures
Packet buffer space contains free space, valid user packets and internal skip packets. Internal skip packets indicates padding, e.g. at the of the buffer.

**Allocation**  Using pairs for read and write indexes, available space is determined. If space can be allocated, temporary write index is moved and pointer to a space within buffer is returned. Packet header is reset. If allocation required wrapping of the write index, a skip packet is added to the end of buffer. If space cannot be allocated and overwrite is disabled then NULL pointer is returned or context blocks if allocation was with timeout.

**Allocation with overwrite**  If overwrite is enabled, oldest packets are dropped until requested amount of space can be allocated. When packets are dropped busy flag is checked in the header to ensure that currently consumed packet is not overwritten. In that case, skip packet is added before busy packet and packets following the busy packet are dropped. When busy packet is being freed, such situation is detected and packet is converted to skip packet to avoid double processing.

**Usage**

**Packet header definition**  Packet header details can be found in include/zephyr/sys/mpsc_packet.h. API functions can be found in include/zephyr/sys/mpsc_pbuf.h. Headers are split to avoid include spam when declaring the packet.

User header structure must start with internal header:

```c
#include <zephyr/sys/mpsc_packet.h>

struct foo_header {
    MPSC_PBUF_HDR;
    uint32_t length: 32 - MPSC_PBUF_HDR_BITS;
};
```

**Packet buffer configuration**  Configuration structure contains buffer details, configuration flags and callbacks. Following callbacks are used by the packet buffer:

- Drop notification - callback called whenever a packet is dropped due to overwrite.
- Get packet length - callback to determine packet length

**Packet producing**  Standard, two step method:

```c
foo_packet *packet = mpsc_pbuf_alloc(buffer, len, K_NO_WAIT);
fill_data(packet);
mpsc_pbuf_commit(buffer, packet);
```

Performance optimized storing of small packets:

- 32 bit word packet
- 32 bit word with pointer packet

Note that since packets are written by value, they should already contain valid bit set in the header.

```c
mpsc_pbuf_put_word(buffer, data);
mpsc_pbuf_put_word_ext(buffer, data, ptr);
```
Packet consuming  Two step method:

```c
foo_packet *packet = mpsc_pbuf_claim(buffer);
process(packet);
mpsc_pbuf_free(buffer, packet);
```

### 3.5.4 Single Producer Single Consumer Packet Buffer

A Single Producer Single Consumer Packet Buffer (SPSC_PBUF) is a circular buffer, whose contents are stored in first-in-first-out order. Variable size packets are stored in the buffer. Packet buffer works under assumption that there is a single context that produces packets and a single context that consumes the data.

Implementation is focused on performance and memory footprint.

Packets are added to the buffer using `spsc_pbuf_write()` which copies a data into the buffer. If the buffer is full error is returned.

Packets are copied out of the buffer using `spsc_pbuf_read()`.

### 3.5.5 Balanced Red/Black Tree

For circumstances where sorted containers may become large at runtime, a list becomes problematic due to algorithmic costs of searching it. For these situations, Zephyr provides a balanced tree implementation which has runtimes on search and removal operations bounded at $O(\log_2(N))$ for a tree of size $N$. This is implemented using a conventional red/black tree as described by multiple academic sources.

The `rbtree` tracking struct for a rbtree may be initialized anywhere in user accessible memory. It should contain only zero bits before first use. No specific initialization API is needed or required.

Unlike a list, where position is explicit, the ordering of nodes within an rbtree must be provided as a predicate function by the user. A function of type `rb_lessthan_t()` should be assigned to the `lessthan_fn` field of the `rbtree` struct before any tree operations are attempted. This function should, as its name suggests, return a boolean True value if the first node argument is “less than” the second in the ordering desired by the tree. Note that “equal” is not allowed, nodes within a tree must have a single fixed order for the algorithm to work correctly.

As with the slist and dlist containers, nodes within an rbtree are represented as a `rbnode` structure which exists in user-managed memory, typically embedded within the the data structure being tracked in the tree. Unlike the list code, the data within an rbnode is entirely opaque. It is not possible for the user to extract the binary tree topology and “manually” traverse the tree as it is for a list.

Nodes can be inserted into a tree with `rb_insert()` and removed with `rb_remove()`. Access to the “first” and “last” nodes within a tree (in the sense of the order defined by the comparison function) is provided by `rb_get_min()` and `rb_get_max()`. There is also a predicate, `rb_contains()`, which returns a boolean True if the provided node pointer exists as an element within the tree. As described above, all of these routines are guaranteed to have at most log time complexity in the size of the tree.

There are two mechanisms provided for enumerating all elements in an rbtree. The first, `rb_walk()`, is a simple callback implementation where the caller specifies a C function pointer and an untyped argument to be passed to it, and the tree code calls that function for each node in order. This has the advantage of a very simple implementation, at the cost of a somewhat more cumbersome API for the user (not unlike ISO C’s `bsearch()` routine). It is a recursive implementation, however, and is thus not always available in environments that forbid the use of unbounded stack techniques like recursion.

There is also a `RB_FOR_EACH` iterator provided, which, like the similar APIs for the lists, works to iterate over a list in a more natural way, using a nested code block instead of a callback. It is also nonrecursive, though it requires log-sized space on the stack by default (however, this can be configured to use a...
fixed/maximally size buffer instead where needed to avoid the dynamic allocation). As with the lists, this is also available in a `RB_FOR_EACH_CONTAINER` variant which enumerates using a pointer to a container field and not the raw node pointer.

**Tree Internals**

As described, the Zephyr rbtree implementation is a conventional red/black tree as described pervasively in academic sources. Low level details about the algorithm are out of scope for this document, as they match existing conventions. This discussion will be limited to details notable or specific to the Zephyr implementation.

The core invariant guaranteed by the tree is that the path from the root of the tree to any leaf is no more than twice as long as the path to any other leaf. This is achieved by associating one bit of “color” with each node, either red or black, and enforcing a rule that no red child can be a child of another red child (i.e. that the number of black nodes on any path to the root must be the same, and that no more than that number of “extra” red nodes may be present). This rule is enforced by a set of rotation rules used to “fix” trees following modification.

![Tree Internals Diagram](image)

**Fig. 3.9:** A maximally unbalanced rbtree with a black height of two. No more nodes can be added underneath the rightmost node without rebalancing.

These rotations are conceptually implemented on top of a primitive that “swaps” the position of one node with another in the list. Typical implementations effect this by simply swapping the nodes internal “data” pointers, but because the Zephyr `rbn`ode is intrusive, that cannot work. Zephyr must include somewhat more elaborate code to handle the edge cases (for example, one swapped node can be the root, or the two may already be parent/child).

The `rbn`ode struct for a Zephyr rbtree contains only two pointers, representing the “left”, and “right” children of a node within the binary tree. Traversal of a tree for rebalancing following modification,
however, routinely requires the ability to iterate “upwards” from a node as well. It is very common for red/black trees in the industry to store a third “parent” pointer for this purpose. Zephyr avoids this requirement by building a “stack” of node pointers locally as it traverses downward through the tree and updating it appropriately as modifications are made. So a Zephyr rbtree can be implemented with no more runtime storage overhead than a dlist.

These properties, of a balanced tree data structure that works with only two pointers of data per node and that works without any need for a memory allocation API, are quite rare in the industry and are somewhat unique to Zephyr.

Red/Black Tree API Reference

\texttt{group rbtree\_apis}

\textbf{Defines}

\texttt{RB\_FOR\_EACH}(tree, node)

Walk a tree in-order without recursing.

While \texttt{rb\_walk()} is very simple, recursing on the C stack can be clumsy for some purposes and on some architectures wastes significant memory in stack frames. This macro implements a non-recursive “foreach” loop that can iterate directly on the tree, at a moderate cost in code size.

Note that the resulting loop is not safe against modifications to the tree. Changes to the tree structure during the loop will produce incorrect results, as nodes may be skipped or duplicated. Unlike linked lists, no \texttt{SAFE} variant exists.

Note also that the macro expands its arguments multiple times, so they should not be expressions with side effects.

\textbf{Parameters}

- tree – A pointer to a struct rbtree to walk
- node – The symbol name of a local struct rbnode* variable to use as the iterator

\texttt{RB\_FOR\_EACH\_CONTAINER}(tree, node, field)

Loop over rbtree with implicit container field logic.

As for \texttt{RB\_FOR\_EACH()}, but “node” can have an arbitrary type containing a struct rbnode.

\textbf{Parameters}

- tree – A pointer to a struct rbtree to walk
- node – The symbol name of a local iterator
- field – The field name of a struct rbnode inside node

\textbf{Typedefs}

typedef bool (*\texttt{rb\_lessthan\_t})(struct rbnode *a, struct rbnode *b)

Red/black tree comparison predicate.

Compares the two nodes and returns true if node A is strictly less than B according to the tree’s sorting criteria, false otherwise.

Note that during insert, the new node being inserted will always be “A”, where “B” is the existing node within the tree against which it is being compared. This trait can be used
(with care!) to implement “most/least recently added” semantics between nodes which would otherwise compare as equal.

typedef void (*rb_visit_t)(struct rbnode *node, void *cookie)

Functions

void rb_insert(struct rbtree *tree, struct rbnode *node)
    Insert node into tree.
void rb_remove(struct rbtree *tree, struct rbnode *node)
    Remove node from tree.
static inline struct rbnode *rb_get_min(struct rbtree *tree)
    Returns the lowest-sorted member of the tree.
static inline struct rbnode *rb_get_max(struct rbtree *tree)
    Returns the highest-sorted member of the tree.
bool rb_contains(struct rbtree *tree, struct rbnode *node)
    Returns true if the given node is part of the tree.
    Note that this does not internally dereference the node pointer (though the tree's lessthan callback might!), it just tests it for equality with items in the tree. So it's feasible to use this to implement a "set" construct by simply testing the pointer value itself.
static inline void rb_walk(struct rbtree *tree, rb_visit_t visit_fn, void *cookie)
    Walk/enumerate a rbtree.
    Very simple recursive enumeration. Low code size, but requiring a separate function can be clumsy for the user and there is no way to break out of the loop early. See RB_FOR_EACH for an iterative implementation.

struct rbtree
    #include <rb.h>

3.5.6 Ring Buffers

A ring buffer is a circular buffer, whose contents are stored in first-in-first-out order.

For circumstances where an application needs to implement asynchronous “streaming” copying of data, Zephyr provides a struct ring_buf abstraction to manage copies of such data in and out of a shared buffer of memory.

Two content data modes are supported:

- **Byte mode**: raw bytes can be enqueued and dequeued.
- **Data item mode**: Multiple 32-bit word data items with metadata can be enqueued and dequeued from the ring buffer in chunks of up to 1020 bytes. Each data item also has two associated metadata values: a type identifier and a 16-bit integer value, both of which are application-specific.

While the underlying data structure is the same, it is not legal to mix these two modes on a single ring buffer instance. A ring buffer initialized with a byte count must be used only with the “bytes” API, one initialized with a word count must use the “items” calls.

- **Concepts**
  - **Byte mode**
Any number of ring buffers can be defined (limited only by available RAM). Each ring buffer is referenced by its memory address.

A ring buffer has the following key properties:

- A **data buffer** of bytes or 32-bit words. The data buffer contains the raw bytes or 32-bit words that have been added to the ring buffer but not yet removed.

- A **data buffer size**, measured in bytes or 32-byte words. This governs the maximum amount of data (including possible metadata values) the ring buffer can hold.

A ring buffer must be initialized before it can be used. This sets its data buffer to empty.

A struct `ring_buf` may be placed anywhere in user-accessible memory, and must be initialized with `ring_buf_init()` or `ring_buf_element_init()` before use. This must be provided a region of user-controlled memory for use as the buffer itself. Note carefully that the units of the size of the buffer passed change (either bytes or words) depending on how the ring buffer will be used later. Macros for combining these steps in a single static declaration exist for convenience. `RING_BUF_DECLARE` will declare and statically initialize a ring buffer with a specified byte count, where `RING_BUF_ITEM_DECLARE` will declare and statically initialize a buffer with a given count of 32 bit words. `RING_BUF_ITEM_SIZEOF` will compute the size in 32-bit words corresponding to a type or an expression. Note: rounds up if the size is not a multiple of 32 bits.

“Bytes” data may be copied into the ring buffer using `ring_buf_put()`, passing a data pointer and byte count. These bytes will be copied into the buffer in order, as many as will fit in the allocated buffer. The total number of bytes copied (which may be fewer than provided) will be returned. Likewise `ring_buf_get()` will copy bytes out of the ring buffer in the order that they were written, into a user-provided buffer, returning the number of bytes that were transferred.

To avoid multiply-copied-data situations, a “claim” API exists for byte mode. `ring_buf_put_claim()` takes a byte size value from the user and returns a pointer to memory internal to the ring buffer that can be used to receive those bytes, along with a size of the contiguous internal region (which may be smaller than requested). The user can then copy data into that region at a later time without assembling all the bytes in a single region first. When complete, `ring_buf_put_finish()` can be used to signal the buffer that the transfer is complete, passing the number of bytes actually transferred. At this point a new transfer can be initiated. Similarly, `ring_buf_get_claim()` returns a pointer to internal ring buffer data from which the user can read without making a verbatim copy, and `ring_buf_get_finish()` signals the buffer with how many bytes have been consumed and allows for a new transfer to begin.

“Items” mode works similarly to bytes mode, except that all transfers are in units of 32 bit words and all memory is assumed to be aligned on 32 bit boundaries. The write and read operations are `ring_buf_item_put()` and `ring_buf_item_get()`, and work otherwise identically to the bytes mode APIs. There no “claim” API provided for items mode. One important difference is that unlike...
**ring_buf_put()**, **ring_buf_item_put()** will not do a partial transfer; it will return an error in the case where the provided data does not fit in its entirety.

The user can manage the capacity of a ring buffer without modifying it using either **ring_buf_space_get()** or **ring_buf_item_space_get()** which returns the number of free bytes or free 32-bit item words respectively, or by testing the **ring_buf_is_empty()** predicate.

Finally, a **ring_buf_reset()** call exists to immediately empty a ring buffer, discarding the tracking of any bytes or items already written to the buffer. It does not modify the memory contents of the buffer itself, however.

**Byte mode** A byte mode ring buffer instance is declared using **RING_BUF_DECLARE()** and accessed using: **ring_buf_put_claim()**, **ring_buf_put_finish()**, **ring_buf_get_claim()**, **ring_buf_get_finish()**, **ring_buf_put()** and **ring_buf_get()**.

Data can be copied into the ring buffer (see **ring_buf_put()**) or ring buffer memory can be used directly by the user. In the latter case, the operation is split into three stages:

1. allocating the buffer (**ring_buf_put_claim()**) when user requests the destination location where data can be written.
2. writing the data by the user (e.g. buffer written by DMA).
3. indicating the amount of data written to the provided buffer (**ring_buf_put_finish()**). The amount can be less than or equal to the allocated amount.

Data can be retrieved from a ring buffer through copying (see **ring_buf_get()**) or accessed directly by address. In the latter case, the operation is split into three stages:

1. retrieving source location with valid data written to a ring buffer (see **ring_buf_get_claim()**).
2. processing data
3. freeing processed data (see **ring_buf_get_finish()**). The amount freed can be less than or equal to the retrieved amount.

**Data item mode** A data item mode ring buffer instance is declared using **RING_BUF_ITEM_DECLARE()** and accessed using **ring_buf_item_put()** and **ring_buf_item_get()**.

A ring buffer data item is an array of 32-bit words from 0 to 1020 bytes in length. When a data item is **enqueued** (**ring_buf_item_put()**), its contents are copied to the data buffer, along with its associated metadata values (which occupy one additional 32-bit word). If the ring buffer has insufficient space to hold the new data item the enqueue operation fails.

A data item is **dequeued** (**ring_buf_item_get()**) from a ring buffer by removing the oldest enqueued item. The contents of the dequeued data item, as well as its two metadata values, are copied to areas supplied by the retriever. If the ring buffer is empty, or if the data array supplied by the retriever is not large enough to hold the data item's data, the dequeue operation fails.

**Concurrency** The ring buffer APIs do not provide any concurrency control. Depending on usage (particularly with respect to number of concurrent readers/writers) applications may need to protect the ring buffer with mutexes and/or use semaphores to notify consumers that there is data to read.

For the trivial case of one producer and one consumer, concurrency control shouldn’t be needed.

**Internal Operation** Data streamed through a ring buffer is always written to the next byte within the buffer, wrapping around to the first element after reaching the end, thus the “ring” structure. Internally, the struct **ring_buf** contains its own buffer pointer and its size, and also a set of “head” and “tail” indices representing where the next read and write operations may occur.

This boundary is invisible to the user using the normal put/get APIs, but becomes a barrier to the “claim” API, because obviously no contiguous region can be returned that crosses the end of the buffer. This
can be surprising to application code, and produce performance artifacts when transfers need to happen close to the end of the buffer, as the number of calls to claim/finish needs to double for such transfers.

**Implementation**

**Defining a Ring Buffer**  A ring buffer is defined using a variable of type `ring_buf`. It must then be initialized by calling `ring_buf_init()` or `ring_buf_item_init()`.

The following code defines and initializes an empty **data item mode** ring buffer (which is part of a larger data structure). The ring buffer's data buffer is capable of holding 64 words of data and metadata information.

```c
#define MY_RING_BUF_WORDS 64

struct my_struct {  
    struct ring_buf rb;  
    uint32_t buffer[MY_RING_BUF_WORDS];  
    ...  
};

struct my_struct ms;

void init_my_struct {  
    ring_buf_item_init(&ms.rb, MY_RING_BUF_WORDS, ms.buffer);  
    ...  
}
```

Alternatively, a ring buffer can be defined and initialized at compile time using one of two macros at file scope. Each macro defines both the ring buffer itself and its data buffer.

The following code defines a **data item mode** ring buffer:

```c
#define MY_RING_BUF_WORDS 93
RING_BUF_ITEM_DECLARE(my_ring_buf, MY_RING_BUF_WORDS);
```

The following code defines a ring buffer intended to be used for raw bytes:

```c
#define MY_RING_BUF_BYTES 93
RING_BUF_DECLARE(my_ring_buf, MY_RING_BUF_BYTES);
```

**Enqueuing Data**  Bytes are copied to a **byte mode** ring buffer by calling `ring_buf_put()`.

```c
uint8_t my_data[MY_RING_BUF_BYTES];
uint32_t ret;

ret = ring_buf_put(&ring_buf, my_data, MY_RING_BUF_BYTES);
if (ret != MY_RING_BUF_BYTES) {  
    /* not enough room, partial copy. */  
    ...  
}
```

Data can be added to a **byte mode** ring buffer by directly accessing the ring buffer’s memory. For example:

```c
uint32_t size;
uint32_t rx_size;
uint8_t *data;
int err;
```

(continues on next page)
/* Allocate buffer within a ring buffer memory. */
size = ring_buf_put_claim(&ring_buf, &data, MY_RING_BUF_BYTES);

/* Work directly on a ring buffer memory. */
rx_size = uart_rx(data, size);

/* Indicate amount of valid data. rx_size can be equal or less than size. */
err = ring_buf_put_finish(&ring_buf, rx_size);
if (err != 0) {
    /* This shouldn't happen unless rx_size > size */
    ...
}

A data item is added to a ring buffer by calling `ring_buf_item_put()`.

```c
uint32_t data[MY_DATA_WORDS];
int ret;
ret = ring_buf_item_put(&ring_buf, TYPE_FOO, 0, data, MY_DATA_WORDS);
if (ret == -EMSGSIZE) {
    /* not enough room for the data item */
    ...
}
```

If the data item requires only the type or application-specific integer value (i.e. it has no data array), a size of 0 and data pointer of `NULL` can be specified.

```c
int ret;
ret = ring_buf_item_put(&ring_buf, TYPE_BAR, 17, NULL, 0);
if (ret == -EMSGSIZE) {
    /* not enough room for the data item */
    ...
}
```

### Retrieving Data

Data bytes are copied out from a `byte mode` ring buffer by calling `ring_buf_get()`.

For example:

```c
uint8_t my_data[MY_DATA_BYTES];
size_t ret;
ret = ring_buf_get(&ring_buf, my_data, sizeof(my_data));
if (ret != sizeof(my_data)) {
    /* Fewer bytes copied. */
} else {
    /* Requested amount of bytes retrieved. */
    ...
}
```

Data can be retrieved from a `byte mode` ring buffer by direct operations on the ring buffer's memory.

For example:

```c
uint32_t size;
uint32_t proc_size;
uint8_t *data;
```
int err;

/* Get buffer within a ring buffer memory. */
size = ring_buf_get_claim(&ring_buf, &data, MY_RING_BUF_BYTES);

/* Work directly on a ring buffer memory. */
proc_size = process(data, size);

/* Indicate amount of data that can be freed. proc_size can be equal or less than size. */
err = ring_buf_get_finish(&ring_buf, proc_size);
if (err != 0) {
    /* proc_size exceeds amount of valid data in a ring buffer. */
    ...
}

A data item is removed from a ring buffer by calling ring_buf_item_get().

    uint32_t my_data[MY_DATA_WORDS];
    uint16_t my_type;
    uint8_t my_value;
    uint8_t my_size;
    int ret;

    my_size = MY_DATA_WORDS;
    ret = ring_buf_item_get(&ring_buf, &my_type, &my_value, my_data, &my_size);
    if (ret == -EMSGSIZE) {
        printk("Buffer is too small, need %d uint32_t\n", my_size);
    } else if (ret == -EAGAIN) {
        printk("Ring buffer is empty\n");
    } else {
        printk("Got item of type %u value %u of size %u dwords\n", 
            my_type, my_value, my_size);
            ...
    }

Configuration Options

Related configuration options:

- CONFIG_RING_BUFFER: Enable ring buffer.

API Reference

The following ring buffer APIs are provided by include/zephyr/sys/ring_buffer.h:

group ring_buffer_apis

Defines

RING_BUF_DECLARE(name, size8)
    Define and initialize a ring buffer for byte data.
This macro establishes a ring buffer of an arbitrary size. The basic storage unit is a byte. The ring buffer can be accessed outside the module where it is defined using:

```
extern struct ring_buf <name>;
```

**Parameters**
- `name` – Name of the ring buffer.
- `size8` – Size of ring buffer (in bytes).

```
RING_BUF_ITEM_DECLARE(name, size32)
```

Define and initialize an “item based” ring buffer.

This macro establishes an “item based” ring buffer. Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

The ring buffer can be accessed outside the module where it is defined using:

```
extern struct ring_buf <name>;
```

**Parameters**
- `name` – Name of the ring buffer.
- `size32` – Size of ring buffer (in 32-bit words).

```
RING_BUF_ITEM_DECLARE_SIZE(name, size32)
```

Define and initialize an “item based” ring buffer.

This exists for backward compatibility reasons. `RING_BUF_ITEM_DECLARE` should be used instead.

**Parameters**
- `name` – Name of the ring buffer.
- `size32` – Size of ring buffer (in 32-bit words).

```
RING_BUF_ITEM_DECLARE_POW2(name, pow)
```

Define and initialize a power-of-2 sized “item based” ring buffer.

This macro establishes an “item based” ring buffer by specifying its size using a power of 2. This exists mainly for backward compatibility reasons. `RING_BUF_ITEM_DECLARE` should be used instead.

**Parameters**
- `name` – Name of the ring buffer.
- `pow` – Ring buffer size exponent.

```
RING_BUF_ITEM_SIZEOF(expr)
```

Compute the ring buffer size in 32-bit needed to store an element.

The argument can be a type or an expression. Note: rounds up if the size is not a multiple of 32 bits.

**Parameters**
- `expr` – Expression or type to compute the size of
Functions

static inline void ring_buf_init(struct ring_buf *buf, uint32_t size, uint8_t *data)
Initialize a ring buffer for byte data.
This routine initializes a ring buffer, prior to its first use. It is only used for ring buffers not
defined using RING_BUF_DECLARE.

Parameters
- buf – Address of ring buffer.
- size – Ring buffer size (in bytes).
- data – Ring buffer data area (uint8_t data[size]).

static inline void ring_buf_item_init(struct ring_buf *buf, uint32_t size, uint32_t *data)
Initialize an “item based” ring buffer.
This routine initializes a ring buffer, prior to its first use. It is only used for ring buffers not
defined using RING_BUF_ITEM_DECLARE.
Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with
a 16-bit type identifier and an 8-bit integer value.
Each data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with
a 16-bit type identifier and an 8-bit integer value.

Parameters
- buf – Address of ring buffer.
- size – Ring buffer size (in 32-bit words)
- data – Ring buffer data area (uint32_t data[size]).

static inline bool ring_buf_is_empty(struct ring_buf *buf)
Determine if a ring buffer is empty.

Parameters
- buf – Address of ring buffer.

Returns
true if the ring buffer is empty, or false if not.

static inline void ring_buf_reset(struct ring_buf *buf)
Reset ring buffer state.

Parameters
- buf – Address of ring buffer.

static inline uint32_t ring_buf_space_get(struct ring_buf *buf)
Determine free space in a ring buffer.

Parameters
- buf – Address of ring buffer.

Returns
Ring buffer free space (in bytes).

static inline uint32_t ring_buf_item_space_get(struct ring_buf *buf)
Determine free space in an “item based” ring buffer.

Parameters
- buf – Address of ring buffer.
Returns
Ring buffer free space (in 32-bit words).

static inline uint32_t ring_buf_capacity_get(struct ring_buf *buf)
Return ring buffer capacity.

Parameters
• buf – Address of ring buffer.

Returns
Ring buffer capacity (in bytes).

static inline uint32_t ring_buf_size_get(struct ring_buf *buf)
Determine used space in a ring buffer.

Parameters
• buf – Address of ring buffer.

Returns
Ring buffer space used (in bytes).

uint32_t ring_buf_put_claim(struct ring_buf *buf, uint8_t **data, uint32_t size)
Allocate buffer for writing data to a ring buffer.
With this routine, memory copying can be reduced since internal ring buffer can be used
directly by the user. Once data is written to allocated area number of bytes written must be
confirmed (see ring_buf_put_finish).

Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent
write operations, either by preventing all writers from being preemted or by using a
mutex to govern writes to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item access (calls prefixed
with ring_buf_item_).

Parameters
• data – [out] Pointer to the address. It is set to a location within ring buffer.

Returns
Size of allocated buffer which can be smaller than requested if there is not enough
free space or buffer wraps.

int ring_buf_put_finish(struct ring_buf *buf, uint32_t size)
Indicate number of bytes written to allocated buffers.
The number of bytes must be equal to or lower than the sum corresponding to all preceding
ring_buf_put_claim invocations (or even 0). Surplus bytes will be returned to the available
free buffer space.

Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent
write operations, either by preventing all writers from being preemted or by using a
mutex to govern writes to the ring buffer.
Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters
• buf – Address of ring buffer.
• size – Number of valid bytes in the allocated buffers.

Return values
• 0 – Successful operation.
• -EINVAL – Provided size exceeds free space in the ring buffer.

```c
uint32_t ring_buf_put(struct ring_buf *buf, const uint8_t *data, uint32_t size)
```

Write (copy) data to a ring buffer.

This routine writes data to a ring buffer buf.

Warning: Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preempted or by using a mutex to govern writes to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters
• buf – Address of ring buffer.
• data – Address of data.
• size – Data size (in bytes).

Return values
Number – of bytes written.

```c
uint32_t ring_buf_get_claim(struct ring_buf *buf, uint8_t **data, uint32_t size)
```

Get address of a valid data in a ring buffer.

With this routine, memory copying can be reduced since internal ring buffer can be used directly by the user. Once data is processed it must be freed using ring_buf_get_finish.

Warning: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item access (calls prefixed with ring_buf_item_).

Parameters
• data – [out] Pointer to the address. It is set to a location within ring buffer.

3.5. Data Structures

Returns
Number of valid bytes in the provided buffer which can be smaller than requested if there is not enough free space or buffer wraps.

int ring_buf_get_finish(struct ring_buf *buf, uint32_t size)
Indicate number of bytes read from claimed buffer.
The number of bytes must be equal or lower than the sum corresponding to all preceding ring_buf_get_claim invocations (or even 0). Surplus bytes will remain available in the buffer.

Warning: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).

Parameters
• buf – Address of ring buffer.
• size – Number of bytes that can be freed.

Return values
• 0 – Successful operation.
• -EINVAL – Provided size exceeds valid bytes in the ring buffer.

uint32_t ring_buf_get(struct ring_buf *buf, uint8_t *data, uint32_t size)
Read data from a ring buffer.
This routine reads data from a ring buffer buf.

Warning: Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

Warning: Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).

Parameters
• buf – Address of ring buffer.
• data – Address of the output buffer. Can be NULL to discard data.
• size – Data size (in bytes).

Return values
Number – of bytes written to the output buffer.
uint32_t ring_buf_peek(struct ring_buf *buf, uint8_t *data, uint32_t size)
Peek at data from a ring buffer. This routine reads data from a ring buffer buf without removal.

**Warning:** Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preemptioned or by using a mutex to govern reads to the ring buffer.

**Warning:** Ring buffer instance should not mix byte access and item mode (calls prefixed with ring_buf_item_).

**Warning:** Multiple calls to peek will result in the same data being ‘peeked’ multiple times. To remove data, use either ring_buf_get or ring_buf_get_claim followed by ring_buf_get_finish with a non-zero size.

**Parameters**
- buf – Address of ring buffer.
- data – Address of the output buffer. Cannot be NULL.
- size – Data size (in bytes).

**Return values**
- Number – of bytes written to the output buffer.

int ring_buf_item_put(struct ring_buf *buf, uint16_t type, uint8_t value, uint32_t *data, uint8_t size32)
Write a data item to a ring buffer.

This routine writes a data item to ring buffer buf. The data item is an array of 32-bit words (from zero to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

**Warning:** Use cases involving multiple writers to the ring buffer must prevent concurrent write operations, either by preventing all writers from being preemptioned or by using a mutex to govern writes to the ring buffer.

**Parameters**
- buf – Address of ring buffer.
- type – Data item’s type identifier (application specific).
- value – Data item’s integer value (application specific).
- data – Address of data item.
- size32 – Data item size (number of 32-bit words).

**Return values**
- 0 – Data item was written.
- -EMSGSIZE – Ring buffer has insufficient free space.
int ring_buf_item_get(struct ring_buf *buf, uint16_t *type, uint8_t *value, uint32_t *data, uint8_t *size32)

Read a data item from a ring buffer.

This routine reads a data item from ring buffer buf. The data item is an array of 32-bit words (up to 1020 bytes in length), coupled with a 16-bit type identifier and an 8-bit integer value.

**Warning:** Use cases involving multiple reads of the ring buffer must prevent concurrent read operations, either by preventing all readers from being preempted or by using a mutex to govern reads to the ring buffer.

**Parameters**

- `buf` – Address of ring buffer.
- `type` – Area to store the data item’s type identifier.
- `value` – Area to store the data item’s integer value.
- `data` – Area to store the data item. Can be NULL to discard data.
- `size32` – Size of the data item storage area (number of 32-bit chunks).

**Return values**

- `0` – Data item was fetched; `size32` now contains the number of 32-bit words read into data area `data`.
- `-EAGAIN` – Ring buffer is empty.
- `-EMSGSIZE` – Data area `data` is too small; `size32` now contains the number of 32-bit words needed.

### 3.6 Executing Time Functions

The timing functions can be used to obtain execution time of a section of code to aid in analysis and optimization.

Please note that the timing functions may use a different timer than the default kernel timer, where the timer being used is specified by architecture, SoC or board configuration.

#### 3.6.1 Configuration

To allow using the timing functions, `CONFIG_TIMING_FUNCTIONS` needs to be enabled.

#### 3.6.2 Usage

To gather timing information:

1. Call `timing_init()` to initialize the timer.
2. Call `timing_start()` to signal the start of gathering of timing information. This usually starts the timer.
3. Call `timing_counter_get()` to mark the start of code execution.
4. Call `timing_counter_get()` to mark the end of code execution.
5. Call `timing_cycles_get()` to get the number of timer cycles between start and end of code execution.
6. Call `timing_cycles_to_ns()` with total number of cycles to convert number of cycles to nanoseconds.

7. Repeat from step 3 to gather timing information for other blocks of code.

8. Call `timing_stop()` to signal the end of gathering of timing information. This usually stops the timer.

**Example**

This shows an example on how to use the timing functions:

```c
#include <zephyr/timing/timing.h>

void gather_timing(void)
{
    timing_t start_time, end_time;
    uint64_t total_cycles;
    uint64_t total_ns;

    timing_init();
    timing_start();

    start_time = timing_counter_get();
    code_execution_to_beMeasured();
    end_time = timing_counter_get();

    total_cycles = timing_cycles_get(&start_time, &end_time);
    total_ns = timing_cycles_to_ns(total_cycles);

    timing_stop();
}
```

### 3.6.3 API documentation

#### group timing_api

Timing Measurement APIs.

#### Functions

- **void timing_init(void)**
  
  Initialize the timing subsystem.

  Perform the necessary steps to initialize the timing subsystem.

- **void timing_start(void)**
  
  Signal the start of the timing information gathering.

  Signal to the timing subsystem that timing information will be gathered from this point forward.
void timing_stop(void)
    Signal the end of the timing information gathering.
    Signal to the timing subsystem that timing information is no longer being gathered from this point forward.

static inline timing_t timing_counter_get(void)
    Return timing counter.

    Returns
    Timing counter.

static inline uint64_t timing_cycles_get(volatile timing_t *const start, volatile timing_t *const end)
    Get number of cycles between start and end.
    For some architectures or SoCs, the raw numbers from counter need to be scaled to obtain actual number of cycles.

    Parameters
    • start – Pointer to counter at start of a measured execution.
    • end – Pointer to counter at stop of a measured execution.

    Returns
    Number of cycles between start and end.

static inline uint64_t timing_freq_get(void)
    Get frequency of counter used (in Hz).

    Returns
    Frequency of counter used for timing in Hz.

static inline uint64_t timing_cycles_to_ns(uint64_t cycles)
    Convert number of cycles into nanoseconds.

    Parameters
    • cycles – Number of cycles

    Returns
    Converted time value

static inline uint64_t timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)
    Convert number of cycles into nanoseconds with averaging.

    Parameters
    • cycles – Number of cycles
    • count – Times of accumulated cycles to average over

    Returns
    Converted time value

static inline uint32_t timing_freq_get_mhz(void)
    Get frequency of counter used (in MHz).

    Returns
    Frequency of counter used for timing in MHz.

3.7 Time Utilities
3.7.1 Overview

Uptime in Zephyr is based on the a tick counter. With the default CONFIG_TICKLESS_KERNEL this counter advances at a nominally constant rate from zero at the instant the system started. The POSIX equivalent to this counter is something like CLOCK_MONOTONIC or, in Linux, CLOCK_MONOTONIC_RAW. k_uptime_get() provides a millisecond representation of this time.

Applications often need to correlate the Zephyr internal time with external time scales used in daily life, such as local time or Coordinated Universal Time. These systems interpret time in different ways and may have discontinuities due to leap seconds and local time offsets like daylight saving time.

Because of these discontinuities, as well as significant inaccuracies in the clocks underlying the cycle counter, the offset between time estimated from the Zephyr clock and the actual time in a “real” civil time scale is not constant and can vary widely over the runtime of a Zephyr application.

The time utilities API supports:

- converting between time representations
- synchronizing and aligning time scales

For terminology and concepts that support these functions see Concepts Underlying Time Support in Zephyr.

3.7.2 Time Utility APIs

Representation Transformation

Time scale instants can be represented in multiple ways including:

- Seconds since an epoch. POSIX representations of time in this form include time_t and struct timespec, which are generally interpreted as a representation of “UNIX Time”.
- Calendar time as a year, month, day, hour, minutes, and seconds relative to an epoch. POSIX representations of time in this form include struct tm.

Keep in mind that these are simply time representations that must be interpreted relative to a time scale which may be local time, UTC, or some other continuous or discontinuous scale.

Some necessary transformations are available in standard C library routines. For example, time_t measuring seconds since the POSIX EPOCH is converted to struct tm representing calendar time with gmtime(). Sub-second timestamps like struct timespec can also use this to produce the calendar time representation and deal with sub-second offsets separately.

The inverse transformation is not standardized: APIs like mktime() expect information about time zones. Zephyr provides this transformation with timeutil_timegm() and timeutil_timegm64().

Functions

int64_t timeutil_timegm64(const struct tm *tm)

Convert broken-down time to a POSIX epoch offset in seconds.

See also:


Parameters

- tm – pointer to broken down time.
Returns
the corresponding time in the POSIX epoch time scale.

\[ \text{timeutil\_timegm}(\text{const struct} \ \text{tm} *\text{tm}) \]
Convert broken-down time to a POSIX epoch offset in seconds.

See also:

Parameters
• \text{tm} – pointer to broken down time.

Returns
the corresponding time in the POSIX epoch time scale. If the time cannot be
represented then (time\_t)-1 is returned and \text{errno} is set to \text{ERANGE}.

Time Scale Synchronization

There are several factors that affect synchronizing time scales:

• The rate of discrete instant representation change. For example Zephyr uptime is tracked in ticks
which advance at events that nominally occur at \text{CONFIG\_SYS\_CLOCK\_TICKS\_PER\_SEC} Hertz, while
an external time source may provide data in whole or fractional seconds (e.g. microseconds).

• The absolute offset required to align the two scales at a single instant.

• The relative error between observable instants in each scale, required to align multiple instants
consistently. For example a reference clock that’s conditioned by a 1-pulse-per-second GPS signal
will be much more accurate than a Zephyr system clock driven by a RC oscillator with a +/- 250
ppm error.

Synchronization or alignment between time scales is done with a multi-step process:

• An instant in a time scale is represented by an (unsigned) 64-bit integer, assumed to advance at a
fixed nominal rate.

• \text{timeutil\_sync\_config} records the nominal rates of a reference time scale/source (e.g. TAI) and
a local time source (e.g. \text{k\_uptime\_ticks()}).

• \text{timeutil\_sync\_instant} records the representation of a single instant in both the reference and
local time scales.

• \text{timeutil\_sync\_state} provides storage for an initial instant, a recently received second observa-
tion, and a skew that can adjust for relative errors in the actual rate of each time scale.

• \text{timeutil\_sync\_ref\_from\_local()} and \text{timeutil\_sync\_local\_from\_ref()} convert instants in
one time scale to another taking into account skew that can be estimated from the two instances
stored in the state structure by \text{timeutil\_sync\_estimate\_skew()}. 

Functions

\text{int timeutil\_sync\_state\_update(struct timeutil\_sync\_state \ *tsp, const struct \timeutil\_sync\_instant \ *inst)}
Record a new instant in the time synchronization state.
Note that this updates only the latest persisted instant. The skew is not adjusted automatically.
Parameters

- `tsp` – pointer to a `timeutil_sync_state` object.
- `inst` – the new instant to be recorded. This becomes the base instant if there is no base instant, otherwise the value must be strictly after the base instant in both the reference and local time scales.

Return values

- `0` – if installation succeeded in providing a new base
- `1` – if installation provided a new latest instant
- `-EINVAL` – if the new instant is not compatible with the base instant

```c
int timeutil_sync_state_set_skew(struct timeutil_sync_state *tsp, float skew, const struct timeutil_sync_instant *base)
```
Update the state with a new skew and possibly base value.

Set the skew from a value retrieved from persistent storage, or calculated based on recent skew estimations including from `timeutil_sync_estimate_skew()`.

Optionally update the base timestamp. If the base is replaced the latest instant will be cleared until `timeutil_sync_state_update()` is invoked.

Parameters

- `tsp` – pointer to a time synchronization state.
- `skew` – the skew to be used. The value must be positive and shouldn’t be too far away from 1.
- `base` – optional new base to be set. If provided this becomes the base timestamp that will be used along with skew to convert between reference and local timescale instants. Setting the base clears the captured latest value.

Returns

0 if skew was updated

Returns

- `EINVAL` if skew was not valid

```c
float timeutil_sync_estimate_skew(const struct timeutil_sync_state *tsp)
```
Estimate the skew based on current state.

Using the base and latest syncpoints from the state determine the skew of the local clock relative to the reference clock. See `timeutil_sync_state::skew`.

Parameters

- `tsp` – pointer to a time synchronization state. The base and latest syncpoints must be present and the latest syncpoint must be after the base point in the local time scale.

Returns

the estimated skew, or zero if skew could not be estimated.

```c
int timeutil_sync_ref_from_local(const struct timeutil_sync_state *tsp, uint64_t local, uint64_t *refp)
```
Interpolate a reference timescale instant from a local instant.

Parameters

- `tsp` – pointer to a time synchronization state. This must have a base and a skew installed.
- `local` – an instant measured in the local timescale. This may be before or after the base instant.
refp – where the corresponding instant in the reference timescale should be stored. A negative interpolated reference time produces an error. If interpolation fails the referenced object is not modified.

Return values

• 0 – if interpolated using a skew of 1
• 1 – if interpolated using a skew not equal to 1
• -EINVAL – the times synchronization state is not adequately initialized
• -ERANGE – the interpolated reference time would be negative

int timeutil_sync_local_from_ref(const struct timeutil_sync_state *tsp, uint64_t ref, int64_t *localp)

Interpolate a local timescale instant from a reference instant.

Parameters

• tsp – pointer to a time synchronization state. This must have a base and a skew installed.
• ref – an instant measured in the reference timescale. This may be before or after the base instant.
• localp – where the corresponding instant in the local timescale should be stored. An interpolated value before local time 0 is provided without error. If interpolation fails the referenced object is not modified.

Return values

• 0 – if successful with a skew of 1
• 1 – if successful with a skew not equal to 1
• -EINVAL – the time synchronization state is not adequately initialized
• -ERANGE – refp is null

int32_t timeutil_sync_skew_to_ppb(float skew)

Convert from a skew to an error in parts-per-billion.

A skew of 1.0 has zero error. A skew less than 1 has a positive error (clock is faster than it should be). A skew greater than one has a negative error (clock is slower than it should be).

Note that due to the limited precision of float compared with double the smallest error that can be represented is about 120 ppb. A “precise” time source may have error on the order of 2000 ppb.

A skew greater than 3.14748 may underflow the 32-bit representation; this represents a clock running at less than 1/3 its nominal rate.

Returns

skew error represented as parts-per-billion, or INT32_MIN if the skew cannot be represented in the return type.

struct timeutil_sync_config

#include <timeutil.h> Immutable state for synchronizing two clocks.

Values required to convert durations between two time scales.
**Note:** The accuracy of the translation and calculated skew between sources depends on the resolution of these frequencies. A reference frequency with microsecond or nanosecond resolution would produce the most accurate tracking when the local reference is the Zephyr tick counter. A reference source like an RTC chip with 1 Hz resolution requires a much larger interval between sampled instants to detect relative clock drift.

### Public Members

**uint32_t ref_Hz**

The nominal instance counter rate in Hz.

This value is assumed to be precise, but may drift depending on the reference clock source.

The value must be positive.

**uint32_t local_Hz**

The nominal local counter rate in Hz.

This value is assumed to be inaccurate but reasonably stable. For a local clock driven by a crystal oscillator an error of 25 ppm is common; for an RC oscillator larger errors should be expected. The timeutil_sync infrastructure can calculate the skew between the local and reference clocks and apply it when converting between time scales.

The value must be positive.

#### struct timeutil_sync_instant

```c
#include <timeutil.h>
```

Representation of an instant in two time scales.

Capturing the same instant in two time scales provides a registration point that can be used to convert between those time scales.

### Public Members

**uint64_t ref**

An instant in the reference time scale.

This must never be zero in an initialized `timeutil_sync_instant` object.

**uint64_t local**

The corresponding instance in the local time scale.

This may be zero in a valid `timeutil_sync_instant` object.

#### struct timeutil_sync_state

```c
#include <timeutil.h>
```

State required to convert instants between time scales.

This state in conjunction with functions that manipulate it capture the offset information necessary to convert between two timescales along with information that corrects for skew due to inaccuracies in clock rates.

State objects should be zero-initialized before use.
Public Members

const struct timeutil_sync_config *cfg
    Pointer to reference and local rate information.

struct timeutil_sync_instant base
    The base instant in both time scales.

struct timeutil_sync_instant latest
    The most recent instant in both time scales.
    This is captured here to provide data for skew calculation.

float skew
    The scale factor used to correct for clock skew.
    The nominal rate for the local counter is assumed to be inaccurate but stable, i.e. it will
generally be some parts-per-million faster or slower than specified.
    A duration in observed local clock ticks must be multiplied by this value to produce a
duration in ticks of a clock operating at the nominal local rate.
    A zero value indicates that the skew has not been initialized. If the value is zero when
base is initialized the skew will be set to 1. Otherwise the skew is assigned through
timeutil_sync_state_set_skew().

3.7.3 Concepts Underlying Time Support in Zephyr

Terms from ISO/TC 154/WG 5 N0038 (ISO/WD 8601-1) and elsewhere:

• A time axis is a representation of time as an ordered sequence of instants.
  • A time scale is a way of representing an instant relative to an origin that serves as the epoch.
  • A time scale is monotonic (increasing) if the representation of successive time instants never decreases in value.
  • A time scale is continuous if the representation has no abrupt changes in value, e.g. jumping forward or back when going between successive instants.
  • Civil time generally refers to time scales that legally defined by civil authorities, like local governments, often to align local midnight to solar time.

Relevant Time Scales

International Atomic Time (TAI) is a time scale based on averaging clocks that count in SI seconds. TAI is a monotonic and continuous time scale.

Universal Time (UT) is a time scale based on Earth's rotation. UT is a discontinuous time scale as it requires occasional adjustments (leap seconds) to maintain alignment to changes in Earth's rotation. Thus the difference between TAI and UT varies over time. There are several variants of UT, with UTC being the most common.

UT times are independent of location. UT is the basis for Standard Time (or “local time”) which is the time at a particular location. Standard time has a fixed offset from UT at any given instant, primarily influenced by longitude, but the offset may be adjusted (“daylight saving time”) to align standard time to the local solar time. In a sense local time is “more discontinuous” than UT.
**POSIX Time** is a time scale that counts seconds since the “POSIX epoch” at 1970-01-01T00:00:00Z (i.e. the start of 1970 UTC). **UNIX Time** is an extension of POSIX time using negative values to represent times before the POSIX epoch. Both of these scales assume that every day has exactly 86400 seconds. In normal use instants in these scales correspond to times in the UTC scale, so they inherit the discontinuity.

The continuous analogue is **UNIX Leap Time** which is UNIX time plus all leap-second corrections added after the POSIX epoch (when TAI-UTC was 8 s).

**Example of Time Scale Differences** A positive leap second was introduced at the end of 2016, increasing the difference between TAI and UTC from 36 seconds to 37 seconds. There was no leap second introduced at the end of 1999, when the difference between TAI and UTC was only 32 seconds. The following table shows relevant civil and epoch times in several scales:

<table>
<thead>
<tr>
<th>UTC Date</th>
<th>UNIX time</th>
<th>TAI Date</th>
<th>TAI-UTC</th>
<th>UNIX Leap Time</th>
</tr>
</thead>
<tbody>
<tr>
<td>1970-01-01T00:00:00Z</td>
<td>0</td>
<td>1970-01-01T00:00:08</td>
<td>+8</td>
<td>0</td>
</tr>
<tr>
<td>1999-12-31T23:59:28Z</td>
<td>946684768</td>
<td>2000-01-01T00:00:00</td>
<td>+32</td>
<td>946684792</td>
</tr>
<tr>
<td>1999-12-31T23:59:59Z</td>
<td>946684799</td>
<td>2000-01-01T00:00:31</td>
<td>+32</td>
<td>946684823</td>
</tr>
<tr>
<td>2000-01-01T00:00:00Z</td>
<td>946684800</td>
<td>2000-01-01T00:00:32</td>
<td>+32</td>
<td>946684824</td>
</tr>
<tr>
<td>2016-12-31T23:59:59Z</td>
<td>1483228799</td>
<td>2017-01-01T00:00:35</td>
<td>+36</td>
<td>1483228827</td>
</tr>
<tr>
<td>2016-12-31T23:59:60Z</td>
<td>undefined</td>
<td>2017-01-01T00:00:36</td>
<td>+36</td>
<td>1483228828</td>
</tr>
<tr>
<td>2017-01-01T00:00:00Z</td>
<td>1483228800</td>
<td>2017-01-01T00:00:37</td>
<td>+37</td>
<td>1483228829</td>
</tr>
</tbody>
</table>

**Functional Requirements** The Zephyr tick counter has no concept of leap seconds or standard time offsets and is a continuous time scale. However it can be relatively inaccurate, with drifts as much as three minutes per hour (assuming an RC timer with 5% tolerance).

There are two stages required to support conversion between Zephyr time and common human time scales:

- Translation between the continuous but inaccurate Zephyr time scale and an accurate external stable time scale;
- Translation between the stable time scale and the (possibly discontinuous) civil time scale.

The API around `timeutil_sync_state_update()` supports the first step of converting between continuous time scales.

The second step requires external information including schedules of leap seconds and local time offset changes. This may be best provided by an external library, and is not currently part of the time utility APIs.

**Selecting an External Source and Time Scale** If an application requires civil time accuracy within several seconds then UTC could be used as the stable time source. However, if the external source adjusts to a leap second there will be a discontinuity: the elapsed time between two observations taken at 1 Hz is not equal to the numeric difference between their timestamps.

For precise activities a continuous scale that is independent of local and solar adjustments simplifies things considerably. Suitable continuous scales include:

- GPS time: epoch of 1980-01-06T00:00:00Z, continuous following TAI with an offset of TAI-GPS=19 s.
- Bluetooth mesh time: epoch of 2000-01-01T00:00:00Z, continuous following TAI with an offset of -32.
- UNIX Leap Time: epoch of 1970-01-01T00:00:00Z, continuous following TAI with an offset of -8.

Because C and Zephyr library functions support conversion between integral and calendar time representations using the UNIX epoch, UNIX Leap Time is an ideal choice for the external time scale.
The mechanism used to populate synchronization points is not relevant: it may involve reading from a local high-precision RTC peripheral, exchanging packets over a network using a protocol like NTP or PTP, or processing NMEA messages received a GPS with or without a 1pps signal.

### 3.8 Utilities

This page contains reference documentation for `<sys/util.h>`, which provides miscellaneous utility functions and macros.

```
group sys-util

Defines

POINTER_TO_UINT(x)
    Cast x, a pointer, to an unsigned integer.

UINT_TO_POINTER(x)
    Cast x, an unsigned integer, to a void*.

POINTER_TO_INT(x)
    Cast x, a pointer, to a signed integer.

INT_TO_POINTER(x)
    Cast x, a signed integer, to a void*.

BITS_PER_LONG
    Number of bits in a long int.

GENMASK(h, l)
    Create a contiguous bitmask starting at bit position l and ending at position h.

LSB_GET(value)
    Extract the Least Significant Bit from value.

FIELD_GET(mask, value)
    Extract a bitfield element from value corresponding to the field mask.

FIELD_PREP(mask, value)
    Prepare a bitfield element using value with mask representing its field position and width.
    The result should be combined with other fields using a logical OR.

ZERO_OR_COMPILE_ERROR(cond)
    0 if cond is true-ish; causes a compile error otherwise.

IS_ARRAY(array)
    Zero if array has an array type, a compile error otherwise.
    This macro is available only from C, not C++.

ARRAY_SIZE(array)
    Number of elements in the given array.
    In C++, due to language limitations, this will accept as array any type that implements operator[]. The results may not be particularly meaningful in this case.
    In C, passing a pointer as array causes a compile error.
```
IS_ARRAY_ELEMENT(array, ptr)

Whether ptr is an element of array.

This macro can be seen as a slightly stricter version of PART_OF_ARRAY in that it also ensures that ptr is aligned to an array-element boundary of array.

In C, passing a pointer as array causes a compile error.

Parameters

- array – the array in question
- ptr – the pointer to check

Returns

1 if ptr is part of array, 0 otherwise

ARRAY_INDEX(array, ptr)

Index of ptr within array.

With CONFIG_ASSERT=y, this macro will trigger a runtime assertion when ptr does not fall into the range of array or when ptr is not aligned to an array-element boundary of array.

In C, passing a pointer as array causes a compile error.

Parameters

- array – the array in question
- ptr – pointer to an element of array

Returns

the array index of ptr within array, on success

PART_OF_ARRAY(array, ptr)

Check if a pointer ptr lies within array.

In C but not C++, this causes a compile error if array is not an array (e.g. if ptr and array are mixed up).

Parameters

- array – an array
- ptr – a pointer

Returns

1 if ptr is part of array, 0 otherwise

ARRAY_INDEX_FLOOR(array, ptr)

Array-index of ptr within array, rounded down.

This macro behaves much like ARRAY_INDEX with the notable difference that it accepts any ptr in the range of array rather than exclusively a ptr aligned to an array-element boundary of array.

With CONFIG_ASSERT=y, this macro will trigger a runtime assertion when ptr does not fall into the range of array.

In C, passing a pointer as array causes a compile error.

Parameters

- array – the array in question
- ptr – pointer to an element of array

Returns

the array index of ptr within array, on success
CONTAINER_OF(ptr, type, field)
Get a pointer to a structure containing the element.

Example:

```c
struct foo {
    int bar;
};

struct foo my_foo;
int *ptr = &my_foo.bar;
struct foo *container = CONTAINER_OF(ptr, struct foo, bar);
```

Above, `container` points at `my_foo`.

**Parameters**
- `ptr` – pointer to a structure element
- `type` – name of the type that `ptr` is an element of
- `field` – the name of the field within the struct `ptr` points to

**Returns**
a pointer to the structure that contains `ptr`

ROUND_UP(x, align)
Value of `x` rounded up to the next multiple of `align`, which must be a power of 2.

ROUND_DOWN(x, align)
Value of `x` rounded down to the previous multiple of `align`, which must be a power of 2.

WB_UP(x)
Value of `x` rounded up to the next word boundary.

WB_DN(x)
Value of `x` rounded down to the previous word boundary.

ceiling_fraction(numerator, divider)
Ceiling function applied to `numerator / divider` as a fraction.

MAX(a, b)
Obtain the maximum of two values.

**Note:** Arguments are evaluated twice. Use Z_MAX for a GCC-only, single evaluation version

MIN(a, b)
Obtain the minimum of two values.

**Note:** Arguments are evaluated twice. Use Z_MIN for a GCC-only, single evaluation version
Parameters
• a – First value.
• b – Second value.

Returns
Minimum value of a and b.

CLAMP(val, low, high)
Clamp a value to a given range.

Note: Arguments are evaluated multiple times. Use Z_CLAMP for a GCC-only, single evaluation version.

Parameters
• val – Value to be clamped.
• low – Lowest allowed value (inclusive).
• high – Highest allowed value (inclusive).

Returns
Clamped value.

IN_RANGE(val, min, max)
Checks if a value is within range.

Note: val is evaluated twice.

Parameters
• val – Value to be checked.
• min – Lower bound (inclusive).
• max – Upper bound (inclusive).

Return values
• true – If value is within range
• false – If the value is not within range

KB(x)
Number of bytes in x kibibytes.

MB(x)
Number of bytes in x mebibytes.

GB(x)
Number of bytes in x gibibytes.

KHZ(x)
Number of Hz in x kHz.

MHZ(x)
Number of Hz in x MHz.
\textbf{WAIT\_FOR}(\textit{expr}, \textit{timeout}, \textit{delay\_stmt})

Wait for an expression to return true with a timeout.

Spin on an expression with a timeout and optional delay between iterations

Commonly needed when waiting on hardware to complete an asynchronous request to read/write/initialize/reset, but useful for any expression.

\textbf{Parameters}

- \textit{expr} – Truth expression upon which to poll, e.g.: XYZREG & XYZREG\_EN
- \textit{timeout} – Timeout to wait for in microseconds, e.g.: 1000 (1ms)
- \textit{delay\_stmt} – Delay statement to perform each poll iteration e.g.: NULL, \textit{k\_yield()}, \textit{k\_msleep(1)} or \textit{k\_busy\_wait(1)}

\textbf{Return values}

- \textit{expr} – As a boolean return, if false then it has timed out.

\textbf{BIT}(\textit{n})

Unsigned integer with bit position \textit{n} set (signed in assembly language).

\textbf{BIT64}(\_\textit{n})

64-bit unsigned integer with bit position \_\textit{n} set.

\textbf{WRITE\_BIT}(\textit{var}, \textit{bit}, \textit{set})

Set or clear a bit depending on a boolean value.

The argument \textit{var} is a variable whose value is written to as a side effect.

\textbf{Parameters}

- \textit{var} – Variable to be altered
- \textit{bit} – Bit number
- \textit{set} – if 0, clears \textit{bit} in \textit{var}; any other value sets \textit{bit}

\textbf{BIT\_MASK}(\textit{n})

Bit mask with bits 0 through \textit{n}-1 (inclusive) set, or 0 if \textit{n} is 0.

\textbf{BIT64\_MASK}(\textit{n})

64-bit bit mask with bits 0 through \textit{n}-1 (inclusive) set, or 0 if \textit{n} is 0.

\textbf{IS\_ENABLED}(\textit{config\_macro})

Check for macro definition in compiler-visible expressions.

This trick was pioneered in Linux as the \texttt{config\_enabled()} macro. It has the effect of taking a macro value that may be defined to “1” or may not be defined at all and turning it into a literal expression that can be handled by the C compiler instead of just the preprocessor. It is often used with a \texttt{CONFIG\_FOO} macro which may be defined to 1 via Kconfig, or left undefined.

That is, it works similarly to \texttt{if defined(CONFIG\_FOO)} except that its expansion is a C expression. Thus, much \texttt{ifdef} usage can be replaced with equivalents like:

\begin{verbatim}
if (IS\_ENABLED(CONFIG\_FOO)) {
    do\_something\_with\_foo
}
\end{verbatim}

This is cleaner since the compiler can generate errors and warnings for \texttt{do\_something\_with\_foo} even when \texttt{CONFIG\_FOO} is undefined.

\textbf{Parameters}

- \textit{config\_macro} – Macro to check
**Returns**

1 if `config_macro` is defined to 1, 0 otherwise (including if `config_macro` is not defined)

\[ \text{COND_CODE}_1(\text{flag, if\_1\_code, else\_code}) \]

Insert code depending on whether \text{flag} expands to 1 or not.

This relies on similar tricks as `IS_ENABLED()`, but as the result of \text{flag} expansion, results in either \text{if\_1\_code} or \text{else\_code} is expanded.

To prevent the preprocessor from treating commas as argument separators, the \text{if\_1\_code} and \text{else\_code} expressions must be inside brackets/parentheses: (). These are stripped away during macro expansion.

Example:

\[ \text{COND_CODE}_1(\text{CONFIG\_FLAG, (uint32\_t x;), (there\_is\_no\_flag();)}) \]

If \text{CONFIG\_FLAG} is defined to 1, this expands to:

\[ \text{uint32\_t x;} \]

It expands to \text{there\_is\_no\_flag();} otherwise.

This could be used as an alternative to:

```c
#if defined(CONFIG_FLAG) && (CONFIG_FLAG == 1)
#define MAYBE_DECLARE(x) uint32_t x
#else
#define MAYBE_DECLARE(x) there_is_no_flag()
#endif
MAYBE_DECLARE(x);
```

However, the advantage of `COND_CODE_1()` is that code is resolved in place where it is used, while the #if method defines `MAYBE_DECLARE` on two lines and requires it to be invoked again on a separate line. This makes `COND_CODE_1()` more concise and also sometimes more useful when used within another macro's expansion.

**Note:** \text{flag} can be the result of preprocessor expansion, e.g. an expression involving \text{NUM\_VA\_ARGS\_LESS\_1(...)}. However, \text{if\_1\_code} is only expanded if \text{flag} expands to the integer literal 1. Integer expressions that evaluate to 1, e.g. after doing some arithmetic, will not work.

**Parameters**

- \text{flag} – evaluated flag
- \text{if\_1\_code} – result if \text{flag} expands to 1; must be in parentheses
- \text{else\_code} – result otherwise; must be in parentheses

\[ \text{COND_CODE}_0(\text{flag, if\_0\_code, else\_code}) \]

Like `COND_CODE_1()` except tests if \text{flag} is 0.

This is like `COND_CODE_1()`, except that it tests whether \text{flag} expands to the integer literal 0. It expands to \text{if\_0\_code} if so, and \text{else\_code} otherwise; both of these must be enclosed in parentheses.
See also:

`COND_CODE_1()`

Parameters

- `_flag` – evaluated flag
- `_if_0_code` – result if `_flag` expands to 0; must be in parentheses
- `_else_code` – result otherwise; must be in parentheses

`IF_ENABLED(_flag, _code)`

Insert code if `_flag` is defined and equals 1.

Like `COND_CODE_1()`, this expands to `_code` if `_flag` is defined to 1; it expands to nothing otherwise.

Example:

```c
IF_ENABLED(CONFIG_FLAG, (uint32_t foo;))
```

If `CONFIG_FLAG` is defined to 1, this expands to:

```c
uint32_t foo;
```

and to nothing otherwise.

It can be considered as a more compact alternative to:

```c
#if defined(CONFIG_FLAG) && (CONFIG_FLAG == 1)
uint32_t foo;
#endif
```

Parameters

- `_flag` – evaluated flag
- `_code` – result if `_flag` expands to 1; must be in parentheses

`IS_EMPTY(…)`

Check if a macro has a replacement expression.

If a is a macro defined to a nonempty value, this will return true, otherwise it will return false. It only works with defined macros, so an additional `#ifdef` test may be needed in some cases.

This macro may be used with `COND_CODE_1()` and `COND_CODE_0()` while processing `__VA_ARGS__` to avoid processing empty arguments.

Example:

```c
#define EMPTY
#define NON_EMPTY 1
#undef UNDEFINED
IS_EMPTY(EMPTY)
IS_EMPTY(NON_EMPTY)
IS_EMPTY(UNDEFINED)
#if defined(EMPTY) && IS_EMPTY(EMPTY) == true
some_conditional_code
#endif
```

In above examples, the invocations of `IS_EMPTY(…)` return true, false, and true; `some_conditional_code` is included.

Parameters
- macro to check for emptiness (may be __VA_ARGS__)

IS_EQ(a, b)
Like a == b, but does evaluation and short-circuiting at C preprocessor time.
This however only works for integer literal from 0 to 255.

LIST_DROP_EMPTY(...)
Remove empty arguments from list.
During macro expansion, __VA_ARGS__ and other preprocessor generated lists may contain empty elements, e.g.:

```c
#define LIST ,a,b,,d,
```

Using EMPTY to show each empty element, LIST contains:

```c
EMPTY, a, b, EMPTY, d
```

When processing such lists, e.g. using FOR_EACH(), all empty elements will be processed, and may require filtering out. To make that process easier, it is enough to invoke LIST_DROP_EMPTY which will remove all empty elements.

Example:

```c
LIST_DROP_EMPTY(LIST)
```

expands to:

```c
a, b, d
```

Parameters
- ... – list to be processed

EMPTY
Macro with an empty expansion.
This trivial definition is provided for readability when a macro should expand to an empty result, which e.g. is sometimes needed to silence checkpatch.

Example:

```c
#define LIST_ITEM(n) , item##n
```

The above would cause checkpatch to complain, but:

```c
#define LIST_ITEM(n) EMPTY, item##n
```

would not.

IDENTITY(V)
Macro that expands to its argument.
This is useful in macros like FOR_EACH() when there is no transformation required on the list elements.

Parameters
- V – any value
GET_ARG_N(N, ...)
Get nth argument from argument list.

Parameters
- N – Argument index to fetch. Counter from 1.
- ... – Variable list of arguments from which one argument is returned.

Returns
Nth argument.

GET_ARGS_LESS_N(N, ...)
Strips n first arguments from the argument list.

Parameters
- N – Number of arguments to discard.
- ... – Variable list of arguments.

Returns
argument list without N first arguments.

UTIL_OR(a, b)
Like a || b, but does evaluation and short-circuiting at C preprocessor time.

This is not the same as the binary || operator; in particular, a should expand to an integer literal 0 or 1. However, b can be any value.

This can be useful when b is an expression that would cause a build error when a is 1.

UTIL_AND(a, b)
Like a && b, but does evaluation and short-circuiting at C preprocessor time.

This is not the same as the binary && operator, however; in particular, a should expand to an integer literal 0 or 1. However, b can be any value.

This can be useful when b is an expression that would cause a build error when a is 0.

LISTIFY(LEN, F, sep, ...)
Generates a sequence of code with configurable separator.

Example:
```c
#define FOO(i, _) MY_PWM ## i
{ LISTIFY(PWM_COUNT, FOO, (,)) }
```

The above two lines expand to:
```
{ MY_PWM0 , MY_PWM1 }
```

Note: Calling LISTIFY with undefined arguments has undefined behavior.

Parameters
- LEN – The length of the sequence. Must be an integer literal less than 255.
- F – A macro function that accepts at least two arguments: F(i, ...). F is called repeatedly in the expansion. Its first argument i is the index in the sequence, and the variable list of arguments passed to LISTIFY are passed through to F.
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
FOR_EACH(F, sep, ...
Call a macro $F$ on each provided argument with a given separator between each call.

Example:

```
#define F(x) int a##x
FOR_EACH(F, (;), 4, 5, 6);
```

This expands to:

```
int a4;
int a5;
int a6;
```

Parameters

- $F$ – Macro to invoke
- $sep$ – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- $...$ – Variable argument list. The macro $F$ is invoked as $F(element)$ for each element in the list.

FOR_EACH_NONEMPTY_TERM(F, term, ...)

Like FOR_EACH(), but with a terminator instead of a separator, and drops empty elements from the argument list.

The $sep$ argument to FOR_EACH(F, (sep), a, b) is a separator which is placed between calls to $F$, like this:

```
FOR_EACH(F, (sep), a, b) // F(a) sep F(b)
```

By contrast, the $term$ argument to FOR_EACH_NONEMPTY_TERM(F, (term), a, b) is added after each time $F$ appears in the expansion:

```
FOR_EACH_NONEMPTY_TERM(F, (term), a, b) // F(a) term F(b) term
```

Further, any empty elements are dropped:

```
FOR_EACH_NONEMPTY_TERM(F, (term), a, EMPTY, b) // F(a) term F(b) term
```

This is more convenient in some cases, because FOR_EACH_NONEMPTY_TERM() expands to nothing when given an empty argument list, and it’s often cumbersome to write a macro $F$ that does the right thing even when given an empty argument.

One example is when __VA_ARGS__ may or may not be empty, and the results are embedded in a larger initializer:

```
#define SQUARE(x) ((x)*(x))

int my_array[] = {
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), FOO(...))
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), BAR(...))
    FOR_EACH_NONEMPTY_TERM(SQUARE, (,), BAZ(...))
};
```

This is more convenient than:
a. figuring out whether the FOO, BAR, and BAZ expansions are empty and adding a comma manually (or not) between FOR_EACH() calls

b. rewriting SQUARE so it reacts appropriately when “x” is empty (which would be necessary if e.g. FOO expands to nothing)

**Parameters**

- **F** – Macro to invoke on each nonempty element of the variable arguments
- **term** – Terminator (e.g. comma or semicolon) placed after each invocation of F. Must be in parentheses; this is required to enable providing a comma as separator.
- **...** – Variable argument list. The macro F is invoked as F(element) for each nonempty element in the list.

**FOR_EACH_IDX(F, sep, ...)**

Call macro F on each provided argument, with the argument’s index as an additional parameter.

This is like **FOR_EACH()**, except F should be a macro which takes two arguments: F(index, variable_arg).

Example:

```c
#define F(idx, x) int a##idx = x
FOR_EACH_IDX(F, (;), 4, 5, 6);
```

This expands to:

```c
int a0 = 4;
int a1 = 5;
int a2 = 6;
```

**Parameters**

- **F** – Macro to invoke
- **sep** – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- **...** – Variable argument list. The macro F is invoked as F(index, element) for each element in the list.

**FOR_EACH_FIXED_ARG(F, sep, fixed_arg, ...)**

Call macro F on each provided argument, with an additional fixed argument as a parameter.

This is like **FOR_EACH()**, except F should be a macro which takes two arguments: F(variable_arg, fixed_arg).

Example:

```c
static void func(int val, void *dev);
FOR_EACH_FIXED_ARG(func, (;), dev, 4, 5, 6);
```

This expands to:

```c
func(4, dev);
func(5, dev);
func(6, dev);
```

**Parameters**
• F – Macro to invoke
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• fixed_arg – Fixed argument passed to F as the second macro parameter.
• ... – Variable argument list. The macro F is invoked as F(element, fixed_arg) for each element in the list.

FOR_EACH_IDX_FIXED_ARG(F, sep, fixed_arg, ...)
Calls macro F for each variable argument with an index and fixed argument.
This is like the combination of FOR_EACH_IDX() with FOR_EACH_FIXED_ARG().
Example:

```c
#define F(idx, x, fixed_arg) int fixed_arg##idx = x
FOR_EACH_IDX_FIXED_ARG(F, (;), a, 4, 5, 6);
```
This expands to:
```
int a0 = 4;
int a1 = 5;
int a2 = 6;
```

Parameters
• F – Macro to invoke
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; This is required to enable providing a comma as separator.
• fixed_arg – Fixed argument passed to F as the third macro parameter.
• ... – Variable list of arguments. The macro F is invoked as F(index, element, fixed_arg) for each element in the list.

REVERSE_ARGS(...)
Reverse arguments order.

Parameters
• ... – Variable argument list.

NUM_VA_ARGS_LESS_1(...)
Number of arguments in the variable arguments list minus one.

Parameters
• ... – List of arguments

Returns
Number of variadic arguments in the argument list, minus one

MACRO_MAP_CAT(...)
Mapping macro that pastes results together.
This is similar to FOR_EACH() in that it invokes a macro repeatedly on each element of __VA_ARGS__. However, unlike FOR_EACH(), MACRO_MAP_CAT() pastes the results together into a single token.
For example, with this macro FOO:

```c
#define FOO(x) item_##x##_
```
MACRO_MAP_CAT(FOO, a, b, c), expands to the token:

```
item_a_item_b_item_c_
```

**Parameters**
- ... – Macro to expand on each argument, followed by its arguments. (The macro should take exactly one argument.)

**Returns**
The results of expanding the macro on each argument, all pasted together

MACRO_MAP_CAT_N(N, ...)
Mapping macro that pastes a fixed number of results together.
Similar to MACRO_MAP_CAT(), but expects a fixed number of arguments. If more arguments are given than are expected, the rest are ignored.

**Parameters**
- N – Number of arguments to map
- ... – Macro to expand on each argument, followed by its arguments. (The macro should take exactly one argument.)

**Returns**
The results of expanding the macro on each argument, all pasted together

**Functions**

static inline bool is_power_of_two(unsigned int x)
Is x a power of two?

**Parameters**
- x – value to check

**Returns**
true if x is a power of two, false otherwise

static inline int64_t arithmetic_shift_right(int64_t value, uint8_t shift)
Arithmetic shift right.

**Parameters**
- value – value to shift
- shift – number of bits to shift

**Returns**
value shifted right by shift; opened bit positions are filled with the sign bit

static inline void bytecpy(void *dst, const void *src, size_t size)
Copy size bytes of src into dest. This is guaranteed to be done byte by byte.

**Parameters**
- dst – Pointer to the destination memory.
- src – Pointer to the source of the data.
- size – The number of bytes to copy.
static inline void byteswap(void *a, void *b, size_t size)
    byte by byte swap.

    Swap size bytes between memory regions a and b. This is guaranteed to be done byte by byte.

Parameters
    • a – Pointer to the first memory region.
    • b – Pointer to the second memory region.
    • size – The number of bytes to swap.

int char2hex(char c, uint8_t *x)
    Convert a single character into a hexadecimal nibble.

Parameters
    • c – The character to convert
    • x – The address of storage for the converted number.

Returns
    Zero on success or (negative) error code otherwise.

int hex2char(uint8_t x, char *c)
    Convert a single hexadecimal nibble into a character.

Parameters
    • c – The number to convert
    • x – The address of storage for the converted character.

Returns
    Zero on success or (negative) error code otherwise.

size_t bin2hex(const uint8_t *buf, size_t buflen, char *hex, size_t hexlen)
    Convert a binary array into string representation.

Parameters
    • buf – The binary array to convert
    • buflen – The length of the binary array to convert
    • hex – Address of where to store the string representation.
    • hexlen – Size of the storage area for string representation.

Returns
    The length of the converted string, or 0 if an error occurred.

size_t hex2bin(const char *hex, size_t hexlen, uint8_t *buf, size_t buflen)
    Convert a hexadecimal string into a binary array.

Parameters
    • hex – The hexadecimal string to convert
    • hexlen – The length of the hexadecimal string to convert.
    • buf – Address of where to store the binary data
    • buflen – Size of the storage area for binary data

Returns
    The length of the binary array, or 0 if an error occurred.
static inline uint8_t bcd2bin(uint8_t bcd)
    Convert a binary coded decimal (BCD 8421) value to binary.

Parameters
    • bcd – BCD 8421 value to convert.

Returns
    Binary representation of input value.

static inline uint8_t bin2bcd(uint8_t bin)
    Convert a binary value to binary coded decimal (BCD 8421).

Parameters
    • bin – Binary value to convert.

Returns
    BCD 8421 representation of input value.

uint8_t u8_to_dec(char *buf, uint8_t buflen, uint8_t value)
    Convert a uint8_t value into its ASCII decimal string representation. The string is terminated
    if there is enough space in buf.

Parameters
    • buf – Address of where to store the string representation.
    • buflen – Size of the storage area for string representation.
    • value – The value to convert to decimal string

Returns
    The length of the converted string (excluding terminator if any), or 0 if an error
    occurred.

cchar *utf8_trunc(char *utf8_str)
    Properly truncate a NULL-terminated UTF-8 string.

Take a NULL-terminated UTF-8 string and ensure that if the string has been truncated (by
setting the NULL terminator) earlier by other means, that the string ends with a properly
formatted UTF-8 character (1-4 bytes).

Parameters
    • utf8_str – NULL-terminated string

Returns
    Pointer to the utf8_str

cchar *utf8_lcpy(char *dst, const char *src, size_t n)
    Copies a UTF-8 encoded string from src to dst.

The resulting dst will always be NULL terminated if n is larger than 0, and the dst string will
always be properly UTF-8 truncated.

Parameters
    • dst – The destination of the UTF-8 string.
    • src – The source string
    • n – The size of the dst buffer. Maximum number of characters copied is n - 1.
        If 0 nothing will be done, and the dst will not be NULL terminated.

Returns
    Pointer to the dst
3.9 Iterable Sections

This page contains the reference documentation for the iterable sections APIs, which can be used for defining iterable areas of equally-sized data structures, that can be iterated on using \texttt{STRUCT\_SECTION\_FOREACH}.

3.9.1 Usage

Iterable section elements are typically used by defining the data structure and associated initializer in a common header file, so that they can be instantiated anywhere in the code base.

\begin{verbatim}
struct my_data {
    int a, b;
};

#define DEFINE_DATA(name, _a, _b) \
    STRUCT\_SECTION\_ITERABLE(my_data, name) = { \
        .a = _a, \n        .b = _b, \n    }

...DEFINE_DATA(d1, 1, 2);
DEFINE_DATA(d2, 3, 4);
DEFINE_DATA(d3, 5, 6);
\end{verbatim}

Then the linker has to be setup to place the place the structure in a contiguous segment using one of the linker macros such as \texttt{ITERABLE\_SECTION\_RAM} or \texttt{ITERABLE\_SECTION\_ROM}. Custom linker snippets are normally declared using one of the \texttt{zephyr\_linker\_sources()} CMake functions, using the appropriate section identifier, \texttt{DATA\_SECTIONS} for RAM structures and \texttt{SECTIONS} for ROM ones.

\begin{verbatim}
# CMakeLists.txt
zephyr\_linker\_sources(DATA\_SECTIONS iterables.ld)

# iterables.ld
ITERABLE\_SECTION\_RAM(my_data, 4)
\end{verbatim}

The data can then be accessed using \texttt{STRUCT\_SECTION\_FOREACH}.

\begin{verbatim}
STRUCT\_SECTION\_FOREACH(my_data, data) {
    printk("%p: a: %d, b: %d\n", data, data->a, data->b);
}
\end{verbatim}

\textbf{Note}: The linker is going to place the entries sorted by name, so the example above would visit d1, d2 and d3 in that order, regardless of how they were defined in the code.

3.9.2 API Reference

\begin{verbatim}
group iterable\_section\_apis
    Iterable Sections APIs.
\end{verbatim}
Defines

ITERABLE_SECTION_ROM(struct_type, subalign)
Define a read-only iterable section output.
Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.
This macro should be used for read-only data.
Note that this keeps the symbols in the image even though they are not being directly referenced. Use this when symbols are indirectly referenced by iterating through the section.

ITERABLE_SECTION_ROM_GC_ALLOWED(struct_type, subalign)
Define a garbage collectable read-only iterable section output.
Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.
This macro should be used for read-only data.
Note that the symbols within the section can be garbage collected.

ITERABLE_SECTION_RAM(struct_type, subalign)
Define a read-write iterable section output.
Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.
This macro should be used for read-write data that is modified at runtime.
Note that this keeps the symbols in the image even though they are not being directly referenced. Use this when symbols are indirectly referenced by iterating through the section.

ITERABLE_SECTION_RAM_GC_ALLOWED(struct_type, subalign)
Define a garbage collectable read-write iterable section output.
Define an output section which will set up an iterable area of equally-sized data structures. For use with STRUCT_SECTION_ITERABLE(). Input sections will be sorted by name, per ld's SORT_BY_NAME.
This macro should be used for read-write data that is modified at runtime.
Note that the symbols within the section can be garbage collected.

STRUCT_SECTION_ITERABLE(struct_type, name)
Defines a new element for an iterable section.
Convenience helper combining __in_section() and Z_DECL_ALIGN(). The section name is the struct type prepended with an underscore. The subsection is “static” and the subsubsection is the variable name.
In the linker script, create output sections for these using ITERABLE_SECTION_ROM() or ITERABLE_SECTION_RAM().

Note: In order to store the element in ROM, a const specifier has to be added to the declaration: const STRUCT_SECTION_ITERABLE(...);

STRUCT_SECTION_ITERABLE_ALTERNATE(out_type, struct_type, name)
Defines a new element of alternate data type for an iterable section.
Special variant of \texttt{STRUCT\_SECTION\_ITERABLE()}, for placing alternate data types within the iterable section of a specific data type. The data type sizes and semantics must be equivalent!

\texttt{STRUCT\_SECTION\_FOREACH}(\texttt{struct\_type}, \texttt{iterator})

Iterate over a specified iterable section.

\begin{itemize}
\item \texttt{iterator} for structure instances gathered by \texttt{STRUCT\_SECTION\_ITERABLE()}. The linker must provide a \_\_\texttt{struct\_type}\_\_list\_start symbol and a \_\_\texttt{struct\_type}\_\_list\_end symbol to mark the start and the end of the list of struct objects to iterate over. This is normally done using \texttt{ITERABLE\_SECTION\_ROM()} or \texttt{ITERABLE\_SECTION\_RAM()} in the linker script.
\end{itemize}

\texttt{STRUCT\_SECTION\_GET}(\texttt{struct\_type}, \texttt{i}, \texttt{dst})

Get element from section.

\begin{itemize}
\item \texttt{struct\_type} – \texttt{[in]} Struct type.
\item \texttt{i} – \texttt{[in]} Index.
\item \texttt{dst} – \texttt{[out]} Pointer to location where pointer to element is written.
\end{itemize}

\texttt{STRUCT\_SECTION\_COUNT}(\texttt{struct\_type}, \texttt{dst})

Count elements in a section.

\begin{itemize}
\item \texttt{struct\_type} – \texttt{[in]} Struct type
\item \texttt{dst} – \texttt{[out]} Pointer to location where result is written.
\end{itemize}

\section{3.10 Code And Data Relocation}

\subsection{3.10.1 Overview}

This feature will allow relocating \texttt{.text}, \texttt{.rodata}, \texttt{.data}, and \texttt{.bss} sections from required files and place them in the required memory region. The memory region and file are given to the \texttt{scripts/build/gen_relocate_app.py} script in the form of a string. This script is always invoked from inside cmake.

This script provides a robust way to re-order the memory contents without actually having to modify the code. In simple terms this script will do the job of \texttt{\_\_attribute\_\_((section("name")))} for a bunch of files together.

\subsection{3.10.2 Details}

The memory region and file are given to the \texttt{scripts/build/gen_relocate_app.py} script in the form of a string.

An example of such a string is: \texttt{SRAM2:/home/xyz/zephyr/samples/hello_world/src/main.c, SRAM1:/home/xyz/zephyr/samples/hello_world/src/main2.c}

This script is invoked with the following parameters: \texttt{python3 gen_relocate_app.py -i input_string -o generated_linker -c generated_code}

Kconfig \texttt{CONFIG\_CODE\_DATA\_RELOCATION} option, when enabled in \texttt{prj.conf}, will invoke the script and do the required relocation.
This script also trigger the generation of `linker_relocate.ld` and `code_relocation.c` files. The `linker_relocate.ld` file creates appropriate sections and links the required functions or variables from all the selected files.

**Note:** The text section is split into 2 parts in the main linker script. The first section will have some info regarding vector tables and other debug related info. The second section will have the complete text section. This is needed to force the required functions and data variables to the correct locations. This is due to the behavior of the linker. The linker will only link once and hence this text section had to be split to make room for the generated linker script.

The `code_relocation.c` file has code that is needed for initializing data sections, and a copy of the text sections (if XIP). Also this contains code needed for bss zeroing and for data copy operations from ROM to required memory type.

The procedure to invoke this feature is:

- Enable `CONFIG_CODE_DATA_RELOCATION` in the `prj.conf` file
- Inside the `CMakeLists.txt` file in the project, mention all the files that need relocation.
  
  ```
  zephyr_code_relocate(src/*.c SRAM2)
  
  Where the first argument is the file/files and the second argument is the memory where it must be placed.
  ```

**Note:** The file argument supports limited regular expressions. function `zephyr_code_relocate()` can be called as many times as required. This step has to be performed before the inclusion of `boilerplate.cmake`.

### Additional Configurations

This section shows additional configuration options that can be set in `CMakeLists.txt`

- if the memory is SRAM1, SRAM2, CCD, or AON, then place the full object in the sections for example:
  
  ```
  zephyr_code_relocate(src/file1.c SRAM2)
  zephyr_code_relocate(src/file2.c.c SRAM)
  ```

- if the memory type is appended with _DATA, _TEXT, _RODATA or _BSS, only the selected memory is placed in the required memory region. for example:
  
  ```
  zephyr_code_relocate(src/file1.c SRAM2_DATA)
  zephyr_code_relocate(src/file2.c.c SRAM2_TEXT)
  ```

- Multiple regions can also be appended together such as: SRAM2_DATA_BSS. This will place data and bss inside SRAM2.

### NOCOPY flag

When a NOCOPY option is passed to the `zephyr_code_relocate()` function, the relocation code is not generated in `code_relocation.c`. This flag can be used when we want to move the content of a specific file (or set of files) to a XIP area.

This example will place the .text section of the `xip_external_flash.c` file to the EXTFLASH memory region where it will be executed from (XIP). The .data will be relocated as usual into SRAM.
Sample

A sample showcasing this feature is provided at $ZEPHYR_BASE/samples/application_development/code_relocation/

This is an example of using the code relocation feature.

This example will place .text, .data, .bss from 3 files to various parts in the SRAM using a custom linker file derived from include/arch/arm/aarch32/cortex_m/scripts/linker.ld

A sample showcasing the NOCOPY flag is provided at $ZEPHYR_BASE/samples/application_development/code_relocation_nocopy/
4.1 Cryptography

The crypto section contains information regarding the cryptographic primitives supported by the Zephyr kernel. Use the information to understand the principles behind the operation of the different algorithms and how they were implemented.

The following crypto libraries have been included:

4.1.1 TinyCrypt Cryptographic Library

Overview

The TinyCrypt Library provides an implementation for targeting constrained devices with a minimal set of standard cryptography primitives, as listed below. To better serve applications targeting constrained devices, TinyCrypt implementations differ from the standard specifications (see the Important Remarks section for some important differences). Certain cryptographic primitives depend on other primitives, as mentioned in the list below.

Aside from the Important Remarks section below, valuable information on the usage, security and technicalities of each cryptographic primitive are found in the corresponding header file.

- SHA-256:
  - Type of primitive: Hash function.
  - Requires: –

- HMAC-SHA256:
  - Type of primitive: Message authentication code.
  - Requires: SHA-256

- HMAC-PRNG:
  - Type of primitive: Pseudo-random number generator.
  - Standard Specification: NIST SP 800-90A.
  - Requires: SHA-256 and HMAC-SHA256.

- AES-128:
  - Type of primitive: Block cipher.
- Requires: –

- AES-CBC mode:
  - Type of primitive: Encryption mode of operation.
  - Standard Specification: NIST SP 800-38A.
  - Requires: AES-128.

- AES-CTR mode:
  - Type of primitive: Encryption mode of operation.
  - Standard Specification: NIST SP 800-38A.
  - Requires: AES-128.

- AES-CMAC mode:
  - Type of primitive: Message authentication code.
  - Standard Specification: NIST SP 800-38B.
  - Requires: AES-128.

- AES-CCM mode:
  - Type of primitive: Authenticated encryption.
  - Standard Specification: NIST SP 800-38C.
  - Requires: AES-128.

- ECC-DH:
  - Type of primitive: Key exchange.
  - Requires: ECC auxiliary functions (ecc.h/c).

- ECC-DSA:
  - Type of primitive: Digital signature.
  - Requires: ECC auxiliary functions (ecc.h/c).

**Design Goals**

- Minimize the code size of each cryptographic primitive. This means minimize the size of a board-independent implementation, as presented in TinyCrypt. Note that various applications may require further features, optimizations with respect to other metrics and countermeasures for particular threats. These peculiarities would increase the code size and thus are not considered here.

- Minimize the dependencies among the cryptographic primitives. This means that it is unnecessary to build and allocate object code for more primitives than the ones strictly required by the intended application. In other words, one can select and compile only the primitives required by the application.

**Important Remarks**

The cryptographic implementations in TinyCrypt library have some limitations. Some of these limitations are inherent to the cryptographic primitives themselves, while others are specific to TinyCrypt. Some of these limitations are discussed in-depth below.
General Remarks

• TinyCrypt does not intend to be fully side-channel resistant. Due to the variety of side-channel attacks, many of them making certain boards vulnerable. In this sense, instead of penalizing all library users with side-channel countermeasures such as increasing the overall code size, TinyCrypt only implements certain generic timing-attack countermeasures.

Specific Remarks

• SHA-256:
  – The number of bits_hashed in the state is not checked for overflow. Note however that this will only be a problem if you intend to hash more than $2^{64}$ bits, which is an extremely large window.

• HMAC:
  – The HMAC verification process is assumed to be performed by the application. This compares the computed tag with some given tag. Note that conventional memory-comparison methods (such as memcmp function) might be vulnerable to timing attacks; thus be sure to use a constant-time memory comparison function (such as compare_constant_time function provided in lib/utils.c).

• HMAC-PRNG:
  – Before using HMAC-PRNG, you must find an entropy source to produce a seed. PRNGs only stretch the seed into a seemingly random output of arbitrary length. The security of the output is exactly equal to the unpredictability of the seed.
  – NIST SP 800-90A requires three items as seed material in the initialization step: entropy seed, personalization and a nonce (which is not implemented). TinyCrypt requires the personalization byte array and automatically creates the entropy seed using a mandatory call to the re-seed function.

• AES-128:
  – The current implementation does not support other key-lengths (such as 256 bits). Note that if you need AES-256, it doesn't sound as though your application is running in a constrained environment. AES-256 requires keys twice the size as for AES-128, and the key schedule is 40% larger.

• CTR mode:
  – The AES-CTR mode limits the size of a data message they encrypt to $2^{32}$ blocks. If you need to encrypt larger data sets, your application would need to replace the key after $2^{32}$ block encryptions.

• CBC mode:
  – TinyCrypt CBC decryption assumes that the iv and the ciphertext are contiguous (as produced by TinyCrypt CBC encryption). This allows for a very efficient decryption algorithm that would not otherwise be possible.

• CMAC mode:
  – AES128-CMAC mode of operation offers 64 bits of security against collision attacks. Note however that an external attacker cannot generate the tags him/herself without knowing the MAC key. In this sense, to attack the collision property of AES128-CMAC, an external attacker would need the cooperation of the legal user to produce an exponentially high number of tags (e.g. $2^{64}$) to finally be able to look for collisions and benefit from them. As an extra precaution, the current implementation allows to at most $2^{48}$ calls to tc_cmac_update function before re-calling tc_cmac_setup (allowing a new key to be set), as suggested in Appendix B of SP 800-38B.

• CCM mode:
There are a few tradeoffs for the selection of the parameters of CCM mode. In special, there is a tradeoff between the maximum number of invocations of CCM under a given key and the maximum payload length for those invocations. Both things are related to the parameter ‘q’ of CCM mode. The maximum number of invocations of CCM under a given key is determined by the nonce size, which is: 15-q bytes. The maximum payload length for those invocations is defined as 2^8q bytes.

To achieve minimal code size, TinyCrypt CCM implementation fixes q = 2, which is a quite reasonable choice for constrained applications. The implications of this choice are:

The nonce size is: 13 bytes.
The maximum payload length is: 2^16 bytes = 65 KB.

The mac size parameter is an important parameter to estimate the security against collision attacks (that aim at finding different messages that produce the same authentication tag). TinyCrypt CCM implementation accepts any even integer between 4 and 16, as suggested in SP 800-38C.

TinyCrypt CCM implementation accepts associated data of any length between 0 and (2^16 - 2^8) = 65280 bytes.

TinyCrypt CCM implementation accepts:
* Both non-empty payload and associated data (it encrypts and authenticates the payload and only authenticates the associated data);
* Non-empty payload and empty associated data (it encrypts and authenticates the payload);
* Non-empty associated data and empty payload (it degenerates to an authentication-only mode on the associated data).

RFC-3610, which also specifies CCM, presents a few relevant security suggestions, such as: it is recommended for most applications to use a mac size greater than 8. Besides, it is emphasized that the usage of the same nonce for two different messages which are encrypted with the same key obviously destroys the security properties of CCM mode.

- ECC-DH and ECC-DSA:

TinyCrypt ECC implementation is based on nano-ecc (see https://github.com/iSECPartners/nano-ecc) which in turn is based on micro-ecc (see https://github.com/kmackay/micro-ecc). In the original nano and micro-ecc documentation, there is an important remark about the way integers are represented:

“Integer representation: To reduce code size, all large integers are represented using little-endian words - so the least significant word is first. You can use the ‘ecc_bytes2native()’ and ‘ecc_native2bytes()’ functions to convert between the native integer representation and the standardized octet representation.”

Examples of Applications

It is possible to do useful cryptography with only the given small set of primitives. With this list of primitives it becomes feasible to support a range of cryptography usages:

- Measurement of code, data structures, and other digital artifacts (SHA256);
- Generate commitments (SHA256);
- Construct keys (HMAC-SHA256);
- Extract entropy from strings containing some randomness (HMAC-SHA256);
- Construct random mappings (HMAC-SHA256);
- Construct nonces and challenges (HMAC-PRNG);
- Authenticate using a shared secret (HMAC-SHA256);
- Create an authenticated, replay-protected session (HMAC-SHA256 + HMAC-PRNG);
- Authenticated encryption (AES-128 + AES-CCM);
- Key-exchange (EC-DH);
- Digital signature (EC-DSA);

Test Vectors

The library provides a test program for each cryptographic primitive (see ‘test’ folder). Besides illustrating how to use the primitives, these tests evaluate the correctness of the implementations by checking the results against well-known publicly validated test vectors.

For the case of the HMAC-PRNG, due to the necessity of performing an extensive battery test to produce meaningful conclusions, we suggest the user to evaluate the unpredictability of the implementation by using the NIST Statistical Test Suite (see References).

For the case of the EC-DH and EC-DSA implementations, most of the test vectors were obtained from the site of the NIST Cryptographic Algorithm Validation Program (CAVP), see References.

References

- NIST FIPS PUB 180-4 (SHA-256)
- NIST FIPS PUB 197 (AES-128)
- NIST SP800-90A (HMAC-PRNG)
- NIST SP 800-38A (AES-CBC and AES-CTR)
- NIST SP 800-38B (AES-CMAC)
- NIST SP 800-38C (AES-CCM)
- NIST Statistical Test Suite
- NIST Cryptographic Algorithm Validation Program (CAVP) site
- RFC 2104 (HMAC-SHA256)
- RFC 6090 (ECC-DH and ECC-DSA)

4.1.2 Random Number Generation

The random API subsystem provides random number generation APIs in both cryptographically and non-cryptographically secure instances. Which random API to use is based on the cryptographic requirements of the random number. The non-cryptographic APIs will return random values much faster if non-cryptographic values are needed.

The cryptographically secure random functions shall be compliant to the FIPS 140-2 [?] recommended algorithms. Hardware based random-number generators (RNG) can be used on platforms with appropriate hardware support. Platforms without hardware RNG support shall use the CTR-DRBG algorithm. The algorithm can be provided by TinyCrypt or mbedTLS depending on your application performance and resource requirements.

Note: The CTR-DRBG generator needs an entropy source to establish and maintain the cryptographic security of the PRNG.
Kconfig Options

These options can be found in the following path `subsys/random/Kconfig`.

- **CONFIG_TEST RANDOM GENERATOR**
  For testing, this option permits random number APIs to return values that are not truly random.

The random number generator choice group allows selection of the RNG source function for the system via the `RNG_GENERATOR_CHOICE` choice group. An override of the default value can be specified in the SOC or board `.defconfig` file by using:

```choice RNG_GENERATOR_CHOICE
    default XOSHIRO_RANDOM_GENERATOR
endchoice```

The random number generators available include:

- **CONFIG_TIMER_RANDOM_GENERATOR**
  enables number generator based on system timer clock. This number generator is not random and used for testing only.

- **CONFIG_ENTROPY_DEVICE_RANDOM_GENERATOR**
  enables a random number generator that uses the enabled hardware entropy gathering driver to generate random numbers.

- **CONFIG_XOSHIRO_RANDOM_GENERATOR**
  enables the Xoshiro128++ pseudo-random number generator, that uses the entropy driver as a seed source.

The CSPRNG_GENERATOR_CHOICE choice group provides selection of the cryptographically secure random number generator source function. An override of the default value can be specified in the SOC or board `.defconfig` file by using:

```choice CSPRNG_GENERATOR_CHOICE
    default CTR_DRBG_CSPRNG_GENERATOR
endchoice```

The cryptographically secure random number generators available include:

- **CONFIG_HARDWARE DEVICE_CS_GENERATOR**
  enables a cryptographically secure random number generator using the hardware random generator driver

- **CONFIG_CTR_DRBG_CSPRNG_GENERATOR**
  enables the CTR-DRBG pseudo-random number generator. The CTR-DRBG is a FIPS140-2 recommended cryptographically secure random number generator.

Personalization data can be provided in addition to the entropy source to make the initialization of the CTR-DRBG as unique as possible.

```CONFIG_CS_CTR_DRBG_PERSONALIZATION
    CTR-DRBG Initialization Personalization string```

API Reference

`group random_api`

Random Function APIs.
uint32_t sys_rand32_get(void)
   Return a 32-bit random value that should pass general randomness tests.

   **Note:** The random value returned is not a cryptographically secure random number value.

   **Returns**
   32-bit random value.

void sys_rand_get(void *dst, size_t len)
   Fill the destination buffer with random data values that should pass general randomness tests.

   **Note:** The random values returned are not considered cryptographically secure random number values.

   **Parameters**
   • dst – [out] destination buffer to fill with random data.
   • len – size of the destination buffer.

int sys_csrand_get(void *dst, size_t len)
   Fill the destination buffer with cryptographically secure random data values.

   **Note:** If the random values requested do not need to be cryptographically secure then use `sys_rand_get()` instead.

   **Parameters**
   • dst – [out] destination buffer to fill.
   • len – size of the destination buffer.

   **Returns**
   0 if success, -EIO if entropy reseed error

### 4.1.3 Crypto APIs

**Overview**

**API Reference**

**Generic API for crypto drivers**

`group crypto`

Crypto APIs.

**Defines**

- `CAP_OPAQUE_KEY_HNDL`
- `CAP_RAW_KEY`

4.1. Cryptography
CAP_KEY_LOADING_API

CAP_INPLACE_OPS
  Whether the output is placed in separate buffer or not

CAP_SEPARATE_IO_BUFS

CAP_SYNC_OPS
  These denotes if the output (completion of a cipher_xxx_op) is conveyed by the op function returning, or it is conveyed by an async notification

CAP_ASYNC_OPS

CAP_AUTONONCE
  Whether the hardware/driver supports autononce feature

CAP_NO_IV_PREFIX
  Don’t prefix IV to cipher blocks

Functions

static inline int crypto_query_hwcaps(const struct device *dev)
  Query the crypto hardware capabilities.

  This API is used by the app to query the capabilities supported by the crypto device. Based on this the app can specify a subset of the supported options to be honored for a session during cipher_begin_session().

  Parameters
  • dev – Pointer to the device structure for the driver instance.

  Returns
  bitmask of supported options.

struct crypto_driver_api
  #include <crypto.h> Crypto driver API definition.

Ciphers API

group crypto_cipher
  Crypto Cipher APIs.

Typedefs

typedef int (*block_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt)

typedef int (*cbc_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)

typedef int (*ctr_op_t)(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *ctr)
typedef int (*ccm_op_t)(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)

typedef int (*gcm_op_t)(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)

typedef void (*cipher_completion_cb)(struct cipher_pkt *completed, int status)

Enums

enum cipher_algo
    Cipher Algorithm

    Values:

    enumerator CRYPTO_CIPHER_ALGO_AES = 1

enum cipher_op
    Cipher Operation

    Values:

    enumerator CRYPTO_CIPHER_OP_DECRYPT = 0

    enumerator CRYPTO_CIPHER_OP_ENCRYPT = 1

enum cipher_mode
    Possible cipher mode options.
    More to be added as required.

    Values:

    enumerator CRYPTO_CIPHER_MODE_ECB = 1

    enumerator CRYPTO_CIPHER_MODE_CBC = 2

    enumerator CRYPTO_CIPHER_MODE_CTR = 3

    enumerator CRYPTO_CIPHER_MODE_CCM = 4

    enumerator CRYPTO_CIPHER_MODE_GCM = 5

Functions

static inline int cipher_begin_session(const struct device *dev, struct cipher_ctx *ctx, enum cipher_algo algo, enum cipher_mode mode, enum cipher_op optype)

    Setup a crypto session.

    Initializes one time parameters, like the session key, algorithm and cipher mode which may remain constant for all operations in the session. The state may be cached in hardware and/or driver data state variables.
Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **ctx** – Pointer to the context structure. Various one-time parameters like key, keylength, etc. are supplied via this structure. The structure documentation specifies which fields are to be populated by the app before making this call.
- **algo** – The crypto algorithm to be used in this session. e.g AES
- **mode** – The cipher mode to be used in this session. e.g CBC, CTR
- **optype** – Whether we should encrypt or decrypt in this session

Returns

0 on success, negative errno code on fail.

```c
static inline int cipher_free_session(const struct device *dev, struct cipher_ctx *ctx)
```

Cleanup a crypto session.

Clears the hardware and/or driver state of a previous session.

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **ctx** – Pointer to the crypto context structure of the session to be freed.

Returns

0 on success, negative errno code on fail.

```c
static inline int cipher_callback_set(const struct device *dev, cipher_completion_cb cb)
```

Registers an async crypto op completion callback with the driver.

The application can register an async crypto op completion callback handler to be invoked by the driver, on completion of a prior request submitted via cipher_do_op(). Based on crypto device hardware semantics, this is likely to be invoked from an ISR context.

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **cb** – Pointer to application callback to be called by the driver.

Returns

0 on success, -ENOTSUP if the driver does not support async op, negative errno code on other error.

```c
static inline int cipher_block_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt)
```

Perform single-block crypto operation (ECB cipher mode). This should not be overloaded to operate on multiple blocks for security reasons.

Parameters

- **ctx** – Pointer to the crypto context of this op.
- **pkt** – Structure holding the input/output buffer pointers.

Returns

0 on success, negative errno code on fail.

```c
static inline int cipher_cbc_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)
```

Perform Cipher Block Chaining (CBC) crypto operation.

Parameters

- **ctx** – Pointer to the crypto context of this op.
- **pkt** – Structure holding the input/output buffer pointers.
• \textit{iv} – Initialization Vector (IV) for the operation. Same IV value should not be reused across multiple operations (within a session context) for security.

**Returns**
0 on success, negative errno code on fail.

static inline int cipher_ctr_op(struct cipher_ctx *ctx, struct cipher_pkt *pkt, uint8_t *iv)
Perform Counter (CTR) mode crypto operation.

**Parameters**
• \textit{ctx} – Pointer to the crypto context of this op.
• \textit{pkt} – Structure holding the input/output buffer pointers.
• \textit{iv} – Initialization Vector (IV) for the operation. We use a split counter formed by appending IV and ctr. Consequently ivlen = keylen - ctrlen. ‘ctrlen’ is specified during session setup through the ‘ctx.mode_params.ctr_params.ctr_len’ parameter. IV should not be reused across multiple operations (within a session context) for security. The non-IV part of the split counter is transparent to the caller and is fully managed by the crypto provider.

**Returns**
0 on success, negative errno code on fail.

static inline int cipher_ccm_op(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)
Perform Counter with CBC-MAC (CCM) mode crypto operation.

**Parameters**
• \textit{ctx} – Pointer to the crypto context of this op.
• \textit{pkt} – Structure holding the input/output, Associated Data (AD) and auth tag buffer pointers.
• \textit{nonce} – Nonce for the operation. Same nonce value should not be reused across multiple operations (within a session context) for security.

**Returns**
0 on success, negative errno code on fail.

static inline int cipher_gcm_op(struct cipher_ctx *ctx, struct cipher_aead_pkt *pkt, uint8_t *nonce)
Perform Galois/Counter Mode (GCM) crypto operation.

**Parameters**
• \textit{ctx} – Pointer to the crypto context of this op.
• \textit{pkt} – Structure holding the input/output, Associated Data (AD) and auth tag buffer pointers.
• \textit{nonce} – Nonce for the operation. Same nonce value should not be reused across multiple operations (within a session context) for security.

**Returns**
0 on success, negative errno code on fail.

```c
struct cipher_ops
#include <cipher.h>

struct ccm_params
#include <cipher.h>
```
struct 

    #include <cipher.h>

struct 

    #include <cipher.h>

struct 

    #include <cipher.h> Structure encoding session parameters.
    Refer to comments for individual fields to know the contract in terms of who fills what and when w.r.t begin_session() call.

Public Members

struct cipher_ops ops

    Place for driver to return function pointers to be invoked per cipher operation. To be populated by crypto driver on return from begin_session() based on the algo/mode chosen by the app.

union cipher_ctx.[anonymous] key

    To be populated by the app before calling begin_session()

const struct device *device

    The device driver instance this crypto context relates to. Will be populated by the begin_session() API.

void *drv_sessn_state

    If the driver supports multiple simultaneously crypto sessions, this will identify the specific driver state this crypto session relates to. Since dynamic memory allocation is not possible, it is suggested that at build time drivers allocate space for the max simultaneous sessions they intend to support. To be populated by the driver on return from begin_session().

void *app_sessn_state

    Place for the user app to put info relevant stuff for resuming when completion callback happens for async ops. Totally managed by the app.

union cipher_ctx.[anonymous] mode_params

    Cypher mode parameters, which remain constant for all ops in a session. To be populated by the app before calling begin_session().

uint16_t keylen

    Cryptographic keylength in bytes. To be populated by the app before calling begin_session()

uint16_t tflags

    How certain fields are to be interpreted for this session. (A bitmask of CAP_* below.) To be populated by the app before calling begin_session(). An app can obtain the capability flags supported by a hw/driver by calling crypto_query_hwcaps().

struct cipher_pkt

#include <cipher.h> Structure encoding IO parameters of one cryptographic operation like encrypt/decrypt.

The fields which has not been explicitly called out has to be filled up by the app before making the cipher_xxx_op() call.

Public Members

uint8_t *in_buf
Start address of input buffer

int in_len
Bytes to be operated upon

uint8_t *out_buf
Start of the output buffer, to be allocated by the application. Can be NULL for in-place ops. To be populated with contents by the driver on return from op / async callback.

int out_buf_max
Size of the out_buf area allocated by the application. Drivers should not write past the size of output buffer.

int out_len
To be populated by driver on return from cipher_xxx_op() and holds the size of the actual result.

struct cipher_ctx *ctx
Context this packet relates to. This can be useful to get the session details, especially for async ops. Will be populated by the cipher_xxx_op() API based on the ctx parameter.

struct cipher_aead_pkt

#include <cipher.h> Structure encoding IO parameters in AEAD (Authenticated Encryption with Associated Data) scenario like in CCM.

App has to furnish valid contents prior to making cipher_ccm_op() call.

Public Members

uint8_t *ad
Start address for Associated Data. This has to be supplied by app.

uint32_t ad_len
Size of Associated Data. This has to be supplied by the app.

uint8_t *tag
Start address for the auth hash. For an encryption op this will be populated by the driver when it returns from cipher_ccm_op call. For a decryption op this has to be supplied by the app.
4.2 Debugging

4.2.1 Thread analyzer

The thread analyzer module enables all the Zephyr options required to track the thread information, e.g. thread stack size usage and other runtime thread runtime statistics.

The analysis is performed on demand when the application calls `thread_analyzer_run()` or `thread_analyzer_print()`.

For example, to build the synchronization sample with Thread Analyser enabled, do the following:

```bash
west build -b qemu_x86 samples/synchronization/ -- -DCONFIG_QEMU_ICOUNT=n -
-DCONFIG_THREAD_ANALYZER=y \
-DCONFIG_THREAD_ANALYZER_USE_PRINTK=y -DCONFIG_THREAD_ANALYZER_AUTO=y \
-DCONFIG_THREAD_ANALYZER_AUTO_INTERVAL=5
```

When you run the generated application in Qemu, you will get the additional information from Thread Analyzer:

```
thread_a: Hello World from cpu 0 on qemu_x86!
Thread analyze:
thread_b: STACK: unused 740 usage 284 / 1024 (27 %); CPU: 0 %
thread_analyzer: STACK: unused 8 usage 504 / 512 (98 %); CPU: 0 %
thread_a: STACK: unused 648 usage 376 / 1024 (36 %); CPU: 98 %
idle: STACK: unused 204 usage 116 / 320 (36 %); CPU: 0 %
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
Thread analyze:
thread_b: STACK: unused 648 usage 376 / 1024 (36 %); CPU: 7 %
thread_analyzer: STACK: unused 8 usage 504 / 512 (98 %); CPU: 0 %
thread_a: STACK: unused 648 usage 376 / 1024 (36 %); CPU: 9 %
idle: STACK: unused 204 usage 116 / 320 (36 %); CPU: 82 %
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
Thread analyze:
thread_b: STACK: unused 648 usage 376 / 1024 (36 %); CPU: 7 %
thread_analyzer: STACK: unused 8 usage 504 / 512 (98 %); CPU: 0 %
thread_a: STACK: unused 648 usage 376 / 1024 (36 %); CPU: 8 %
idle: STACK: unused 204 usage 116 / 320 (36 %); CPU: 83 %
thread_b: Hello World from cpu 0 on qemu_x86!
thread_a: Hello World from cpu 0 on qemu_x86!
thread_b: Hello World from cpu 0 on qemu_x86!
```
Configuration

Configure this module using the following options.

- **THREAD_ANALYZER**: enable the module.
- **THREAD_ANALYZER_USE_PRINTK**: use printk for thread statistics.
- **THREAD_ANALYZER_USE_LOG**: use the logger for thread statistics.
- **THREAD_ANALYZER_AUTO**: run the thread analyzer automatically. You do not need to add any code to the application when using this option.
- **THREAD_ANALYZER_AUTO_INTERVAL**: the time for which the module sleeps between consecutive printing of thread analysis in automatic mode.
- **THREAD_ANALYZER_AUTO_STACK_SIZE**: the stack for thread analyzer automatic thread.
- **THREAD_NAME**: enable this option in the kernel to print the name of the thread instead of its ID.
- **THREAD_RUNTIME_STATS**: enable this option to print thread runtime data such as utilization (This options is automatically selected by THREAD_ANALYZER).

API documentation

*group* **thread_analyzer**

Module for analyzing threads.
This module implements functions and the configuration that simplifies thread analysis.

*Typedefs*

typedef void (*thread_analyzer_cb)(struct thread_analyzer_info *info)

Thread analyzer stack size callback function.
Callback function with thread analysis information.

**Param info**

Thread analysis information.

*Functions*

void **thread_analyzer_run**(thread_analyzer_cb cb)

Run the thread analyzer and provide information to the callback.
This function analyzes the current state for all threads and calls a given callback on every thread found.

**Parameters**

- **cb** – The callback function handler

void **thread_analyzer_print**(void)

Run the thread analyzer and print stack size statistics.
This function runs the thread analyzer and prints the output in standard form.

struct thread_analyzer_info

```
#include <thread_analyzer.h>
```
Public Members

const char *name
    The name of the thread or stringified address of the thread handle if name is not set.

size_t stack_size
    The total size of the stack

size_t stack_used
    Stack size in used

4.2.2 Core Dump

The core dump module enables dumping the CPU registers and memory content for offline debugging. This module is called when a fatal error is encountered and prints or stores data according to which backends are enabled.

Configuration

Configure this module using the following options.

- DEBUG_COREDUMP: enable the module.

Here are the options to enable output backends for core dump:

- DEBUG_COREDUMP_BACKEND_LOGGING: use log module for core dump output.
- DEBUG_COREDUMP_BACKEND_NULL: fallback core dump backend if other backends cannot be enabled. All output is sent to null.

Here are the choices regarding memory dump:

- DEBUG_COREDUMP_MEMORY_DUMP_MIN: only dumps the stack of the exception thread, its thread struct, and some other bare minimal data to support walking the stack in the debugger. Use this only if absolute minimum of data dump is desired.

Additional memory can be included in a dump (even with the “DEBUG_COREDUMP_MEMORY_DUMP_MIN” config selected) through one or more core dump devices

Usage

When the core dump module is enabled, during a fatal error, CPU registers and memory content are printed or stored according to which backends are enabled. This core dump data can be fed into a custom-made GDB server as a remote target for GDB (and other GDB compatible debuggers). CPU registers, memory content and stack can be examined in the debugger.

This usually involves the following steps:

1. Get the core dump log from the device depending on enabled backends. For example, if the log module backend is used, get the log output from the log module backend.
2. Convert the core dump log into a binary format that can be parsed by the GDB server. For example, scripts/coredump/coredump_serial_log_parser.py can be used to convert the serial console log into a binary file.
3. Start the custom GDB server using the script scripts/coredump/coredump_gdbserver.py with the core dump binary log file, and the Zephyr ELF file as parameters.
4. Start the debugger corresponding to the target architecture.
**Note:** Developers for Intel ADSP CAVS 15-25 platforms using `ZEPHYR_TOOLCHAIN_VARIANT=zephyr` should use the debugger in the xtensa-intel_apl_adsp toolchain of the SDK.

**Example**  This example uses the log module backend tied to serial console. This was done on qemu_x86 where a null pointer was dereferenced.

This is the core dump log from the serial console, and is stored in coredump.log:

```
Booting from ROM...*** Booting Zephyr OS build zephyr-v2.3.0-1840-g7bba9144a63 ***
Hello World! qemu_x86
E: Page fault at address 0x0 (error code 0x2)
E: Linear address not present in page tables
E: PDE: 0x0000000000115827Writable, User, Execute Enabled
E: PTE: Non-present
E: EAX: 0x00000000, EBX: 0x00000000, ECX: 0x00119d74, EDX: 0x0000003f8
E: ESI: 0x00000000, EDI: 0x00119d10, ESP: 0x00119d00
E: EFLAGS: 0x00000206 CS: 0x0008 CR3: 0x00119000
E: call trace:
E: EIP: 0x00100459
E: 0x00100477 (0x0)
E: 0x00100492 (0x0)
E: 0x001004c8 (0x0)
E: 0x00105465 (0x105465)
E: 0x00101abe (0x0)
E: >>> ZEPHYR FATAL ERROR 0: CPU exception on CPU 0
E: Current thread: 0x00119080 (unknown)
E: #CD:BEGIN#
```

(continues on next page)
1. Run the core dump serial log converter:

   ./scripts/coredump/coredump_serial_log_parser.py coredump.log coredump.bin

2. Start the custom GDB server:

   ./scripts/coredump/coredump_gdbserver.py build/zephyr/zephyr.elf coredump.bin

3. Start GDB:

   <path to SDK>/x86_64-zephyr-elf/bin/x86_64-zephyr-elf-gdb build/zephyr/zephyr.elf

4. Inside GDB, connect to the GDB server via port 1234:

   (gdb) target remote localhost:1234

5. Examine the CPU registers:

   (gdb) info registers

   Output from GDB:

   
   | eax   | 0x0   | 0   |
   | ecx   | 0x119d74 | 1154420 |
   | edx   | 0x3f8 | 1016 |
   | ebx   | 0x0   | 0   |
   | esp   | 0x119d00 | 0x119d00 <z_main_stack+844> |
   | ebp   | 0x119d10 | 0x119d10 <z_main_stack+860> |
   | esi   | 0x0   | 0   |
   | edi   | 0x101aa7 | 1055399 |
   | eip   | 0x100459 | 0x100459 <func_3+16> |
   | eflags | 0x206 | [ PF IF ] |
   | cs    | 0x8   | 8   |
   | ss    | <unavailable> |
   | ds    | <unavailable> |
   | es    | <unavailable> |
   | fs    | <unavailable> |
   | gs    | <unavailable> |

6. Examine the backtrace:

   (gdb) bt
Output from GDB:

```c
#0 0x00100459 in func_3 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:14
#1 0x00100477 in func_2 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:21
#2 0x00100492 in func_1 (addr=0x0) at zephyr/rtos/zephyr/samples/hello_world/src/main.c:28
#3 0x001004c8 in main () at zephyr/rtos/zephyr/samples/hello_world/src/main.c:42
```

File Format

The core dump binary file consists of one file header, one architecture-specific block, and multiple memory blocks. All numbers in the headers below are little endian.

**File Header**  The file header consists of the following fields:

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of the header. This needs to be incremented whenever the header struct is modified. This allows parser to reject older header versions so it will not incorrectly parse the header.</td>
</tr>
<tr>
<td>Target code</td>
<td>uint16_t</td>
<td>Indicate which target (e.g. architecture or SoC) so the parser can instantiate the correct register block parser.</td>
</tr>
<tr>
<td>Pointer size</td>
<td>'uint8_t'</td>
<td>Size of uintptr_t in power of 2. (e.g. 5 for 32-bit, 6 for 64-bit). This is needed to accommodate 32-bit and 64-bit target in parsing the memory block addresses.</td>
</tr>
<tr>
<td>Flags</td>
<td>uint8_t</td>
<td></td>
</tr>
<tr>
<td>Fatal error reason</td>
<td>unsigned int</td>
<td>Reason for the fatal error, as the same in enum k_fatal_error_reason defined in include/zephyr/fatal.h</td>
</tr>
</tbody>
</table>

**Architecture-specific Block**  The architecture-specific block contains the byte stream of data specific to the target architecture (e.g. CPU registers)

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ID</td>
<td>char</td>
<td>'A' to indicate this is a architecture-specific block.</td>
</tr>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of this block. To be interpreted by the target architecture specific block parser.</td>
</tr>
<tr>
<td>Number of bytes</td>
<td>uint16_t</td>
<td>Number of bytes following the header which contains the byte stream for target data. The format of the byte stream is specific to the target and is only being parsed by the target parser.</td>
</tr>
<tr>
<td>Register stream</td>
<td>byte uint8_t</td>
<td>Contains target architecture specific data.</td>
</tr>
</tbody>
</table>

**Memory Block**  The memory block contains the start and end addresses and the data within the memory region.

4.2. Debugging
Table 4.3: Memory Block

<table>
<thead>
<tr>
<th>Field</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ID</td>
<td>char</td>
<td>M to indicate this is a memory block.</td>
</tr>
<tr>
<td>Header version</td>
<td>uint16_t</td>
<td>Identify the version of the header. This needs to be incremented whenever the header struct is modified. This allows parser to reject older header versions so it will not incorrectly parse the header.</td>
</tr>
<tr>
<td>Start address</td>
<td>uintptr_t</td>
<td>The start address of the memory region.</td>
</tr>
<tr>
<td>End address</td>
<td>uintptr_t</td>
<td>The end address of the memory region.</td>
</tr>
<tr>
<td>Memory stream byte</td>
<td>uint8_t[]</td>
<td>Contains the memory content between the start and end addresses.</td>
</tr>
</tbody>
</table>

Adding New Target

The architecture-specific block is target specific and requires new dumping routine and parser for new targets. To add a new target, the following needs to be done:

1. Add a new target code to the enum coredump_tgt_code in include/zephyr/debug/coredump.h.
2. Implement arch_coredump_tgt_code_get() simply to return the newly introduced target code.
3. Implement arch_coredump_info_dump() to construct a target architecture block and call coredump_buffer_output() to output the block to core dump backend.
4. Add a parser to the core dump GDB stub scripts under scripts/coredump/gdbstubs/
   1. Extends the gdbstubs.gdbstub.GdbStub class.
   2. During __init__, store the GDB signal corresponding to the exception reason in self.gdb_signal.
   3. Parse the architecture-specific block from self.logfile.get_arch_data(). This needs to match the format as implemented in step 3 (inside arch_coredump_info_dump()).
   4. Implement the abstract method handle_register_group_read_packet where it returns the register group as GDB expected. Refer to GDB's code and documentation on what it is expecting for the new target.
   5. Optionally implement handle_register_single_read_packet for registers not covered in the g packet.
5. Extend get_gdbstub() in scripts/coredump/gdbstubs/__init__.py to return the newly implemented GDB stub.

API documentation

`group coredump_apis`

Coredump APIs.

`Functions`

void coredump(unsigned int reason, const z_arch_esf_t *esf, struct k_thread *thread)

Perform coredump.

Normally, this is called inside z_fatal_error() to generate coredump when a fatal error is encountered. This can also be called on demand whenever a coredump is desired.

`Parameters`
void coredump_memory_dump(uintptr_t start_addr, uintptr_t end_addr)
Dump memory region.

Parameters
• start_addr – Start address of memory region to be dumped
• end_addr – End address of memory region to be dumped

void coredump_buffer_output(uint8_t *buf, size_t buflen)
Output the buffer via coredump.
This outputs the buffer of byte array to the coredump backend. For example, this can be called to output the coredump section containing registers, or a section for memory dump.

Parameters
• buf – Buffer to be send to coredump output
• buflen – Buffer length

int coredump_query(enum coredump_query_id query_id, void *arg)
Perform query on coredump subsystem.
Query the coredump subsystem for information, for example, if there is an error.

Parameters
• query_id – [in] Query ID
• arg – [inout] Pointer to argument for exchanging information

Returns
Depends on the query

int coredump_cmd(enum coredump_cmd_id query_id, void *arg)
Perform command on coredump subsystem.
Perform certain on coredump subsystem, for example, output the stored coredump via logging.

Parameters
• cmd_id – [in] Command ID
• arg – [inout] Pointer to argument for exchanging information

Returns
Depends on the command

Functions

void arch_coredump_info_dump(const z_arch_esf_t *esf)
Architecture-specific handling during coredump.
This dumps architecture-specific information during coredump.

Parameters
• esf – Exception Stack Frame (arch-specific)
uint16_t arch_coredump_tgt_code_get(void)

Get the target code specified by the architecture.

4.2.3 GDB stub

- **Overview**
- **Features**
  - **Enabling GDB Stub**
    - Using Serial Backend
  - **Debugging**
    - Using Serial Backend
  - **Example**

**Overview**

The gdbstub feature provides an implementation of the GDB Remote Serial Protocol (RSP) that allows you to remotely debug Zephyr using GDB.

The protocol supports different connection types: serial, UDP/IP and TCP/IP. Zephyr currently supports only serial device communication.

The GDB program acts as the client while Zephyr acts as the server. When this feature is enabled, Zephyr stops its execution after `gdb_init()` starts gdbstub service and waits for a GDB connection. Once a connection is established it is possible to synchronously interact with Zephyr. Note that currently it is not possible to asynchronously send commands to the target.

**Features**

The following features are supported:

- Add and remove breakpoints
- Continue and step the target
- Print backtrace
- Read or write general registers
- Read or write the memory

**Enabling GDB Stub**

GDB stub can be enabled with the `CONFIG_GDBSTUB` option.

**Using Serial Backend** The serial backend for GDB stub can be enabled with the `CONFIG_GDBSTUB_SERIAL_BACKEND` option.

Since serial backend utilizes UART devices to send and receive GDB commands,

- If there are spare UART devices on the board, set `zephyr,gdbstub-uart` property of the chosen node to the spare UART device so that `printk()` and log messages are not being printed to the same UART device used for GDB.
For boards with only one UART device, printk() and logging must be disabled if they are also using the same UART device for output. GDB related messages may interleave with log messages which may have unintended consequences. Usually this can be done by disabling CONFIG_PRINTK and CONFIG_LOG.

Debugging

Using Serial Backend

1. Build with GDB stub and serial backend enabled.
2. Flash built image onto board and reset the board.
   • Execution should now be paused at gdb_init().
3. Execute GDB on development machine and connect to the GDB stub.

   ```
   target remote <serial device>
   ```

   For example,

   ```
   target remote /dev/ttyUSB1
   ```

4. GDB commands can be used to start debugging.

Example

This is an example using samples/subsys/debug/gdbstub to demonstrate how GDB stub works.

1. Open two terminal windows.
2. On the first terminal, build and run the sample:

   ```
   # From the root of the zephyr repository
   west build -b qemu_x86 samples/subsys/debug/gdbstub
   west build -t run
   ```

3. On the second terminal, start GDB:

   ```
   <SDK install directory>/x86_64-zephyr-elf/bin/x86_64-zephyr-elf-gdb
   ```

   1. Tell GDB where to look for the built ELF file:

   ```
   (gdb) file <build directory>/zephyr/zephyr.elf
   ```

   Response from GDB:

   ```
   Reading symbols from <build directory>/zephyr/zephyr.elf...
   ```

   2. Tell GDB to connect to the server:

   ```
   (gdb) target remote localhost:5678
   ```

   Note that QEMU is setup to redirect the serial used for GDB stub in the Zephyr image to a networking port. Hence the connection to localhost, port 5678.

   Response from GDB:

   ```
   Remote debugging using :5678
   arch_gdb_init () at <ZEPHYR_BASE>/arch/x86/core/ia32/gdbstub.c:232
   232   }
   ```
GDB also shows where the code execution is stopped. In this case, it is at `arch/x86/core/ia32/gdbstub.c`, line 232.

3. Use command `bt` or `backtrace` to show the backtrace of stack frames.

```plaintext
(gdb) bt
#0 arch_gdb_init () at <ZEPHYR_BASE>/arch/x86/core/ia32/gdbstub.c:232
#1 0x00105068 in gdb_init (arg=0x0) at <ZEPHYR_BASE>/subsys/debug/gdbstub.
    -- c:833
#2 0x001009d6f in z_sys_init_run_level (level=0x1) at <ZEPHYR_BASE>/kernel/
    -- device.c:72
#3 0x0010a40b in z_cstart () at <ZEPHYR_BASE>/kernel/init.c:423
#4 0x00105383 in z_x86_prep_c (arg=0x9500) at <ZEPHYR_BASE>/arch/x86/core/
    -- prep_c.c:58
#5 0x0010000a9 in __csSet () at <ZEPHYR_BASE>/arch/x86/core/ia32/crt0.S:273
```

4. Use command `list` to show the source code and surroundings where code execution is stopped.

```plaintext
(gdb) list
227     }
228
229     void arch_gdb_init(void)
230     {
231         __asm__ volatile("int3");
232     }
233
234     /* Hook current IDT. */
235     _EXCEPTION_CONNECT_NOCODE(z_gdb_debug_isr, IV_DEBUG, 3);
236     _EXCEPTION_CONNECT_NOCODE(z_gdb_break_isr, IV_BREAKPOINT, 3);
```

5. Use command `s` or `step` to step through program until it reaches a different source line. Now that it finished executing `arch_gdb_init()` and is continuing in `gdb_init()`.

```plaintext
(gdb) s
gdb_init (arg=0x0) at /home/dleung5/zephyr/rtos/zephyr/subsys/debug/gdbstub.
    -- c:834
834     return 0;
```

```plaintext
(gdb) list
829     LOG_ERR("Could not initialize gdbstub backend.");
830     return -1;
831     }
832
833     arch_gdb_init();
834     return 0;
835     }
836
837     #ifdef CONFIG_XTENSA
838     /*
```

6. Use command `br` or `break` to setup a breakpoint. This example sets up a breakpoint at `main()`, and let code execution continue without any intervention using command `c` (or `continue`).

```plaintext
(gdb) break main
Breakpoint 1 at 0x1005a9: file <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/
    -- src/main.c, line 32.
(gdb) continue
Continuing.
```
Once code execution reaches `main()`, execution will be stopped and GDB prompt returns.

Breakpoint 1, main () at <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/main.c:32

```
32 ret = test();
```

Now GDB is waiting at the beginning of `main()`:

```
(gdb) list
27
28 void main(void)
29 {
30 int ret;
31 32 ret = test();
33 printk("%d\n", ret);
34 }
35
36 K_THREAD_DEFINE(thread, STACKSIZE, thread_entry, NULL, NULL, NULL,
```

7. To examine the value of `ret`, the command `p` or `print` can be used.

```
(gdb) p ret
$1 = 0x11318c
```

Since `ret` has not been assigned a value yet, what it contains is simply a random value.

8. If step (s or step) is used here, it will continue execution until `printk()` is reached, thus skipping the interior of `test()`. To examine code execution inside `test()`, a breakpoint can be set for `test()`, or simply using `si` (or stepi) to execute one machine instruction, where it has the side effect of going into the function.

```
(gdb) si
```

```
test () at <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/main.c:13
13 {
(gdb) list
8 #include <zephyr/sys/printk.h>
9
10 #define STACKSIZE 512
11
12 static int test(void)
13 {
14    int a;
15    int b;
16    17 a = 10;
```

9. Here, step can be used to go through all code inside `test()` until it returns. Or the command `finish` can be used to continue execution without intervention until the function returns.

```
(gdb) finish
Run till exit from #0 test () at <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/main.c:13
0x001005ae in main () at <ZEPHYR_BASE>/samples/subsys/debug/gdbstub/src/main.c:32
32 ret = test();
Value returned is $2 = 0x1e
```

And now, execution is back to `main()`.
10. Examine `ret` again which should have the return value from `test()`. Sometimes, the assignment is not done until another step is issued, as in this case. This is due to the assignment code is done after returning from function. The assignment code is generated by the toolchain as machine instructions which are not visible when viewing the corresponding C source file.

```
(gdb) p ret
$3 = 0x11318c
(gdb) s
33 printk("%d\n", ret);
(gdb) p ret
$4 = 0x1e
```

11. If `continue` is issued here, code execution will continue indefinitely as there are no breakpoints to further stop execution. Breaking execution in GDB via Ctrl-C does not currently work as the GDB stub does not support this functionality (yet).

### 4.3 Device Management

#### 4.3.1 MCUmgr

**Overview**

The management subsystem allows remote management of Zephyr-enabled devices. The following management operations are available:

- Image management
- File System management
- Log management (currently disabled)
- OS management
- Shell management

over the following transports:

- BLE (Bluetooth Low Energy)
- Serial (UART)
- UDP over IP

The management subsystem is based on the Simple Management Protocol (SMP) provided by MCUmgr, an open source project that provides a management subsystem that is portable across multiple real-time operating systems.

The management subsystem is split in two different locations in the Zephyr tree:

- `zephyrproject-rtos/mcumgr` repo contains a clean import of the MCUmgr project
- `subsys/mgmt/` contains the Zephyr-specific bindings to MCUmgr

Additionally there is a sample that provides management functionality over BLE and serial.

**Command-line Tool**

MCUmgr provides a command-line tool, `mcumgr`, for managing remote devices. The tool is written in the Go programming language.

To install the tool:

```
go version < 1.18
```
go get github.com/apache/mynewt-mcumgr-cli/mcumgr

go version >= 1.18

go install github.com/apache/mynewt-mcumgr-cli/mcumgr@latest

Configuring the transport

There are two command-line options that are responsible for setting and configuring the transport layer to use when communicating with managed device:

- **--conntype** is used to choose the transport used, and
- **--connstring** is used to pass a comma separated list of options in the key=value format, where each valid key depends on the particular conntype.

Valid transports for **--conntype** are serial, ble and udp. Each transport expects a different set of key/value options:

**serial**

**--connstring** accepts the following key values:

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>dev</td>
<td>the device name for the OS mcumgr is running on (eg, /dev/ttyUSB0, /dev/tty.</td>
</tr>
<tr>
<td></td>
<td>usbserial, COM1, etc).</td>
</tr>
<tr>
<td>baud</td>
<td>the communication speed; must match the baudrate of the server.</td>
</tr>
<tr>
<td>mtu</td>
<td>aka Maximum Transmission Unit, the maximum protocol packet size.</td>
</tr>
</tbody>
</table>

**ble**

**--connstring** accepts the following key values:

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ctlr_name</td>
<td>an OS specific string for the controller name.</td>
</tr>
<tr>
<td>own_addr_type</td>
<td>can be one of public, random, rpa_pub, rpa_rnd, where random is the default.</td>
</tr>
<tr>
<td>peer_name</td>
<td>the name the peer BLE device advertises, this should match the configuration specified with CONFIG_BT_DEVICE_NAME.</td>
</tr>
<tr>
<td>peer_id</td>
<td>the peer BLE device address or UUID. Only required when peer_name was not given. The format depends on the OS where mcumgr is run, it is a 6 bytes hexadecimal string separated by colons on Linux, or a 128-bit UUID on macOS.</td>
</tr>
<tr>
<td>conn_timeout</td>
<td>a float number representing the connection timeout in seconds.</td>
</tr>
</tbody>
</table>

**udp**

**--connstring** takes the form [addr]:port where:

<table>
<thead>
<tr>
<th>Key</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>addr</td>
<td>can be a DNS name (if it can be resolved to the device IP), IPv4 addr (app must be built with CONFIG_MCUMGR_SMP_UDP_IPV4), or IPv6 addr (app must be built with CONFIG_MCUMGR_SMP_UDP_IPV6)</td>
</tr>
<tr>
<td>port</td>
<td>any valid UDP port.</td>
</tr>
</tbody>
</table>

Saving the connection config

The transport configuration can be managed with the conn sub-command and later used with **--conn** (or -c) parameter to skip typing both **--conntype** and **--connstring**. For example a new config for a serial device that would require typing mcumgr **--conntype** serial **--connstring** dev=/dev/ttyACM0, baud=115200, mtu=512 can be saved with:
mcumgr conn add acm0 type="serial" connstring="dev=/dev/ttyACM0,baud=115200,mtu=512"

Accessing this port can now be done with:

```
mcumgr -c acm0
```

**General options**

Some options work for every `mcumgr` command and might be helpful to debug and fix issues with the communication, among them the following deserve special mention:

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>-l</code> &lt;log-level&gt;</td>
<td>Configures the log level, which can be one of critical, error, warn, info or debug, from less to most verbose. When there are communication issues, <code>-lDEBUG</code> might be useful to dump the packets for later inspection.</td>
</tr>
<tr>
<td><code>-t</code> &lt;timeout&gt;</td>
<td>Changes the timeout waiting for a response from the default of 10s to a given value. Some commands might take a long time of processing, eg, the erase before an image upload, and might need incrementing the timeout to a larger value.</td>
</tr>
<tr>
<td><code>-r</code> &lt;tries&gt;</td>
<td>Changes the number of retries on timeout from the default of 1 to a given value.</td>
</tr>
</tbody>
</table>

**List of Commands**

Not all commands defined by `mcumgr` (and SMP protocol) are currently supported on Zephyr. The ones that are supported are described in the following table:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>echo</td>
<td>Send data to a device and display the echoed back data. This command is part of the OS group, which must be enabled by setting <code>CONFIG_MCUMGR_CMD_OS_MGMT</code>. The echo command itself can be enabled by setting <code>CONFIG_OS_MGMT_ECHO</code>.</td>
</tr>
<tr>
<td>fs</td>
<td>Access files on a device. More info in Filesystem Management.</td>
</tr>
<tr>
<td>image</td>
<td>Manage images on a device. More info in Image Management.</td>
</tr>
<tr>
<td>reset</td>
<td>Perform a soft reset of a device. This command is part of the OS group, which must be enabled by setting <code>CONFIG_MCUMGR_CMD_OS_MGMT</code>. The reset command itself is always enabled and the time taken for a reset to happen can be set with <code>CONFIG_OS_MGMT_RESET_MS</code> (in ms).</td>
</tr>
<tr>
<td>shell</td>
<td>Execute a command in the remote shell. This option is disabled by default and can be enabled with <code>CONFIG_MCUMGR_CMD_SHELL_MGMT = y</code>. To know more about the shell in Zephyr check Shell.</td>
</tr>
<tr>
<td>taskstat</td>
<td>Read task statistics from a device. This command is part of the OS group, which must be enabled by setting <code>CONFIG_MCUMGR_CMD_OS_MGMT</code>. The taskstat command itself can be enabled by setting <code>CONFIG_OS_MGMT_TASKSTAT</code>. <code>CONFIG_THREAD_MONITOR</code> also needs to be enabled otherwise a <code>-8 (MGMT_ERR_ENOTSUP)</code> will be returned.</td>
</tr>
</tbody>
</table>

**Tip:** Running `mcumgr` with no parameters, or `-h` will display the list of commands.

**Tip:** `taskstat` has a few options that might require tweaking. The `CONFIG_THREAD_NAME` must be set to display the task names, otherwise the priority is displayed. Since the taskstat packets are large, they might need increasing the `CONFIG_MCUMGR_BUF_SIZE` option.
**Warning:** To display the correct stack size in the taskstat command, the `CONFIG_THREAD_STACK_INFO` option must be set. To display the correct stack usage in the taskstat command, both `CONFIG_THREAD_STACK_INFO` and `CONFIG_INIT_STACKS` options must be set.

### J-Link Virtual MSD Interaction Note

On boards where a J-Link OB is present which has both CDC and MSC (virtual Mass Storage Device, also known as drag-and-drop) support, the MSD functionality can prevent mcumgr commands over the CDC UART port from working due to how USB endpoints are configured in the J-Link firmware (for example on the Nordic nrf52840dk) because of limiting the maximum packet size (most likely to occur when using image management commands for updating firmware). This issue can be resolved by disabling MSD functionality on the J-Link device, follow the instructions on nordic_segger_msd to disable MSD support.

### Image Management

The image management provided by `mcumgr` is based on the image format defined by MCUboot. For more details on the internals see [MCUboot design and Signing Binaries](https://zephyrproject.org/docs/device-management/mcumgr.html).

To list available images in a device:

```
mcumgr <connection-options> image list
```

This should result in an output similar to this:

```
$ mcumgr -c acm0 image list
Images:
    image=0 slot=0
    version: 1.0.0
    bootable: true
    flags: active confirmed
    hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fc4d5a9ed00cc7
Split status: N/A (0)
```

Where `image` is the number of the image pair in a multi-image system, and `slot` is the number of the slot where the image is stored, 0 for primary and 1 for secondary. This image being active and confirmed means it will run again on next reset. Also relevant is the hash, which is used by other commands to refer to this specific image when performing operations.

An image can be manually erased using:

```
mcumgr <connection-options> image erase
```

The behavior of `erase` is defined by the server (`mcumgr` in the device). The current implementation is limited to erasing the image in the secondary partition.

To upload a new image:

```
mcumgr <connection-options> image upload [-n] [-e] [-u] [-w] <signed-bin>
```

- `-n`: This option allows uploading a new image to a specific set of images in a multi-image system, and is currently only supported by MCUboot when the `CONFIG_MCUBOOT_SERIAL` option is enabled.
- `-e`: This option avoids performing a full erase of the partition before starting a new upload.
Tip: The `-e` option should always be passed in because the upload command already checks if an erase is required, respecting the CONFIG_IMG_ERASE_PROGRESSIVELY setting.

Tip: If the upload command times out while waiting for a response from the device, `-t` might be used to increase the wait time to something larger than the default of 10s. See general_options.

Warning: mcumgr does not understand .hex files, when uploading a new image always use the .bin file.

- `-u`: This option allows upgrading only to newer image version.
- `-w`: This option allows setting the maximum size for the window of outstanding chunks in transit. It is set to 5 by default.

Tip: If the option is set to a value lower than the default one, for example `-w 1`, less chunks are transmitted on the window, resulting in lower risk of errors. Conversely, setting a value higher than 5 increases risk of errors and may impact performance.

After an image upload is finished, a new image list would now have an output like this:

```
$ mcumgr -c acm0 image upload -e build/zephyr/zephyr.signed.bin
  35.69 KiB / 92.92 KiB [==========>---------------] 38.41% 2.97 KiB/s 00m19
```

Now listing the images again:

```
$ mcumgr -c acm0 image list
Images:
  image=0 slot=0
    version: 1.0.0
    bootable: true
    flags: active confirmed
    hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
  image=0 slot=1
    version: 1.1.0
    bootable: true
    flags:
      hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
Split status: N/A (0)
```

To test a new upgrade image the test command is used:

```
mcumgr <connection-options> image test <hash>
```

This command should mark a test upgrade, which means that after the next reboot the bootloader will execute the upgrade and jump into the new image. If no other image operations are executed on the newly running image, it will revert back to the image that was previously running on the device on the subsequent reset. When a test is requested, flags will be updated with pending to inform that a new image will be run after a reset:

```
$ mcumgr -c acm0 image test
  → e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
Images:
  image=0 slot=0
    version: 1.0.0
```

(continues on next page)
bootable: true
flags: active confirmed
hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
image=0 slot=1
version: 1.1.0
bootable: true
flags: pending
hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
Split status: N/A (0)

After a reset the output with change to:

```
$ mcumgr -c acm0 image list
Images:
  image=0 slot=0
  version: 1.1.0
  bootable: true
  flags: active
  hash: e8cf0dcef3ec8addee07e8c4d5dc89e64ba3fae46a2c5267fc4efbea4ca0e9f4
  image=0 slot=1
  version: 1.0.0
  bootable: true
  flags: confirmed
  hash: 86dca73a3439112b310b5e033d811ec2df728d2264265f2046fced5a9ed00cc7
Split status: N/A (0)
```

**Tip:** It’s important to mention that an upgrade only ever happens if the image is valid. The first thing MCUboot does when an upgrade is requested is to validate the image, using the SHA-256 and/or the signature (depending on the configuration). So before uploading an image, one way to be sure it is valid is to run `imgtool verify -k <your-signature-key> <your-image>`, where `-k <your-signature-key>` can be skipped if no signature validation was enabled.

The `confirmed` flag in the secondary slot tells that after the next reset a revert upgrade will be performed to switch back to the original layout.

The command used to confirm that an image is OK and no revert should happen (no hash required) is:

```
mcumgr <connection-options> image confirm [hash]
```

The `confirm` command can also be run passing in a hash so that instead of doing a test/revert procedure, the image in the secondary partition is directly upgraded to.

**Tip:** The whole test/revert cycle does not need to be done using only the `mcumgr` command-line tool. A better alternative is to perform a test and allow the new running image to self-confirm after any checks by calling `boot_write_img_confirmed()`.

**Tip:** Building with `CONFIG_IMG_MGMT_VERBOSE_ERR` enables better error messages when failures happen (but increases the application size).

### Statistics Management

Statistics are used for troubleshooting, maintenance, and usage monitoring; it consists basically of user-defined counters which are tightly connected to `mcumgr` and can be used to track any information for

---

**4.3. Device Management**
easy retrieval. The available sub-commands are:

```
mcumgr <connection-options> stat list
mcumgr <connection-options> stat <section-name>
```

Statistics are organized in sections (also called groups), and each section can be individually queried. Defining new statistics sections is done by using macros available under `<stats/stats.h>`. Each section consists of multiple variables (or counters), all with the same size (16, 32 or 64 bits).

To create a new section `my_stats`:

```
STATS_SECT_START(my_stats)
   STATS_SECT_ENTRY(my_stat_counter1)
   STATS_SECT_ENTRY(my_stat_counter2)
   STATS_SECT_ENTRY(my_stat_counter3)
STATS_SECT_END;

STATS_SECT_DECL(my_stats) my_stats;
```

Each entry can be declared with `STATS_SECT_ENTRY` (or the equivalent `STATS_SECT_ENTRY32`, `STATS_SECT_ENTRY16` or `STATS_SECT_ENTRY64`). All statistics in a section must be declared with the same size.

The statistics counters can either have names or not, depending on the setting of the `CONFIG_STATS_NAMES` option. Using names requires an extra declaration step:

```
STATS_NAME_START(my_stats)
   STATS_NAME(my_stats, my_stat_counter1)
   STATS_NAME(my_stats, my_stat_counter2)
   STATS_NAME(my_stats, my_stat_counter3)
STATS_NAME_END(my_stats);
```

**Tip:** Disabling `CONFIG_STATS_NAMES` will free resources. When this option is disabled the `STATS_NAME*` macros output nothing, so adding them in the code does not increase the binary size.

**Tip:** `CONFIG_STAT_MGMT_MAX_NAME_LEN` sets the maximum length of a section name that can be accepted as parameter for showing the section data, and might require tweaking for long section names.

The final steps to use a statistics section is to initialize and register it:

```
rc = STATS_INIT_AND_REG(my_stats, STATS_SIZE_32, "my_stats");
assert (rc == 0);
```

In the running code a statistics counter can be incremented by 1 using `STATS_INC`, by N using `STATS_INCN` or reset with `STATS_CLEAR`.

Let's suppose we want to increment those counters by 1, 2 and 3 every second. To get a list of stats:

```
$ mcumgr --conn acm0 stat list
stat groups:
   my_stats
```

To get the current value of the counters in `my_stats`:

```
$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
   13 my_stat_counter1
```

(continues on next page)
$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
 16 my_stat_counter1
 32 my_stat_counter2
 48 my_stat_counter3

When CONFIG_STATS_NAMES is disabled the output will look like this:

$ mcumgr --conn acm0 stat my_stats
stat group: my_stats
     8 s0
    16 s1
    24 s2

### Filesystem Management

The filesystem module is disabled by default due to security concerns: because of a lack of access control every file in the FS will be accessible, including secrets, etc. To enable it CONFIG_MCUMGR_CMD_FS_MGMT must be set (y). Once enabled the following sub-commands can be used:

- `mcumgr <connection-options> fs download <remote-file> <local-file>`
- `mcumgr <connection-options> fs upload <local-file> <remote-file>`

Using the `fs` command, requires CONFIG_FILE_SYSTEM to be enabled, and that some particular filesystem is enabled and properly mounted by the running application, eg for littlefs this would mean enabling CONFIG_FILESYSTEM_LITTLEFS, defining a storage partition *Flash map* and mounting the filesystem in the startup (`fs_mount()`).

Uploading a new file to a littlefs storage, mounted under `/lfs`, can be done with:

```
$ mcumgr -c acm0 fs upload foo.txt /lfs/foo.txt
25
Done
```

Where 25 is the size of the file.

For downloading a file, let's first use the `fs` command (CONFIG_FILESYSTEM_SHELL must be enabled) in a remote shell to create a new file:

```
uart:$ fs write /lfs/bar.txt 41 42 43 44 31 32 33 34 0a
uart:$ fs read /lfs/bar.txt
File size: 9
00000000 41 42 43 44 31 32 33 34 0A ABCD1234.
```

Now it can be downloaded using:

```
$ mcumgr -c acm0 fs download /lfs/bar.txt bar.txt
0
9
Done
$ cat bar.txt
ABCD1234
```

Where 0 is the return code, and 9 is the size of the file.

### 4.3. Device Management
**Warning:** The commands might exhaust the system workqueue, if its size is not large enough, so increasing `CONFIG_SYSTEM_WORKQUEUE_STACK_SIZE` might be required for correct behavior.

The size of the stack allocated buffer used to store the blocks, while transferring a file can be adjusted with `CONFIG_FS_MGMT_DL_CHUNK_SIZE`; this allows saving RAM resources.

**Tip:** `CONFIG_FS_MGMT_PATH_SIZE` sets the maximum PATH accepted for a file name. It might require tweaking for longer file names.

## Bootloader Integration

The **Device Firmware Upgrade** subsystem integrates the management subsystem with the bootloader, providing the ability to send and upgrade a Zephyr image to a device.

Currently only the MCUboot bootloader is supported. See **MCUboot** for more information.

## Discord channel

Developers welcome!

- Discord mcumgr channel: https://discord.com/invite/Ck7jw53nU2

### 4.3.2 MCUmgr Callbacks

#### Overview

MCUmgr has a customisable callback/notification system that allows application (and module) code to receive callbacks for MCUmgr events that they are interested in and react to them or return a status code to the calling function that provides control over if the action should be allowed or not. An example of this is with the fs_mgmt group, whereby file access can be gated, the callback allows the application to inspect the request path and allow or deny access to said file, or it can rewrite the provided path to a different path for transparent file redirection support.

#### Implementation

**Enabling** The base callback/notification system can be enabled using `CONFIG_MCUMGR_MGMT_NOTIFICATION_HOOKS` which will compile the registration and notification system into the code. This will not provide any callbacks by default as the callbacks that are supported by a build must also be selected by enabling the Kconfig's for the required callbacks (see Events for further details). A callback function with the `mgmt_cb` type definition can then be declared and registered by calling `mgmt_callback_register()` for the desired event inside of a `struct mgmt_callback` structure. Handlers are called in the order that they were registered.

With the system enabled, a basic handler can be set up and defined in application code as per:

```c
#include <zephyr/kernel.h>
#include <mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>

struct mgmt_callback my_callback;

int32_t my_function(uint32_t event, int32_t rc, bool *abort_more, void *data,
                     struct k_task *self) {
  return 0;  // Example return
}
```

(continues on next page)
size_t data_size) {
    if (event == MGMT_EVT_OP_CMD_DONE) {
        /* This is the event we registered for */
    }

    /* Return OK status code to continue with acceptance to underlying handler */
    return MGMT_ERR_EOK;
}

void main()
{
    my_callback.callback = my_function;
    my_callback.event_id = MGMT_EVT_OP_CMD_DONE;
    mgmt_callback_register(&my_callback);
}

This code registers a handler for the MGMT_EVT_OP_CMD_DONE event, which will be called after a MCUmgr command has been processed and output generated, note that this requires that CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS be enabled to receive this callback.

Multiple callbacks can be setup to use a single function as a common callback, and many different functions can be used for each event by registering each group once, or all notifications for a whole group can be enabled by using one of the MGMT_EVT_OP_*_ALL events, alternatively a handler can setup for every notification by using MGMT_EVT_OP_ALL. When setting up handlers, events can be combined that are in the same group only, for example 5 img_mgmt callbacks can be setup with a single registration call, but to also setup a callback for an os_mgmt callback, this must be done as a separate registration. Group IDs are numerical increments, event IDs are bitmask values, hence the restriction.

Events Events can be selected by enabling their corresponding Kconfig option:

- CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS
  MCUmgr command status (MGMT_EVT_OP_CMD_RECV, MGMT_EVT_OP_CMD_STATUS, MGMT_EVT_OP_CMD_DONE)

- CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK
  fs_mgmt file access (MGMT_EVT_OP_FS_MGMT_FILE_ACCESS)

- CONFIG_MCUMGR_GRP_IMG_UPLOAD_CHECK_HOOK
  img_mgmt upload check (MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK)

- CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS
  img_mgmt upload status (MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED, MGMT_EVT_OP_IMG_MGMT_DFU_STARTED, MGMT_EVT_OP_IMG_MGMT_DFU_PENDING, MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED)

- CONFIG_MCUMGR_GRP_OS_OS_RESET_HOOK
  os_mgmt reset check (MGMT_EVT_OP_OS_MGMT_RESET)

Actions Some callbacks expect a return status to either allow or disallow an operation, an example is the fs_mgmt access hook which allows for access to files to be allowed or denied. With these handlers, the first non-OK error code returned by a handler will be returned to the MCUmgr client.

An example of selectively denying file access:

```
#include <zephyr/kernel.h>
#include <mgmt/mgmt.h>
#include <zephyr/mgmt/mcumgr/mgmt/callbacks.h>
```
# include <string.h>

struct mgmt_callback my_callback;

int32_t my_function(uint32_t event, int32_t rc, bool *abort_more, void *data, size_t data_size)
{
    /* Only run this handler if a previous handler has not failed */
    if (event == MGMT_EVT_OP_FS_MGMT_FILE_ACCESS && rc == MGMT_ERR_EOK) {
        struct fs_mgmt_file_access *fs_data = (struct fs_mgmt_file_access *)data;

        /* Check if this is an upload and deny access if it is, otherwise check the path and deny if it matches a name */
        if (fs_data->upload == true) {
            /* Return an access denied error code to the client and abort calling further handlers */
            *abort_more = true;
            return MGMT_ERR_EACCESSDENIED;
        } else if (strcmp(fs_data->filename, "/lfs1/false_deny.txt") == 0) {
            /* Return a no entry error code to the client, call additional handlers (which will have failed set to true) */
            return MGMT_ERR_ENOENT;
        }
    }

    /* Return OK status code to continue with acceptance to underlying handler */
    return MGMT_ERR_EOK;
}

void main()
{
    my_callback.callback = my_function;
    my_callback.event_id = MGMT_EVT_OP_FS_MGMT_FILE_ACCESS;
    mgmt_callback_register(&my_callback);
}

This code registers a handler for the MGMT_EVT_OP_FS_MGMT_FILE_ACCESS event, which will be called after a fs_mgmt file read/write command has been received to check if access to the file should be allowed or not. Note that this requires that CONFIG_MCUMGR_GRP_FS_FILE_ACCESS_HOOK be enabled to receive this callback.

MCUmgr Command Callback Usage/Adding New Event Types To add a callback to a MCUmgr command, mgmt_callback_notify() can be called with the event ID and, optionally, a data struct to pass to the callback (which can be modified by handlers). If no data needs to be passed back, NULL can be used instead, and size of the data set to 0.

An example MCUmgr command handler:
# define MGMT_EVT_GRP_USER_ONE MGMT_EVT_GRP_USER_CUSTOM_START

enum user_one_group_events {
  /** Callback on first post, data is test_struct. */
  MGMT_EVT_OP_USER_ONE_FIRST = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_USER_ONE, 0),

  /** Callback on second post, data is test_struct. */
  MGMT_EVT_OP_USER_ONE_SECOND = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_USER_ONE, 1),

  /** Used to enable all user_one events. */
  MGMT_EVT_OP_USER_ONE_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_USER_ONE),
};

struct test_struct {
  uint8_t some_value;
};

static int test_command(struct mgmt_ctxt *ctxt) {
  int rc;
  zcbor_state_t *zse = ctxt->cnbe->zs;
  bool ok;
  struct test_struct test_data = {
    .some_value = 8,
  };

  rc = mgmt_callback_notify(MGMT_EVT_OP_USER_ONE_FIRST, &test_data, sizeof(test_data));

  if (rc != MGMT_ERR_EOK) {
    /* A handler returned a failure code */
    return rc;
  }

  /* All handlers returned success codes */

  ok = zcbor_tstr_put_lit(zse, "output_value") &
  zcbor_int32_put(zse, 1234);

  if (!ok) {
    return MGMT_ERR_EMSGSIZE;
  }

  return MGMT_ERR_EOK;
}

If no response is required for the callback, the function call be called and casted to void.

Migration

If there is existing code using the previous callback system(s) in Zephyr 3.2 or earlier, then it will need to be migrated to the new system. To migrate code, the following callback registration functions will need to be migrated to register for callbacks using `mgmt_callback_register()` (note that `CONFIG_MCUMGR_MGMT_NOTIFICATION_HOOKS` will need to be set to enable the new notification system in addition to any migrations):

4.3. Device Management
• mgmt_evt
  Using `MGMT_EVT_OP_CMD_RECV` if `MGMT_EVT_OP_CMD_RECV` was used, `MGMT_EVT_OP_CMD_STATUS` if `MGMT_EVT_OP_CMD_STATUS` was used or `MGMT_EVT_OP_CMD_DONE` if `MGMT_EVT_OP_CMD_DONE` was used, where the provided data is `mgmt_evt_op_cmd_arg`. `CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS` needs to be set.

• fs_mgmt_register_evt_cb
  Using `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` where the provided data is `fs_mgmt_file_access`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS` needs to be set.

• img_mgmt_register_callbacks
  Using `MGMT_EVT_OP_IMG_MGMT_DFU_STARTED` if `dfu_started_cb` was used, `MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED` if `dfu_stopped_cb` was used, `MGMT_EVT_OP_IMG_MGMT_DFU_PENDING` if `dfu_pending_cb` was used or `MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED` if `dfu_confirmed_cb` was used. These callbacks do not have any return status. `CONFIG_MCUMGR_GRP_IMG_STATUS_HOOKS` needs to be set.

• img_mgmt_set_upload_cb
  Using `MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK` where the provided data is `img_mgmt_upload_check`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_GRP_IMG_UPLOAD_CHECK_HOOK` needs to be set.

• os_mgmt_register_reset_evt_cb
  Using `MGMT_EVT_OP_OS_MGMT_RESET`. Instead of returning true to allow the action or false to deny, a MCUmgr result code needs to be returned, `MGMT_ERR_EOK` will allow the action, any other return code will disallow it and return that code to the client (`MGMT_ERR_EACCESSDENIED` can be used for an access denied error). `CONFIG_MCUMGR_SMP_COMMAND_STATUS_HOOKS` needs to be set

API Reference

`group mcumgr_callback_api`
MCUmgr callback API.

`Defines`

`MGMT_EVT_GET_GROUP(event)`
Get group from event.

`MGMT_EVT_GET_ID(event)`
Get event ID from event.

`Typedefs`

typedef int32_t (*mgmt_cb)(uint32_t event, int32_t rc, bool *abort_more, void *data, size_t data_size)
Function to be called on MGMT notification/event.
This callback function is used to notify an application or system about a mcumgr mgmt event.
**Param event**
mcumgr_op_t.

**Param rc**
mcumgr_err_t of the previous handler calls, if it is an error then it will be the first error that was returned by a handler (i.e. this handler is being called for a notification only, the return code will be ignored).

**Param abort_more**
Set to true to abort further processing by additional handlers.

**Param data**
Optional event argument.

**Param data_size**
Size of optional event argument (0 if no data is provided).

**Return**
mcumgr_err_t of the status to return to the calling code (only checked when failed is false).

**Enums**

**enum mgmt_cb_groups**
MGMT event callback group IDs. Note that this is not a 1:1 mapping with mcumgr_group_t values.

*Values:*

- enumerator MGMT_EVT_GRP_ALL = 0
- enumerator MGMT_EVT_GRP_SMP
- enumerator MGMT_EVT_GRP_OS
- enumerator MGMT_EVT_GRP_IMG
- enumerator MGMT_EVT_GRP_FS
- enumerator MGMT_EVT_GRP_USER_CUSTOM_START = MGMT_GROUP_ID_PERUSER

**enum smp_all_events**
MGMT event opcodes for all command processing.

*Values:*

- enumerator MGMT_EVT_OP_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_ALL)
  Used to enable all events.

**enum smp_group_events**
MGMT event opcodes for base SMP command processing.

*Values:*

4.3. Device Management
enumerator MGMT_EVT_OP_CMD_RECV = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_SMP, 0)
    Callback when a command is received, data is mgmt_evt_op_cmd_arg().

enumerator MGMT_EVT_OP_CMD_STATUS = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_SMP, 1)
    Callback when a status is updated, data is mgmt_evt_op_cmd_arg().

enumerator MGMT_EVT_OP_CMD_DONE = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_SMP, 2)
    Callback when a command has been processed, data is mgmt_evt_op_cmd_arg().

enumerator MGMT_EVT_OP_CMD_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_SMP)
    Used to enable all smp_group events.

enum fs_mgmt_group_events
    MGMT event opcodes for filesystem management group.
    Values:

enumerator MGMT_EVT_OP_FS_MGMT_FILE_ACCESS =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_FS, 0)
    Callback when a file has been accessed, data is fs_mgmt_file_access().

enumerator MGMT_EVT_OP_FS_MGMT_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_FS)
    Used to enable all fs_mgmt_group events.

enum img_mgmt_group_events
    MGMT event opcodes for image management group.
    Values:

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 0)
    Callback when a client sends a file upload chunk, data is img_mgmt_upload_check().

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_STOPPED =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 1)
    Callback when a DFU operation is stopped.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_STARTED =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 2)
    Callback when a DFU operation is started.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_PENDING =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 3)
    Callback when a DFU operation has finished being transferred.

enumerator MGMT_EVT_OP_IMG_MGMT_DFU_CONFIRMED =
    MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_IMG, 4)
    Callback when an image has been confirmed.

enumerator MGMT_EVT_OP_IMG_MGMT_ALL =
    MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_IMG)
    Used to enable all img_mgmt_group events.
enum os_mgmt_group_events
    MGMT event opcodes for operating system management group.

Values:

enumerator MGMT_EVT_OP_OS_MGMT_RESET = MGMT_DEF_EVT_OP_ID(MGMT_EVT_GRP_OS, 0)
    Callback when a reset command has been received.

enumerator MGMT_EVT_OP_OS_MGMT_ALL = MGMT_DEF_EVT_OP_ALL(MGMT_EVT_GRP_OS)
    Used to enable all os_mgmt_group events.

Functions

int32_t mgmt_callback_notify(uint32_t event, void *data, size_t data_size)
    This function is called to notify registered callbacks about mcumgr notifications/events.

Parameters

• event – mcumgr_op_t.
• data – Optional event argument.
• data_size – Size of optional event argument (0 if none).

Returns

mcumgr_err_t either MGMT_ERR_EOK if all handlers returned it, or the error code of the first handler that returned an error.

void mgmt_callback_register(struct mgmt_callback *callback)
    Register event callback function.

Parameters

• callback – Callback struct.

void mgmt_callback_unregister(struct mgmt_callback *callback)
    Unregister event callback function.

Parameters

• callback – Callback struct.

struct mgmt_callback
    #include <callbacks.h> MGMT callback struct

Public Members

sys_snode_t node
    Entry list node.

mgmt_cb callback
    Callback that will be called.

uint32_t event_id
    MGMT_EVT_[…] Event ID for handler to be called on.
struct mgmt_evt_op_cmd_arg

Arguments for `MGMT_EVT_OP_CMD_RECV`, `MGMT_EVT_OP_CMD_STATUS` and `MGMT_EVT_OP_CMD_DONE`

Public Members

- `uint16_t group`
  - `mcumgr_group_t`

- `uint8_t id`
  - Message ID within group

- `int err`
  - `mcumgr_err_t`, used in `MGMT_EVT_OP_CMD_DONE`

- `int status`
  - `img_mgmt_id_upload_t`, used in `MGMT_EVT_OP_CMD_STATUS`

MCUmgr fs_mgmt callback API.

struct fs_mgmt_file_access

Structure provided in the `MGMT_EVT_OP_FS_MGMT_FILE_ACCESS` notification callback: This callback function is used to notify the application about a pending file read/write request and to authorise or deny it. Access will be allowed so long as all notification handlers return `MGMT_ERR_EOK`, if one returns an error then access will be denied.

Public Members

- `bool upload`
  - True if the request is for uploading data to the file, otherwise false

- `char *filename`
  - Path and filename of file be accesses, note that this can be changed by handlers to redirect file access if needed (as long as it does not exceed the maximum path string size).

MCUmgr img_mgmt callback API.

struct img_mgmt_upload_check

Structure provided in the `MGMT_EVT_OP_IMG_MGMT_DFU_CHUNK` notification callback: This callback function is used to notify the application about a pending firmware upload packet from a client and authorise or deny it. Upload will be allowed so long as all notification handlers return `MGMT_ERR_EOK`, if one returns an error then the upload will be denied.

Public Members

- `struct img_mgmt_upload_action *action`
  - Action to take
4.3.3 Fixing and backporting fixes to Zephyr v2.7 MCUmgr

The processes described in this document apply to both the zephyr repository itself and the MCUmgr module defined in west.yml.

Note: Currently, the backporting process, described in this document, is required only when providing changes to Zephyr version 2.7 LTS.

There are two different processes: one for issues that have also been fixed in the current version of Zephyr (backports), and one for issues that are being fixed only in a previous version.

The upstream MCUmgr repository is located in this page. The Zephyr fork used in version 2.7 and earlier is located here. Versions of Zephyr past 2.7 use the MCUmgr library that is part of the Zephyr code base.

Possible origins of a code change

In Zephyr version 2.7 and earlier, you must first apply the fix to the upstream repository of MCUmgr and then bring it to Zephyr with snapshot updates.

As such, there are four possible ways to apply a change to the 2.7 branch:

• The fix, done directly to the Zephyr held code of the MCUmgr library, is backported to the v2.7-branch.

• The fix, ported to the Zephyr held code from the upstream repository, is backported to the v2.7-branch.

• The fix, done upstream and no longer relevant to the current version, is directly backported to the v2.7-branch.

• The fix, not present upstream and not relevant for the current version of Zephyr, is directly applied to the v2.7-branch.

The first three cases are cases of backports, the last one is a case of a new fix and has no corresponding fix in the current version.

Applying fixes to previous versions of MCUmgr

This section indicates how to apply fixes to previous versions of MCUmgr.

Creating a bug report Every proposed fix requires a bug report submitted for the specified version of Zephyr affected by the bug.

In case the reported bug in a previous version has already been fixed in the current version, the description of the bug must be copied with the following:

• Additional references to the bug in the current version

• The PR for the current version

• The SHAs of the commits, if the PR has already been merged

You must also apply the backport v2.7-branch label to the bug report.
Creating the pull request for the fix  You can either create a backport pull request or a new-fix pull request.

Creating backport pull requests  Backporting a fix means that some or all of the fix commits, as they exist in the current version, are ported to a previous version.

**Note:** Backporting requires the fix for the current version to be already merged.

To create a backport pull request, do the following:

1. Port the fix commits from the current version to the previous version. Even if some of the commits require changes, keep the commit messages of all the ported commits as close to the ones in the original commits as possible, adding the following line:

   "Backporting commit `<sha>`"

   ``<sha>`` indicates the SHA of the commit after it has been already merged in the current version.

1. Create the pull request selecting `v2.7-branch` as the merge target.

1. Update `west.yml` within Zephyr, creating a pull-request to update the MCUmgr library referenced in Zephyr 2.7.

Creating new-fix pull requests  When the fix needed does not have a corresponding fix in the current version, the bug report must follow the ordinary process.

1. Create the pull request selecting `v2.7-branch` as the merge target.

1. Update `west.yml` within Zephyr, creating a pull-request to update the MCUmgr library referenced in Zephyr 2.7.

Configuration management

This chapter describes the maintainers’ side of accepting and merging fixes and backports.

**Prerequisites**  As a maintainer, these are the steps required before proceeding with the merge process:

1. Check if the author has followed the correct steps that are required to apply the fix, as described in *Applying fixes to previous versions of MCUmgr*.

   1. Ensure that the author of the fix has also provided the `west.yml` update for Zephyr 2.7.

The specific merging process depends on where the fix comes from and whether it is a backport or a new fix.

Merging a backported fix  There are two possible sources of backports:

- The Zephyr code base
- A direct fix from upstream

Both cases are similar and differ only in the branch name.

To merge a backported fix after the pull request for the fix has gone through the review process, as a maintainer, do the following:

1. Create a branch named as follow:
Merging a new fix  Merging a new fix, that is not a backport of either any upstream or Zephyr fix, does not require any special treatment. Apply the fix directly at the top of v2.7-branch.

Merge west.yml  As an MCUmgr maintainer, you may not be able to merge the west.yml update, to introduce the fix to Zephyr. However, you are responsible for such a merge to happen as soon as possible after the MCUmgr fixes have been applied to the v2.7-branch of the MCUmgr.

4.3.4 SMP Protocol Specification

This is description of Simple Management Protocol, SMP, that is used by mcumgr to pass requests to devices and receive responses from them.

SMP is an application layer protocol. The underlying transport layer is not in scope of this documentation.

Frame: The envelope

Each frame consists of header and following it data. The Data Length field in the header may be used for reassembly purposes if underlying transport layer supports fragmentation. Frame is encoded in “Big Endian” (Network endianness), where field is more than one byte lone, and takes the following form:

```
| 3    2    1    0 | 7    6    5    4    3    2    1    0 |
| Res       OP   Flags   Data Length |
| Group ID   | Sequence Num | Command ID |
| Data . . . |
```

The original specification states that SMP should support receiving both the “Little-endian” and “Big-endian” frames but in reality the mcumgr library is hardcoded to always treat “Network” side as “Big-endian”.

The Data is optional and is not present when Data Length is zero. The encoding of data depends on the target of group/ID.

Where meaning of fields is:
Field | Description
--- | ---
Res | This is reserved, not-used field and should be always set to 0.
Op | Operation code
Flags | Reserved for flags; there are no flags defined yet, the field should be set to 0
Data Length | Length of the Data field
Group ID | Management Group ID’s
Sequence Num | This is a frame sequence number. The number is increased by one with each request frame. The Sequence Num of a response should match the one in the request.
Command ID | This is a command, within Group.
Data | This is data payload of the Data Length size. It is optional as Data Length may be set to zero, which means that no data follows the header.

**Note:** Contents of a Data depends on a value of an Op, a Group ID, and a Command ID.

**Note:** The Res field may be repurposed by Zephyr for protocol version in the future.

**Operation code** The operation code determines whether an information is written to a device or requested from it and whether a packet contains request to a SMP server or response from it.

Following operation codes are defined.

<table>
<thead>
<tr>
<th>Decimal ID</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>read request</td>
</tr>
<tr>
<td>1</td>
<td>read response</td>
</tr>
<tr>
<td>2</td>
<td>write request</td>
</tr>
<tr>
<td>3</td>
<td>write response</td>
</tr>
</tbody>
</table>

**Management Group ID’s** The SMP protocol supports predefined common groups and allows user defined groups. Below table presents list of common groups:

<table>
<thead>
<tr>
<th>Decimal ID</th>
<th>Group description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Default/OS Management Group</td>
</tr>
<tr>
<td>1</td>
<td>Application/software image management group</td>
</tr>
<tr>
<td>2</td>
<td>Statistics management</td>
</tr>
<tr>
<td>3</td>
<td>Application/system configuration (currently not used by Zephyr)</td>
</tr>
<tr>
<td>4</td>
<td>Application/system log management (currently not used by Zephyr)</td>
</tr>
<tr>
<td>5</td>
<td>Run-time tests (unused by Zephyr)</td>
</tr>
<tr>
<td>6</td>
<td>Split image management (unused by Zephyr)</td>
</tr>
<tr>
<td>7</td>
<td>Test crashing application (unused by Zephyr)</td>
</tr>
<tr>
<td>8</td>
<td>File management</td>
</tr>
<tr>
<td>9</td>
<td>Shell management</td>
</tr>
<tr>
<td>63</td>
<td>Zephyr specific basic commands group</td>
</tr>
<tr>
<td>64</td>
<td>This is the base group for defining an application specific management groups.</td>
</tr>
</tbody>
</table>

The payload for above groups, except for 64 which is not defined, is always CBOR encoded. The group 64, and above, are free to be defined by application developers and are not defined within this documentation.
Minimal response

Regardless of a command issued, as long as there is SMP client on the other side of a request, a response should be issued containing header followed by CBOR map container. Lack of response is only allowed when there is no SMP service or device is non-responsive.

Minimal response SMP data

Minimal response is CBOR directory:

```
{
    (str)"rc" : (int)
}
```

where:

"rc"  | Status/error codes in responses
--- | ---
0 | No error, OK.
1 | Unknown error.
2 | Not enough memory; this error is reported when there is not enough memory to complete response.
3 | Invalid value; a request contains an invalid value.
4 | Timeout; the operation for some reason could not be completed in assumed time.
5 | No entry; the error means that request frame has been missing some information that is required to perform action. It may also mean that requested information is not available.
6 | Bad state; the error means that application or device is in a state that would not allow it to perform or complete a requested action.
7 | Response too long; this error is issued when buffer assigned for gathering response is not big enough.
8 | Not supported; usually issued when requested Group ID or Command ID is not supported by application.
9 | Corrupted payload received.
10 | Device is busy with processing previous SMP request and may not process incoming one. Client should re-try later.
256 | This is base error number of user defined error codes.

Zephyr uses MGMT_ERR_ prefixed definitions gathered in this header file `sys/mgmt/mcumgr/lib/mgmt/include/mgmt/mgmt.h`

Specifications of management groups supported by Zephyr

Default/OS Management Group

OS management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Echo</td>
</tr>
<tr>
<td>1</td>
<td>Console/Terminal echo control; unimplemented by Zephyr</td>
</tr>
<tr>
<td>2</td>
<td>Statistics</td>
</tr>
<tr>
<td>3</td>
<td>Memory pool statistics</td>
</tr>
<tr>
<td>4</td>
<td>Date-time string; unimplemented by Zephyr</td>
</tr>
<tr>
<td>5</td>
<td>System reset</td>
</tr>
<tr>
<td>6</td>
<td>MCUMGR parameters</td>
</tr>
</tbody>
</table>

4.3. Device Management
**Echo command**  
Echo command responses by sending back string that it has received.

**Echo request**  
Echo request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0 or 2</td>
<td>0</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```plaintext
{
  (str)"d" : (str)
}
```

where:

- "d" string to be replied by echo service

**Echo response**  
Echo response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
<th>Note</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>0</td>
<td>When request OP was 0</td>
</tr>
<tr>
<td>3</td>
<td>0</td>
<td>0</td>
<td>When request OP was 2</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```plaintext
{
  (str)"r" : (str)
}
```

In case of error the CBOR data takes form:

```plaintext
{
  (str)"rc" : (int)
}
```

where:

- "r" Replying echo string
- "rc" Status/error codes in responses

**Task statistics command**  
The command responds with some system statistics.

**Task statistics request**  
Task statistics request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>2</td>
</tr>
</tbody>
</table>

The command sends empty CBOR map as data.
Task statistics response  Task statistics response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
    (str)"tasks" : {
        (str)<task_name> : {
            (str)"prio" : (uint)
            (str)"tid" : (uint)
            (str)"state" : (uint)
            (str)"stkuse" : (uint)
            (str)"stksiz" : (uint)
            (str)"cswcnt" : (uint)
            (str)"runtime" : (uint)
            (str)"last_checkin" : (uint)
            (str)"next_checkin" : (uint)
        }
    ...
    (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&lt;task_name&gt;</td>
<td>string identifying task</td>
</tr>
<tr>
<td>&quot;prio&quot;</td>
<td>task priority</td>
</tr>
<tr>
<td>&quot;tid&quot;</td>
<td>numeric task ID</td>
</tr>
<tr>
<td>&quot;state&quot;</td>
<td>numeric task state</td>
</tr>
<tr>
<td>&quot;stkuse&quot;</td>
<td>task's/thread's stack usage</td>
</tr>
<tr>
<td>&quot;stksiz&quot;</td>
<td>task's/thread's stack size</td>
</tr>
<tr>
<td>&quot;cswcnt&quot;</td>
<td>task's/thread's context switches</td>
</tr>
<tr>
<td>&quot;runtime&quot;</td>
<td>task's/thread's runtime in &quot;ticks&quot;</td>
</tr>
<tr>
<td>&quot;last_checkin&quot;</td>
<td>set to 0 by Zephyr</td>
</tr>
<tr>
<td>&quot;next_checkin&quot;</td>
<td>set to 0 by Zephyr</td>
</tr>
<tr>
<td>&quot;rc&quot;</td>
<td>Status/error codes in responses</td>
</tr>
</tbody>
</table>

**Note:** The unit for “stkuse” and “stksiz” is system dependent and in case of Zephyr this is number of 4 byte word.

Memory pool statistics  The command is used to obtain information on memory pools active in running system.

Memory pool statistic request  Memory pool statistics request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>3</td>
</tr>
</tbody>
</table>

The command sends empty CBOR map as data.
Memory pool statistics response

Memory pool statistics response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>3</td>
</tr>
</tbody>
</table>

CBOR data of response:

```
{
  (str)<pool_name> {
    (str)"blksiz" : (int)
    (str)"nblks" : (int)
    (str)"nfree" : (int)
    (str)"min' : (int)
  }
  ...
  (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>pool_name</th>
<th>string representing the pool name, used as a key for dictionary with pool statistics data</th>
</tr>
</thead>
<tbody>
<tr>
<td>blksiz</td>
<td>size of the memory block in the pool</td>
</tr>
<tr>
<td>nblks</td>
<td>number of blocks in the pool</td>
</tr>
<tr>
<td>nfree</td>
<td>number of free blocks</td>
</tr>
<tr>
<td>min</td>
<td>lowest number of free blocks the pool reached during run-time</td>
</tr>
<tr>
<td>rc</td>
<td>Status/error codes in responses</td>
</tr>
</tbody>
</table>

Date-time command

The command allows to obtain string representing current time-date on a device or set a new time to a device. The time format used, by both set and get operations, is:

```
“yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZZ”
```

Date-time get

The command allows to obtain date-time from a device.

Date-time get request

Date-time request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

The command sends empty CBOR map as data.

Data-time get response

Date-time get response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

CBOR data of response:

```
{
  (str)"datetime" : (str)
  (opt,str)"rc" : (int)
}
```
where:

| “datetime” | String in format yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZZ |
| "rc"       | Status/error codes in responses; may not appear if 0 |

**Date-time set**  The command allows to set date-time to a device.

**Date-time set request**  Date-time set request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
  "datetime" : (str)
}
```

where:

| “datetime” | String in format yyyy-MM-dd'T'HH:mm:ss.SSSSSSZZZZ |

**Data-time set response**  Date-time set response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>4</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
  "rc" : (int)
}
```

where:

| “rc” | Status/error codes in responses |

**System reset**  Performs reset of system. The device should issue response before resetting so that the SMP client could receive information that the command has been accepted. By default, this command is accepted in all conditions, however if the CONFIG_MCMGR_GRP_OS_OS_RESET_HOOK is enabled and an application registers a callback, the callback will be called when this command is issued and can be used to perform any necessary tidy operations prior to the module rebooting, or to reject the reset request outright altogether with an error response. For details on this functionality, see ref: `mcumgr_callbacks`.

**System reset request**  System reset request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>0</td>
<td>5</td>
</tr>
</tbody>
</table>

Normally the command sends empty CBOR map as data, but if previous reset attempt has been responded with “rc” code equal 10 (busy), then following map may be send to force the reset:
System reset response  System reset response header fields

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>0</td>
<td>5</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
    (opt,str)"rc" : (int)
}
```

where:

```
"rc"  Status/error codes in responses; may not appear if 0
```

MCUMGR Parameters  Used to obtain parameters of mcumgr library.

MCUMGR Parameters Request  MCUMGR parameters request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>6</td>
</tr>
</tbody>
</table>

The command sends empty CBOR map as data.

MCUMGR Parameters Response  MCUMGR parameters response header fields

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>0</td>
<td>6</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
    (str)"buf_size" : (uint)
    (str)"buf_count" : (uint)
    (opt,str)"rc" : (int)
}
```

where:

```
"buf_size"  Single SMP buffer size, this includes SMP header and CBOR payload
"buf_count"  Number of SMP buffers supported
"rc"  Status/error codes in responses; may not appear if 0
```
Application/software image management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>State of images</td>
</tr>
<tr>
<td>1</td>
<td>Image upload</td>
</tr>
<tr>
<td>2</td>
<td>File (reserved but not supported by Zephyr)</td>
</tr>
<tr>
<td>3</td>
<td>Corelist (reserved but not supported by Zephyr)</td>
</tr>
<tr>
<td>4</td>
<td>Coreload (reserved but not supported by Zephyr)</td>
</tr>
<tr>
<td>5</td>
<td>Image erase</td>
</tr>
</tbody>
</table>

Notion of “slots” and “images” in Zephyr The “slot” and “image” definition comes from mcuboot where “image” would consist of two “slots”, further named “primary” and “secondary”; the application is supposed to run from the “primary slot” and update is supposed to be uploaded to the “secondary slot”; the mcuboot is responsible in swapping slots on boot. This means that pair of slots is dedicated to single upgradable application. In case of Zephyr this gets a little bit confusing because DTS will use “slot0_partition” and “slot1_partition”, as label of fixed-partition dedicated to single application, but will name them as “image-0” and “image-1” respectively.

Currently Zephyr supports at most two images, in which case mapping is as follows:

<table>
<thead>
<tr>
<th>Image</th>
<th>Slot labels</th>
<th>Slot Names</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>“slot0_partition”</td>
<td>“image-0” “image-1”</td>
</tr>
<tr>
<td>2</td>
<td>“slot2_partition”</td>
<td>“image-2” “image-3”</td>
</tr>
</tbody>
</table>

State of images The command is used to set state of images and obtain list of images with their current state.

Get state of images request Get state of images request header fields:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>
```

The command sends sends empty CBOR map as data.

Get state of images response Get state of images response header fields:

```
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>
```

Note: Below definition of the response contains “image” field that has been marked as optional(opt): the field may not appear in response when target application does not support more than one image. The field is mandatory when application supports more than one application image to allow identifying which image information is listed.

A response will only contain information for valid images, if an image can not be identified as valid it is simply skipped.

CBOR data of successful response:
In case of error the CBOR data takes form:

```
{
  (str,"rc" : (int)
  (str,opt)"rsn" : (str)
}
```

where:

- **"image"** - semi-optional image number; the field is not required when only one image is supported by running application
- **"slot"** - slot number within "image"; each image has two slots: primary (running one) = 0 and secondary (for DFU dual-bank purposes) = 1
- **"version"** - string representing image version, as set with imgtool
- **"hash"** - hash of an upload; this is used to identify an upload session, for example to allow mcumgr library to continue broken session

**Note:** By default mcumgr-cli uses here a few characters of sha256 of the first uploaded chunk.

- **"bootable"** - true if image has bootable flag set; this field does not have to be present if false
- **"pending"** - true if image is set for next swap this field does not have to be present if false
- **"confirmed"** - true if image has been confirmed this field does not have to be present if false
- **"active"** - true if image is currently active application this field does not have to be present if false
- **"permanent"** - true if image is to stay in primary slot after next boot this field does not have to be present if false
- **"splitStatus"** - states whether loader of split image is compatible with application part; this is unused by Zephyr
- **"rc"** - Status/error codes in responses
- **"rsn"** - optional string that clarifies reason for an error; specifically useful for error code 1, unknown error
Note: For more information on how does image/slots function, please refer to the MCUBoot documentation https://www.mcuboot.com/documentation/design/#image-slots

Set state of image request  Set state of image request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
  {
    (str,opt)"hash" : (str)
    (str)"confirm" : (bool)
  }
}
```

If “confirm” is false an image with the “hash” will be set for test, which means that it will not be marked as permanent and upon hard reset the previous application will be restored to the primary slot. In case when “confirm” is true, the “hash” is optional as the currently running application will be assumed as target for confirmation.

Set state of image response  The response takes the same format as Get state of images response

Image upload  The image upload command allows to update application image.

Image upload request  The image upload request is sent for each chunk of image that is uploaded, until complete image gets uploaded to a device.

Set state of image request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of request:

```
{
  {
    (str,opt)"image" : (uint)
    (str,opt)"len" : (uint)
    (str)"off" : (uint)
    (str,opt)"sha" : (str)
    (str,opt)"data" : (byte str)
    (str,opt)"upgrade" : (bool)
  }
}
```

where:
**Image** optional image number; it does not have to appear in request at all, in which case it is assumed to be 0; only request with "off" 0 can contain image number

**"len"** optional length of an image, it only appears in the first packet of request, where “off” is 0

**"off"** offset of image chunk the request carries

**"sha"** string identifying update session; it should only be present if “off” is zero; although name suggests it might be SHA, it can actually be any string

**"data"** optional image data

**"upgrade"** optional flag that states that only upgrade should be allowed, so if version of uploaded software is lower than already on device, the image update should be rejected (unused by Zephyr at this time)

---

**Note:** There is no field representing size of chunk that is carried as “data” because that information is embedded within “data” field itself.

The mcumgr library uses “sha” field to tag ongoing update session, to be able to continue it in case when it gets broken. If library gets request with “off” equal zero it checks stored “sha” within its state and if it matches it will respond to update client application with offset that it should continue with.

---

### Image upload response

Set state of image request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of response:

```
{  
   (str,opt)"off" : (uint)
   (str)"rc" : (int)
   (str,opt)"rsn" : (str)
}
```

where:

<table>
<thead>
<tr>
<th>Field</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>“off”</td>
<td>offset of last successfully written byte of update</td>
</tr>
<tr>
<td>“rc”</td>
<td>Status/error codes in responses</td>
</tr>
<tr>
<td>“rsn”</td>
<td>Optional string that clarifies reason for an error; specifically useful for error code 1, unknown error</td>
</tr>
</tbody>
</table>

The “off” field is only included in responses to successfully processed requests; if “rc” is negative the “off” may not appear.

---

### Image erase

The command is used for erasing image slot on a target device.

**Note:** This is synchronous command which means that a sender of request will not receive response until the command completes.

---

### Image erase request

Image erase request header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>1</td>
<td>5</td>
</tr>
</tbody>
</table>
CBOR data of request:

```json
{
  (str,opt)"slot" : (uint)
}
```

where:

| “slot” | optional slot number, it does not have to appear in the request at all, in which case it is assumed to be 1. |

**Image erase response**  Image erase response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>1</td>
<td>5</td>
</tr>
</tbody>
</table>

CBOR data of response:

```json
{
  (str)"rc" : (int)
  (str,opt)"rsn" : (str)
}
```

where:

<table>
<thead>
<tr>
<th>“rc”</th>
<th>Status/error codes in responses</th>
</tr>
</thead>
<tbody>
<tr>
<td>“rsn”</td>
<td>Optional string that clarifies reason for an error; specifically useful for error code 1, unknown error</td>
</tr>
</tbody>
</table>

**Note:** Response from Zephyr running device may have “rc” value of 6, bad state (*Status/error codes in responses*), which means that the secondary image has been marked for next boot already and may not be erased.

**Statistics management**  Statistics management allows to obtain data gathered by Statistics subsystem of Zephyr, enabled by `CONFIG_STATS`.

Statistics management group defines commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Group data</td>
</tr>
<tr>
<td>1</td>
<td>List groups</td>
</tr>
</tbody>
</table>

**Statistics: group data**  The command is used to obtain data for group specified by a name. The name is one of group names as registered, with `STATS_INIT_AND_REG` macro or `stats_init_and_reg(...)` function call, within module that gathers the statistics.

**Statistics: group data request**  Statistics group data request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>0</td>
</tr>
</tbody>
</table>
CBOR Payload of request:

```json
{
    (str)"name" : (str)
}
```

where:

| "name" | is group name |

Statistics: group data response

Statistics group data response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR Payload of response:

```json
{
    (str)"name" : (str)
    (str)"fields" : {
        (str)<entry_name> : (uint)
        ...
    }
    (str)"rc" : (int)
}
```

where:

| "name" | this is name of group the response contains data for |
| "fields" | this is map of entries within groups that consists of pairs where entry name is mapped to value it represents in statistics |
| <entry_name> | single entry to value mapping; value is hardcoded to unsigned integer type, in a CBOR meaning |
| "rc" | Status/error codes in responses |

Statistics: list of groups

The command is used to obtain list of groups of statistics that are gathered on a device. This is a list of names as given to groups with STATS_INIT_AND_REG macro or stats_init_and_reg(...) function calls, within module that gathers the statistics; this means that this command may be considered optional as it is known during compilation what groups will be included into build and listing them is not needed prior to issuing a query.

Statistics: list of groups request

Statistics group list request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>2</td>
<td>1</td>
</tr>
</tbody>
</table>

The command sends empty CBOR map as data.

Statistics: list of groups response

Statistics group list request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>1</td>
</tr>
</tbody>
</table>
CBOR Payload of response:

```json
{
  (str)"stat_list" : [ 
    (str)<stat_group_name>, ...
  ]
  (str)"rc" : (int)
}
```

where:

- **“stat_list”** array of strings representing group names; this array may be empty if there are no groups
- **“rc”** Status/error codes in responses

### File management

The file management group provides commands that allow to upload and download files to/from a device.

File management group defines following commands:

<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>File download/upload</td>
</tr>
<tr>
<td>1</td>
<td>File status</td>
</tr>
<tr>
<td>2</td>
<td>File hash/checksum</td>
</tr>
<tr>
<td>3</td>
<td>Supported file hash/checksum types</td>
</tr>
</tbody>
</table>

**File download** Command allows to download contents of an existing file from specified path of a target device. The command is stateless and mcumgr does not hold file in open state after response to the command is issued, instead a client application is supposed to keep track of data it has already downloaded, and issue subsequent requests, with modified offset, to gather entire file. Request does not carry size of requested chunk, the size is specified by application itself. Mcumgr server side re-opens a file for each subsequent request, and current specification does not provide means to identify subsequent requests as belonging to specified download session. This means that the file is not locked in any way or exclusively owned by mcumgr, for the time of download session, and may change between requests or even be removed.

**Note:** By default, all file upload requests are unconditionally allowed. However, if the Kconfig option `FS_MGMT_FILE_ACCESS_HOOK` is enabled, then an application can register a callback handler for `fs_mgmt_on_evt_cb` by calling `fs_mgmt_register_evt_cb()` with the handler supplied. This can be used to allow or decline access to reading from or writing to a particular file, or for rewriting the path supplied by the client.

**File download request** File download request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
  (str)"off" : (uint)
  (str)"name" : (str)
}
```
where:

<table>
<thead>
<tr>
<th>“off”</th>
<th>offset to start download at</th>
</tr>
</thead>
<tbody>
<tr>
<td>“name”</td>
<td>absolute path to a file</td>
</tr>
</tbody>
</table>

**File download response**  
File download response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```
{
  (str)"off" : (uint)
  (str)"data" : (byte str)
  (str)"rc" : (int)
  (str,opt)"len" : (uint)
}
```

In case of error the CBOR data takes form:

```
{
  (str)"rc" : (int)
}
```

where:

| “off” | offset the response is for |
| “data” | chunk of data read from file; it is CBOR encoded stream of bytes with embedded size; “data” appears only in responses where “rc” is 0 |
| “len” | length of file, this field is only mandatory when “off” is 0 |
| “rc” | Status/error codes in responses |

In case when “rc” is not 0, success, the other fields will not appear.

**File upload**  
Allows to upload a file to a specified location. Command will automatically overwrite existing file or create a new one if it does not exist at specified path. The protocol supports stateless upload where each requests carries different chunk of a file and it is client side responsibility to track progress of upload.

Mcumgr server side re-opens a file for each subsequent request, and current specification does not provide means to identify subsequent requests as belonging to specified upload session. This means that the file is not locked in any way or exclusively owned by mcumgr, for the time of upload session, and may change between requests or even be removed.

**Note:**  
Weirdly, the current Zephyr implementation is half-stateless as is able to hold single upload context, holding information on ongoing upload, that consists of bool flag indicating in-progress upload, last successfully uploaded offset and total length only.

**Note:**  
By default, all file upload requests are unconditionally allowed. However, if the Kconfig option `FS_MGMT_FILE_ACCESS_HOOK` is enabled, then an application can register a callback handler for `fs_mgmt_on_evt_cb` by calling `fs_mgmt_register_evt_cb()` with the handler supplied. This can be
used to allow or decline access to reading from or writing to a particular file, or for rewriting the path supplied by the client.

**File upload request**  
File upload request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
    (str,"off") : (uint),
    (str,"data") : (str),
    (str,"name") : (str),
    (str,opt)"len" : (uint)
}
```

where:

- "off"  offset to start/continue upload at
- "data"  chunk of data to write to the file; it is CBOR encoded with length embedded
- "name"  absolute path to a file
- "len"  length of file, this field is only mandatory when "off" is 0

**File upload response**  
File upload response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>8</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
    (str,opt)"off" : (uint),
    (str)"rc" : (int)
}
```

where:

- "off"  offset of last successfully written data; appears only when "rc" is 0
- "rc"  Status/error codes in responses

**File status**  
Command allows to retrieve status of an existing file from specified path of a target device.

**File status request**  
File status request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of request:
where:

- **"name"**: absolute path to a file

### File status response

#### File status response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>1</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
    (str)"len" : (uint)
}
```

In case of error the CBOR data takes form:

```json
{
    (str)"rc" : (int)
}
```

where:

- **"len"**: length of file (in bytes)
- **"rc"**: Status/error codes in responses (only present if an error occurred)

In case when “rc” is not 0, success, the other fields will not appear.

### File hash/checksum

Command allows to generate a hash/checksum of an existing file at a specified path on a target device. Note that kernel heap memory is required for buffers to be allocated for this to function, and large stack memory buffers are required for generation of the output hash/checksum.

#### File hash/checksum request

#### File hash/checksum request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of request:

```json
{
    (str)"name" : (str)
    (str,opt)"type" : (str)
    (str,opt)"off" : (uint)
    (str,opt)"len" : (uint)
}
```

where:
### Hash/checksum types

<table>
<thead>
<tr>
<th>String name</th>
<th>Hash/checksum</th>
<th>Byte string</th>
<th>Size (bytes)</th>
</tr>
</thead>
<tbody>
<tr>
<td>crc32</td>
<td>IEEE CRC32 checksum</td>
<td>No</td>
<td>4</td>
</tr>
<tr>
<td>sha256</td>
<td>SHA256 (Secure Hash Algorithm)</td>
<td>Yes</td>
<td>32</td>
</tr>
</tbody>
</table>

Note that the default type will be crc32 if it is enabled, or sha256 if crc32 is not enabled.

### File hash/checksum response

File hash/checksum response header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>2</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
    (str)"type" : (str),
    (str,opt)"off" : (uint),
    (str)"len" : (uint),
    (str)"output" : (uint or bstr)
}
```

In case of error the CBOR data takes form:

```json
{
    (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>“rc”</th>
<th>Status/error codes in responses (only present if an error occurred)</th>
</tr>
</thead>
<tbody>
<tr>
<td>“type”</td>
<td>type of hash/checksum that was performed Hash/checksum types</td>
</tr>
<tr>
<td>“off”</td>
<td>offset that hash/checksum calculation started at (only present if off is not 0)</td>
</tr>
<tr>
<td>“len”</td>
<td>length of input data used for hash/checksum generation (in bytes)</td>
</tr>
<tr>
<td>“output”</td>
<td>output hash/checksum</td>
</tr>
</tbody>
</table>

In case when “rc” is not 0, success, the other fields will not appear.

### Supported file hash/checksum types

Command allows listing which hash and checksum types are available on a device. Requires Kconfig CONFIG_MCUMGR_GRP_FS_CHECKSUM_HASH_SUPPORTED_CMD to be enabled.

### Supported file hash/checksum types request

Supported file hash/checksum types request header:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>8</td>
<td>3</td>
</tr>
</tbody>
</table>
The command sends empty CBOR map as data.

**Supported file hash/checksum types response**  
Supported file hash/checksum types response header:

```
+-------+-------+-------+
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>8</td>
<td>3</td>
</tr>
</tbody>
</table>
```

CBOR data of successful response:

```json
format (0 = int, 1 = byte array)
{
    (str)"types" : {
        (str)<hash_checksum_name> : {
            (str)"format" : (uint)
            (str)"size" : (uint)
        }
    }
    ...
}
```

In case of error the CBOR data takes form:

```json
{
    (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th>&lt;hash_checksum_name&gt;</th>
<th>name of the hash/checksum type</th>
<th>Hash/checksum types</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;format&quot;</td>
<td>format that the hash/checksum returns where 0 is for numerical and 1 is for byte array.</td>
<td></td>
</tr>
<tr>
<td>&quot;size&quot;</td>
<td>size (in bytes) of output hash/checksum response.</td>
<td></td>
</tr>
</tbody>
</table>

In case when “rc” is not 0, success, the other fields will not appear.

**Shell management**  
Shell management allows to pass commands to shell subsystem with use of SMP protocol.

Shell management group defines following commands:

```
+-------+------------------+
<table>
<thead>
<tr>
<th>Command ID</th>
<th>Command description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Shell command line execute</td>
</tr>
</tbody>
</table>
```

**Shell command line execute**  
The command allows to execute command line in a similar way to typing it into a shell, but both a request and a response are transported with use of SMP.

**Shell command line execute request**  
Execute command request header:

```
+-------+-------+-------+
<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>2</td>
<td>9</td>
<td>0</td>
</tr>
</tbody>
</table>
```

CBOR data of request:
where:

<table>
<thead>
<tr>
<th></th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;argv&quot;</td>
<td>is array consisting of strings representing command and its arguments</td>
</tr>
<tr>
<td>&lt;cmd&gt;</td>
<td>command to be executed</td>
</tr>
<tr>
<td>&lt;arg&gt;</td>
<td>optional arguments to command</td>
</tr>
</tbody>
</table>

**Shell command line execute response**

Command line execute response header fields:

<table>
<thead>
<tr>
<th>OP</th>
<th>Group ID</th>
<th>Command ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>9</td>
<td>0</td>
</tr>
</tbody>
</table>

CBOR data of successful response:

```json
{
  (str)"o" : (str),
  (str)"ret" : (int)
}
```

In case of error the CBOR data takes form:

```json
{
  (str)"rc" : (int)
}
```

where:

<table>
<thead>
<tr>
<th></th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>&quot;rc&quot;</td>
<td>Status/error codes in responses (only present if an error occurred)</td>
</tr>
<tr>
<td>&quot;o&quot;</td>
<td>command output</td>
</tr>
<tr>
<td>&quot;ret&quot;</td>
<td>return code from shell command execution</td>
</tr>
</tbody>
</table>

In case when “rc” is not 0, success, the other fields will not appear.

**Note:** In older versions of Zephyr, “rc” was used for both the mcumgr status code and shell command execution return code, this legacy behaviour can be restored by enabling `CONFIG_MCUMGR_CMD_SHELL_MGMT_LEGACY_RC_RETURN_CODE`

### 4.3.5 SMP Transport Specification

The documents specifies information needed for implementing server and client side SMP transports.

**BLE (Bluetooth Low Energy)**

MCUmgm Clients need to use following BLE Characteristics, when implementing SMP client:

- **Service UUID:** `8D53DC1D-1DB7-4CD3-868B-8A527460AA84`
- **Characteristic UUID**: `DA2E7828-FBCE-4E01-AE9E-261174997C48`

  All SMP communication utilizes a single GATT characteristic. An SMP request is sent via a GATT Write Without Response command. An SMP response is sent in the form of a GATT Notification.

  If an SMP request or response is too large to fit in a single GATT command, the sender fragments it across several packets. No additional framing is introduced when a request or response is fragmented; the payload is simply split among several packets. Since GATT guarantees ordered delivery of packets, the SMP header in the first fragment contains sufficient information for reassembly.

**UART/serial and console**

SMP protocol specification by MCUmgr subsystem of Zephyr uses basic framing of data to allow multiplexing of UART channel. Multiplexing requires prefixing each frame with two byte marker and terminating it with newline. Currently MCUmgr imposes a 127 byte limit on frame size, although there are no real protocol constraints that require that limit. The limit includes the prefix and the newline character, so the allowed payload size is actually 124 bytes.

Although no such transport exists in Zephyr, it is possible to implement MCUmgr client/server over UART transport that does not have framing at all, or uses hardware serial port control, or other means of framing.

**Frame fragmenting**  SMP protocol over serial is fragmented into MTU size frames; each frame consists of two byte start marker, body and terminating newline character.

There are four types of types of frames: initial, partial, partial-final and initial-final; each frame type differs by start marker and/or body contents.

**Frame formats**  Initial frame requires to be followed by optional sequence of partial frames and finally by partial-final frame. Body is always Base64 encoded, so the body size, here described as MTU - 3, is able to actually carry N = (MTU - 3) / 4 * 3 bytes of raw data.

Body of initial frame is preceded by two byte total packet length, encoded in Big Endian, and equals size of a raw body plus two bytes, size of CRC16; this means that actual body size allowed into an initial frame is N - 2.

If a body size is smaller than N - 4, than it is possible to carry entire body with preceding length and following it CRC in a single frame, here called initial-final; for the description of initial-final frame look below.

Initial frame format:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0x06 0x09</td>
<td>2 bytes</td>
<td>Frame start marker</td>
</tr>
<tr>
<td>&lt;base64-i&gt;</td>
<td>no more than MTU - 3 bytes</td>
<td>Base64 encoded body</td>
</tr>
<tr>
<td>0x0a</td>
<td>1 byte</td>
<td>Frame termination</td>
</tr>
</tbody>
</table>

<base64-i> is Base64 encoded body of format:

<table>
<thead>
<tr>
<th>Content</th>
<th>Size</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>total length</td>
<td>2 bytes</td>
<td>Big endian 16-bit value representing total length of body + 2 bytes for CRC16; note that size of total length field is not added to total length value.</td>
</tr>
<tr>
<td>body</td>
<td>no more than MTU - 5</td>
<td>Raw body data fragment</td>
</tr>
</tbody>
</table>

Initial-final frame format is similar to initial frame format, but differs by <base64-i> definition.
**4.3.6 Device Firmware Upgrade**

**Overview**

The Device Firmware Upgrade subsystem provides the necessary frameworks to upgrade the image of a Zephyr-based application at run time. It currently consists of two different modules:

- `subsys/dfu/boot/`: Interface code to bootloaders
- `subsys/dfu/img_util/`: Image management code

The DFU subsystem deals with image management, but not with the transport or management protocols themselves required to send the image to the target device. For information on these protocols and frameworks please refer to the *Device Management* section.

**Bootloaders**

**MCUboot**  
Zephyr is directly compatible with the open source, cross-RTOS MCUboot boot loader. It interfaces with MCUboot and is aware of the image format required by it, so that Device Firmware Upgrade is available when MCUboot is the boot loader used with Zephyr. The source code itself is hosted in the [MCUboot GitHub Project](https://github.com/mcu-boot/mcuboot) page.

In order to use MCUboot with Zephyr you need to take the following into account:
1. You will need to define the flash partitions required by MCUboot; see Flash map for details.

2. You will have to specify your flash partition as the chosen code partition

```c
/ {
    chosen {
        zephyr,code-partition = &slot0_partition;
    };
};
```

3. Your application’s .conf file needs to enable the CONFIG_BOOTLOADER_MCUBOOT Kconfig option in order for Zephyr to be built in an MCUboot-compatible manner

4. You need to build and flash MCUboot itself on your device

5. You might need to take precautions to avoid mass erasing the flash and also to flash the Zephyr application image at the correct offset (right after the bootloader)

More detailed information regarding the use of MCUboot with Zephyr can be found in the MCUBoot with Zephyr documentation page on the MCUboot website.

### 4.3.7 Over-the-Air Update

**Overview**

Over-the-Air (OTA) Update is a method for delivering firmware updates to remote devices using a network connection. Although the name implies a wireless connection, updates received over a wired connection (such as Ethernet) are still commonly referred to as OTA updates. This approach requires server infrastructure to host the firmware binary and implement a method of signaling when an update is available. Security is a concern with OTA updates; firmware binaries should be cryptographically signed and verified before upgrading.

The Device Firmware Upgrade section discusses upgrading Zephyr firmware using MCUboot. The same method can be used as part of OTA. The binary is first downloaded into an unoccupied code partition, usually named slot1_partition, then upgraded using the MCUboot process.

**Examples of OTA**

**Golioth**  
Golioth is an IoT management platform that includes OTA updates. Devices are configured to observe your available firmware revisions on the Golioth Cloud. When a new version is available, the device downloads and flashes the binary. In this implementation, the connection between cloud and device is secured using TLS/DTLS, and the signed firmware binary is confirmed by MCUboot before the upgrade occurs.

1. A working sample can be found on the Golioth Zephyr-SDK repository
2. The Golioth OTA documentation includes complete information about the versioning process

**Eclipse hawkBit™**  
Eclipse hawkBit™ is an update server framework that uses polling on a REST api to detect firmware updates. When a new update is detected, the binary is downloaded and installed. MCUboot can be used to verify the signature before upgrading the firmware.

There is a hawkbit-api-sample included in the Zephyr mgmt-samples section.

**UpdateHub**  
UpdateHub is a platform for remotely updating embedded devices. Updates can be manually triggered or monitored via polling. When a new update is detected, the binary is downloaded and installed. MCUboot can be used to verify the signature before upgrading the firmware.

There is an updatehub_fota_sample included in the Zephyr mgmt-samples section.
SMP Server  A Simple Management Protocol (SMP) server can be used to update firmware via Bluetooth Low Energy (BLE) or UDP. **MCUmgr** is used to send a signed firmware binary to the remote device where it is verified by MCUboot before the upgrade occurs.

There is an **smp_svr_sample** included in the Zephyr mgmt-samples section.

Lightweight M2M (LWM2M)  The **Lightweight M2M (LWM2M)** protocol includes support for firmware update via `CONFIG_LWM2M_FIRMWARE_UPDATE_OBJ_SUPPORT`. Devices securely connect to an LwM2M server using DTLS. An **lwm2m-client-sample** sample is available but it does not demonstrate the firmware update feature.

4.3.8  SMP Groups

4.4  File Systems

Zephyr RTOS Virtual Filesystem Switch (VFS) allows applications to mount multiple file systems at different mount points (e.g., `/fatfs` and `/lfs`). The mount point data structure contains all the necessary information required to instantiate, mount, and operate on a file system. The File system Switch decouples the applications from directly accessing an individual file system's specific API or internal functions by introducing file system registration mechanisms.

In Zephyr, any file system implementation or library can be plugged into or pulled out through a file system registration API. Each file system implementation must have a globally unique integer identifier; use `FS_TYPE_EXTERNAL_BASE` to avoid clashes with in-tree identifiers.

```c
int fs_register(int type, const struct fs_file_system_t *fs);
int fs_unregister(int type, const struct fs_file_system_t *fs);
```

Zephyr RTOS supports multiple instances of a file system by making use of the mount point as the disk volume name, which is used by the file system library while formatting or mounting a disk.

A file system is declared as:

```c
static struct fs_mount_t mp = {
    .type = FS_FATFS,
    .mnt_point = FATFS_MNTP,
    .fs_data = &fat_fs,
};
```

where

- `FS_FATFS` is the file system type like FATFS or LittleFS.
- `FATFS_MNTP` is the mount point where the file system will be mounted.
- `fat_fs` is the file system data which will be used by `fs_mount()` API.

4.4.1  Samples

Samples for the VFS are mainly supplied in `samples/subsys/fs`, although various examples of the VFS usage are provided as important functionalities in samples for different subsystems. Here is the list of samples worth looking at:

- **samples/subsys/fs/fat_fs** is an example of FAT file system usage with SDHC media;
- **samples/subsys/shell/fs** is an example of Shell fs subsystem, using internal flash partition formatted to LittleFS;
• samples/subsys/usb/mass/ example of USB Mass Storage device that uses FAT FS driver with RAM or SPI connected FLASH, or LittleFS in flash, depending on the sample configuration.

4.4.2 API Reference

group file_system_api
File System APIs.

fs_open open and creation mode flags

FS_0_READ
Open for read flag

FS_0_WRITE
Open for write flag

FS_0_RDWR
Open for read-write flag combination

FS_0_MODE_MASK
Bitmask for read and write flags

FS_0_CREATE
Create file if it does not exist

FS_0_APPEND
Open/create file for append

FS_0_FLAGS_MASK
Bitmask for open/create flags

FS_0_MASK
Bitmask for open flags

fs_seek whence parameter values

FS_SEEK_SET
Seek from the beginning of file

FS_SEEK_CUR
Seek from a current position

FS_SEEK_END
Seek from the end of file
Defines

FS_MOUNT_FLAG_NO_FORMAT
   Flag prevents formatting device if requested file system not found

FS_MOUNT_FLAG_READ_ONLY
   Flag makes mounted file system read-only

FS_MOUNT_FLAG_AUTOMOUNT
   Flag used in pre-defined mount structures that are to be mounted on startup.
   This flag has no impact in user-defined mount structures.

FS_MOUNT_FLAG_USE_DISK_ACCESS
   Flag requests file system driver to use Disk Access API. When the flag is set to the
   fs_mount_t.flags prior to fs_mount call, a file system needs to use the Disk Access API, other-
   wise mount callback for the driver should return -ENOSUP; when the flag is not set the file
   system driver should use Flash API by default, unless it only supports Disc Access API. When
   file system will use Disk Access API and the flag is not set, the mount callback for the file
   system should set the flag on success.

FSTAB_ENTRY_DT_MOUNT_FLAGS(node_id)

FS_FSTAB_ENTRY(node_id)
   The name under which a zephyr,fstab entry mount structure is defined.

FS_FSTAB_DECLARE_ENTRY(node_id)
   Generate a declaration for the externally defined fstab entry.
   This will evaluate to the name of a struct fs_mount_t object.

Enums

enum fs_dir_entry_type
   Values:

   enumerator FS_DIR_ENTRY_FILE = 0
       Identifier for file entry

   enumerator FS_DIR_ENTRY_DIR
       Identifier for directory entry

enum [anonymous]
   Enumeration to uniquely identify file system types.

Zephyr supports in-tree file systems and external ones. Each requires a unique identifier used
   to register the file system implementation and to associate a mount point with the file system
type. This anonymous enum defines global identifiers for the in-tree file systems.

External file systems should be registered using unique identifiers starting at
   FS_TYPE_EXTERNAL_BASE. It is the responsibility of applications that use external file
   systems to ensure that these identifiers are unique if multiple file system implementations are
   used by the application.
   Values:

4.4. File Systems
enumerator FS_FATFS = 0
    Identifier for in-tree FatFS file system.

enumerator FS_LITTLEFS
    Identifier for in-tree LittleFS file system.

enumerator FS_TYPE_EXTERNAL_BASE
    Base identifier for external file systems.

Functions

static inline void fs_file_t_init(struct fs_file_t *zfp)
    Initialize fs_file_t object.
    Initializes the fs_file_t object; the function needs to be invoked on object before first use with fs_open.

    Parameters
        • zfp – Pointer to file object

static inline void fs_dir_t_init(struct fs_dir_t *zdp)
    Initialize fs_dir_t object.
    Initializes the fs_dir_t object; the function needs to be invoked on object before first use with fs_opendir.

    Parameters
        • zdp – Pointer to file object

int fs_open(struct fs_file_t *zfp, const char *file_name, fs_mode_t flags)
    Open or create file.
    Opens or possibly creates a file and associates a stream with it.
    flags can be 0 or a binary combination of one or more of the following identifiers:
        • FS_O_READ open for read
        • FS_O_WRITE open for write
        • FS_O_RDWR open for read/write (FS_O_READ | FS_O_WRITE)
        • FS_O_CREATE create file if it does not exist
        • FS_O_APPEND move to end of file before each write
    If flags are set to 0 the function will attempt to open an existing file with no read/write access; this may be used to e.g. check if the file exists.

    Parameters
        • zfp – Pointer to a file object
        • file_name – The name of a file to open
        • flags – The mode flags

    Return values
        • 0 – on success;
        • -EBUSY – when zfp is already used;
        • -EINVAL – when a bad file name is given;
- EROFS – when opening read-only file for write, or attempting to create a file on a system that has been mounted with the FS_MOUNT_FLAG_READ ONLY flag;
- ENOENT – when the file path is not possible (bad mount point);
- ENOTSUP – when not implemented by underlying file system driver;
- <0 – an other negative errno code, depending on a file system back-end.

```c
int fs_close(struct fs_file_t *zfp)
```

Close file.

Flushes the associated stream and closes the file.

**Parameters**
- zfp – Pointer to the file object

**Return values**
- 0 – on success;
- ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.

```c
int fs_unlink(const char *path)
```

Unlink file.

Deletes the specified file or directory

**Parameters**
- path – Path to the file or directory to delete

**Return values**
- 0 – on success;
- EINVAL – when a bad file name is given;
- EROFS – if file is read-only, or when file system has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
- ENOTSUP – when not implemented by underlying file system driver;
- <0 – an other negative errno code on error.

```c
int fs_rename(const char *from, const char *to)
```

Rename file or directory.

Performs a rename and / or move of the specified source path to the specified destination. The source path can refer to either a file or a directory. All intermediate directories in the destination path must already exist. If the source path refers to a file, the destination path must contain a full filename path, rather than just the new parent directory. If an object already exists at the specified destination path, this function causes it to be unlinked prior to the rename (i.e., the destination gets clobbered).

**Note:** Current implementation does not allow moving files between mount points.

**Parameters**
- from – The source path
- to – The destination path

**Return values**
• 0 – on success;
• -EINVAL – when a bad file name is given, or when rename would cause move between mount points;
• -EROFS – if file is read-only, or when file system has been mounted with the FS_MOUNT_FLAG_READ_ONLY flag;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

ssize_t fs_read(struct fs_file_t *zfp, void *ptr, size_t size)
Read file.

Reads up to size bytes of data to ptr pointed buffer, returns number of bytes read. A returned value may be lower than size if there were fewer bytes available than requested.

Parameters
• zfp – Pointer to the file object
• ptr – Pointer to the data buffer
• size – Number of bytes to be read

Return values
• >=0 – a number of bytes read, on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – a negative errno code on error.

ssize_t fs_write(struct fs_file_t *zfp, const void *ptr, size_t size)
Write file.

Attempts to write size number of bytes to the specified file. If a negative value is returned from the function, the file pointer has not been advanced. If the function returns a non-negative number that is lower than size, the global errno variable should be checked for an error code, as the device may have no free space for data.

Parameters
• zfp – Pointer to the file object
• ptr – Pointer to the data buffer
• size – Number of bytes to be written

Return values
• >=0 – a number of bytes written, on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_seek(struct fs_file_t *zfp, off_t offset, int whence)
Seek file.

Moves the file position to a new location in the file. The offset is added to file position based on the whence parameter.

Parameters
• zfp – Pointer to the file object
• offset – Relative location to move the file pointer to
• whence – Relative location from where offset is to be calculated.
  – FS_SEEK_SET for the beginning of the file;
  – FS_SEEK_CUR for the current position;
  – FS_SEEK_END for the end of the file.

Return values
• 0 – on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – if not supported by underlying file system driver;
• <0 – an other negative errno code on error.

off_t fs_tell(struct fs_file_t *zfp)
Get current file position.
Retrieves and returns the current position in the file stream.

The current revision does not validate the file object.

Parameters
• zfp – Pointer to the file object

Return values
• >= 0 a current position in file;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – if not supported by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_truncate(struct fs_file_t *zfp, off_t length)
Truncate or extend an open file to a given size.
Truncates the file to the new length if it is shorter than the current size of the file. Expands the
file if the new length is greater than the current size of the file. The expanded region would
be filled with zeroes.

Note: In the case of expansion, if the volume got full during the expansion process, the
function will expand to the maximum possible length and return success. Caller should check
if the expanded size matches the requested length.

Parameters
• zfp – Pointer to the file object
• length – New size of the file in bytes

Return values
• 0 – on success;
• -EBADF – when invoked on zfp that represents unopened/closed file;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.
int \texttt{fs\_sync} (struct \texttt{fs\_file\_t} *zfp)

Flush cached write data buffers of an open file.

The function flushes the cache of an open file; it can be invoked to ensure data gets written to the storage media immediately, e.g. to avoid data loss in case if power is removed unexpectedly.

**Note:** Closing a file will cause caches to be flushed correctly so the function need not be called when the file is being closed.

**Parameters**
- zfp – Pointer to the file object

**Return values**
- 0 – on success;
- -EBADF – when invoked on zfp that represents unopened/closed file;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.

int \texttt{fs\_mkdir} (const char *path)

Directory create.

Creates a new directory using specified path.

**Parameters**
- path – Path to the directory to create

**Return values**
- 0 – on success;
- -EROFS – if file is read-only, or when file system has been mounted with the \texttt{FS\_MOUNT\_FLAG\_READ\_ONLY} flag;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – an other negative errno code on error

int \texttt{fs\_opendir} (struct \texttt{fs\_dir\_t} *zdp, const char *path)

Directory open.

Opens an existing directory specified by the path.

**Parameters**
- zdp – Pointer to the directory object
- path – Path to the directory to open

**Return values**
- 0 – on success;
- -EINVAL – when a bad directory path is given;
- -EBUSY – when zdp is already used;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.
int fs_readdir(struct fs_dir_t *zdp, struct fs_dirent *entry)
    Directory read entry.

    Reads directory entries of an open directory. In end-of-dir condition, the function will return
    0 and set the entry->name[0] to 0.

    **Note:** Most existing underlying file systems do not generate POSIX special directory entries
    “.” or “..”. For consistency the abstraction layer will remove these from lower layer results so
    higher layers see consistent results.

**Parameters**
- zdp – Pointer to the directory object
- entry – Pointer to zfs_dirent structure to read the entry into

**Return values**
- 0 – on success or end-of-dir;
- -ENOENT – when no such directory found;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.

int fs_closedir(struct fs_dir_t *zdp)
    Directory close.

    Closes an open directory.

**Parameters**
- zdp – Pointer to the directory object

**Return values**
- 0 – on success;
- -ENOTSUP – when not implemented by underlying file system driver;
- <0 – a negative errno code on error.

int fs_mount(struct fs_mount_t *mp)
    Mount filesystem.

    Perform steps needed for mounting a file system like calling the file system specific mount
    function and adding the mount point to mounted file system list.

    **Note:** Current implementation of ELM FAT driver allows only following mount points:
    “/RAM:”, “/NAND:”, “/CF:”, “/SD:”, “/SD2:”, “/USB:”, “/USB2:”, “/USB3:” or mount points that
    consist of single digit, e.g: “/0:”, “/1:” and so forth.

**Parameters**
- mp – Pointer to the fs_mount_t structure. Referenced object is not changed if the
    mount operation failed. A reference is captured in the fs infrastructure if the
    mount operation succeeds, and the application must not mutate the structure
    contents until fsUnmount is successfully invoked on the same pointer.

**Return values**
- 0 – on success;
- -ENOENT – when file system type has not been registered;
• -ENOTSUP – when not supported by underlying file system driver; when FS_MOUNT_FLAG_USE_DISK_ACCESS is set but driver does not support it.
• -EROFS – if system requires formatting but FS_MOUNT_FLAG_READ_ONLY has been set;
• <0 – an other negative errno code on error.

int fs_unmount(struct fs_mount_t *mp)
Unmount filesystem.
Perform steps needed to unmount a file system like calling the file system specific unmount function and removing the mount point from mounted file system list.

Parameters
• mp – Pointer to the fs_mount_t structure

Return values
• 0 – on success;
• -EINVAL – if no system has been mounted at given mount point;
• -ENOTSUP – when not supported by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_readmount(int *index, const char **name)
Get path of mount point at index.
This function iterates through the list of mount points and returns the directory name of the mount point at the given index. On success index is incremented and name is set to the mount directory name. If a mount point with the given index does not exist, name will be set to NULL.

Parameters
• index – Pointer to mount point index
• name – Pointer to pointer to path name

Return values
• 0 – on success;
• -ENOENT – if there is no mount point with given index.

int fs_stat(const char *path, struct fs_dirent *entry)
File or directory status.
Checks the status of a file or directory specified by the path.

Note: The file on a storage device may not be updated until it is closed.

Parameters
• path – Path to the file or directory
• entry – Pointer to the zfs_dirent structure to fill if the file or directory exists.

Return values
• 0 – on success;
• -EINVAL – when a bad directory or file name is given;
• -ENOENT – when no such directory or file is found;
• -ENOTSUP – when not supported by underlying file system driver;
• <0 – negative errno code on error.

int fs_statvfs(const char *path, struct fs_statvfs *stat)
Retrieves statistics of the file system volume.
Returns the total and available space in the file system volume.

Parameters
• path – Path to the mounted directory
• stat – Pointer to the zfs_statvfs structure to receive the fs statistics.

Return values
• 0 – on success;
• -EINVAL – when a bad path to a directory, or a file, is given;
• -ENOTSUP – when not implemented by underlying file system driver;
• <0 – an other negative errno code on error.

int fs_register(int type, const struct fs_file_system_t *fs)
Register a file system.
Register file system with virtual file system. Number of allowed file system types to be registered is controlled with the CONFIG_FILE_SYSTEM_MAX_TYPES Kconfig option.

Parameters
• type – Type of file system (ex: FS_FATFS)
• fs – Pointer to File system

Return values
• 0 – on success;
• -EALREADY – when a file system of a given type has already been registered;
• -ENOSCP – when there is no space left, in file system registry, to add this file system type.

int fs_unregister(int type, const struct fs_file_system_t *fs)
Unregister a file system.
Unregister file system from virtual file system.

Parameters
• type – Type of file system (ex: FS_FATFS)
• fs – Pointer to File system

Return values
• 0 – on success;
• -EINVAL – when file system of a given type has not been registered.

struct fs_mount_t
#include <fs.h> File system mount info structure.

Param node
Entry for the fs_mount_list list

Param type
File system type
Param mnt_point
   Mount point directory name (ex: “/fatfs”)

Param fs_data
   Pointer to file system specific data

Param storage_dev
   Pointer to backend storage device

Param mountp_len
   Length of Mount point string

Param fs
   Pointer to File system interface of the mount point

Param flags
   Mount flags

#include <fs.h>
Structure to receive file or directory information.
Used in functions that reads the directory entries to get file or directory information.

Param dir_entry_type
   Whether file or directory
   • FS_DIR_ENTRY_FILE
   • FS_DIR_ENTRY_DIR

Param name
   Name of directory or file

Param size
   Size of file. 0 if directory

#include <fs.h>
Structure to receive volume statistics.
Used to retrieve information about total and available space in the volume.

Param f_bsize
   Optimal transfer block size

Param f_frsize
   Allocation unit size

Param f_blocks
   Size of FS in f_frsize units

Param f_bfree
   Number of free blocks

#include <fs_interface.h>
File object representing an open file.
The object needs to be initialized with function fs_file_t_init().

Param Pointer
   to FATFS file object structure

Param mp
   Pointer to mount point structure
struct fs_dir_t

#include <fs_interface.h> Directory object representing an open directory.
The object needs to be initialized with function fs_dir_t_init().

Param dirp
Pointer to directory object structure

Param mp
Pointer to mount point structure

struct fs_file_system_t

#include <fs_sys.h> File System interface structure.

Param open
Opens or creates a file, depending on flags given

Param read
Reads nbytes number of bytes

Param write
Writes nbytes number of bytes

Param lseek
Moves the file position to a new location in the file

Param tell
Retrieves the current position in the file

Param truncate
Truncates/expands the file to the new length

Param sync
Flushes the cache of an open file

Param close
Flushes the associated stream and closes the file

Param opendir
Opens an existing directory specified by the path

Param readdir
Reads directory entries of an open directory

Param closedir
Closes an open directory

Param mount
Mounts a file system

Param umount
Unmounts a file system

Param unlink
Deletes the specified file or directory

Param rename
Renames a file or directory

Param mkdir
Creates a new directory using specified path

Param stat
Checks the status of a file or directory specified by the path

Param statvfs
Returns the total and available space on the file system volume
4.5 Formatted Output

Applications as well as Zephyr itself requires infrastructure to format values for user consumption. The standard C99 library `printf()` functionality fulfills this need for streaming output devices or memory buffers, but in an embedded system devices may not accept streamed data and memory may not be available to store the formatted output.

Internal Zephyr API traditionally provided this both for `printf()` and for Zephyr's internal minimal libc, but with separate internal interfaces. Logging, tracing, shell, and other applications made use of either these APIs or standard libc routines based on build options.

The `cbprintf()` public APIs convert C99 format strings and arguments, providing output produced one character at a time through a callback mechanism, replacing the original internal functions and providing support for almost all C99 format specifications. Existing use of `s*printf()` C libraries in Zephyr can be converted to `snprintfcb()` to avoid pulling in libc implementations.

Several Kconfig options control the set of features that are enabled, allowing some control over features and memory usage:

- `CONFIG_CBPRINTF_FULL_INTEGRAL` or `CONFIG_CBPRINTF_REduced_INTEGRAL`
- `CONFIG_CBPRINTF_FP_SUPPORT`
- `CONFIG_CBPRINTF_FP_A_SUPPORT`
- `CONFIG_CBPRINTF_FP_ALWAYS_A`
- `CONFIG_CBPRINTF_N_SPECIFIER`

`CONFIG_CBPRINTF_LIBC_SUBSTS` can be used to provide functions that behave like standard libc functions but use the selected `cbprintf` formatter rather than pulling in another formatter from libc.

In addition `CONFIG_CBPRINTF_NANO` can be used to revert back to the very space-optimized but limited formatter used for `printf()` before this capability was added.

4.5.1 Cbprintf Packaging

Typically, strings are formatted synchronously when a function from `printf` family is called. However, there are cases when it is beneficial that formatting is deferred. In that case, a state (format string and arguments) must be captured. Such state forms a self-contained package which contains format string and arguments. Additionally, package may contain copies of strings which are part of a format string (format string or any `%s` argument). Package primary content resembles `va_list` stack frame thus standard formatting functions are used to process a package. Since package contains data which is processed as `va_list` frame, strict alignment must be maintained. Due to required padding, size of the package depends on alignment. When package is copied, it should be copied to a memory block with the same alignment as origin.

Package can have following variants:

- **Self-contained** - non read-only strings appended to the package. String can be formatted from such package as long as there is access to read-only string locations. Package may contain information where read-only strings are located within the package. That information can be used to convert packet to fully self-contained package.

- **Fully self-contained** - all strings are appended to the package. String can be formatted from such package without any external data.

- **Transient** - only arguments are stored. Package contain information where pointers to non read-only strings are located within the package. Optionally, it may contain read-only string location information. String can be formatted from such package as long as non read-only strings are still valid and read-only strings are accessible. Alternatively, package can be converted to `self-contained` package or `fully self-contained` if information about read-only string locations is present in the package.
Package can be created using two methods:

- runtime - using `cbprintf_package()` or `cbvprintf_package()`. This method scans format string and based on detected format specifiers builds the package.
- static - types of arguments are detected at compile time by the preprocessor and package is created as simple assignments to a provided memory. This method is significantly faster than runtime (more than 15 times) but has following limitations: requires `_Generic` keyword (C11 feature) to be supported by the compiler and cannot distinguish between `%p` and `%s` if char pointer is used. It treats all (unsigned) char pointers as `%s` thus it will attempt to append string to a package. It can be handled correctly during conversion from `transient` package to `self-contained` package using `CBPRINTF_PACKAGE_CONVERT_PTR_CHECK` flag. However, it requires access to the format string and it is not always possible thus it is recommended to cast char pointers used for `%p` to `void*`. There is a logging warning generated by `cbprintf_package_convert()` called with `CBPRINTF_PACKAGE_CONVERT_PTR_CHECK` flag when char pointer is used with `%p`.

Several Kconfig options control behavior of the packaging:

- `CONFIG_CBPRINTF_PACKAGE_LONGDOUBLE`
- `CONFIG_CBPRINTF_STATIC_PACKAGE_CHECK_ALIGNMENT`

**Cbprintf package conversion**

It is possible to convert package to a variant which contains more information, e.g `transient` package can be converted to `self-contained`. Conversion to fully `self-contained` package is possible if `CBPRINTF_PACKAGE_ADD_RO_STR_POS` flag was used when package was created.

`cbprintf_package_copy()` is used to calculate space needed for the new package and to copy and convert a package.

**Cbprintf package format**

Format of the package contains paddings which are platform specific. Package consists of header which contains size of package (excluding appended strings) and number of appended strings. It is followed by the arguments which contains alignment paddings and resembles `va_list` stack frame. It is followed by data associated with character pointer arguments used by the string which are not appended to the string (but may be appended later by `cbprintf_package_convert()`). Finally, package, optionally, contains appended strings. Each string contains 1 byte header which contains index of the location where address argument is stored. During packaging address is set to null and before string formatting it is updated to point to the current string location within the package. Updating address argument must happen just before string formatting since address changes whenever package is copied.
<table>
<thead>
<tr>
<th>Header</th>
<th>1 byte: Argument list size including header and \textit{fmt} (in 32 bit words)</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1 byte: Number of strings appended to the package</td>
</tr>
<tr>
<td></td>
<td>1 byte: Number of read-only string argument locations</td>
</tr>
<tr>
<td></td>
<td>1 byte: Number of transient string argument locations</td>
</tr>
<tr>
<td></td>
<td>platform specific padding to sizeof(void *)</td>
</tr>
<tr>
<td>Arguments</td>
<td>Pointer to \textit{fmt} (or null if \textit{fmt} is appended to the package)</td>
</tr>
<tr>
<td></td>
<td>(optional padding for platform specific alignment)</td>
</tr>
<tr>
<td></td>
<td>argument 0</td>
</tr>
<tr>
<td></td>
<td>(optional padding for platform specific alignment)</td>
</tr>
<tr>
<td></td>
<td>argument 1</td>
</tr>
<tr>
<td></td>
<td>...</td>
</tr>
<tr>
<td>String location information (optional)</td>
<td>Indexes of words within the package where read-only strings are located</td>
</tr>
<tr>
<td></td>
<td>Pairs of argument index and argument location index where transient strings are located</td>
</tr>
<tr>
<td>Appended strings (optional)</td>
<td>1 byte: Index within the package to the location of associated argument</td>
</tr>
<tr>
<td></td>
<td>Null terminated string</td>
</tr>
<tr>
<td></td>
<td>...</td>
</tr>
</tbody>
</table>

**Warning:** If 	exttt{CONFIG_MINIMAL_LIBC} is selected in combination with 	exttt{CONFIG_CBPRINTF_NANO} formatting with C standard library functions like \texttt{printf} or \texttt{snprintf} is limited. Among other things the \texttt{%n} specifier, most format flags, precision control, and floating point are not supported.

Limitations and recommendations

- C11 \_Generic support is required by the compiler to use static (fast) packaging.
- It is recommended to cast any character pointer used with \texttt{%p} format specifier to other pointer type (e.g. \texttt{void *}). If format string is not accessible then only static packaging is possible and it will append all detected strings. Character pointer used for \texttt{%p} will be considered as string pointer. Copying from unexpected location can have serious consequences (e.g., memory fault or security violation).

4.5.2 API Reference

\texttt{group cbprintf\_apis}

**Defines**

\texttt{CBPRINTF\_PACKAGE\_ALIGNMENT}

Required alignment of the buffer used for packaging.

\texttt{CBPRINTF\_MUST\_RUNTIME\_PACKAGE(flags, ...)}

Determine if string must be packaged in run time.

Static packaging can be applied if size of the package can be determined at compile time. In general, package size can be determined at compile time if there are no string arguments which might be copied into package body if they are considered transient.
Note: By default any char pointers are considered to be pointing at transient strings. This can be narrowed down to non const pointers by using \texttt{CBPRINTF\_PACKAGE\_CONST\_CHAR\_RO}.

**Parameters**

- \ldots – String with arguments.
- \texttt{flags} – option flags. See Package flags.

**Return values**

- 1 – if string must be packaged in run time.
- 0 – string can be statically packaged.

\texttt{CBPRINTF\_STATIC\_PACKAGE}(packaged, inlen, outlen, align_offset, flags, \ldots)

Statically package string.

Build string package from formatted string. It assumes that formatted string is in the read only memory.

If \_\_Generic is not supported then runtime packaging is performed.

**Parameters**

- \texttt{packaged} – pointer to where the packaged data can be stored. Pass a null pointer to skip packaging but still calculate the total space required. The data stored here is relocatable, that is it can be moved to another contiguous block of memory. It must be aligned to the size of the longest argument. It is recommended to use \texttt{CBPRINTF\_PACKAGE\_ALIGNMENT} for alignment.
- \texttt{inlen} – set to the number of bytes available at \texttt{packaged}. If \texttt{packaged} is NULL the value is ignored.
- \texttt{outlen} – variable updated to the number of bytes required to completely store the packed information. If input buffer was too small it is set to -ENOSPC.
- \texttt{align_offset} – input buffer alignment offset in bytes. Where offset 0 means that buffer is aligned to \texttt{CBPRINTF\_PACKAGE\_ALIGNMENT}. Xtensa requires that \texttt{packaged} is aligned to \texttt{CBPRINTF\_PACKAGE\_ALIGNMENT} so it must be multiply of \texttt{CBPRINTF\_PACKAGE\_ALIGNMENT} or 0.
- \texttt{flags} – option flags. See Package flags.
- \ldots – formatted string with arguments. Format string must be constant.

**Typedefs**

typedef int (*cbprintf\_cb)()

Signature for a cbprintf callback function.

This function expects two parameters:

- \texttt{c} a character to output. The output behavior should be as if this was cast to an unsigned char.
- \texttt{ctx} a pointer to an object that provides context for the output operation.

The declaration does not specify the parameter types. This allows a function like \texttt{fputc} to be used without requiring all context pointers to be to a FILE object.
Return
the value of `c` cast to an unsigned char then back to int, or a negative error code
that will be returned from `cbprintf()`.

typedef int (*cbprintf_convert_cb)(const void *buf, size_t len, void *ctx)
Signature for a cbprintf multibyte callback function.
	nreturn Amount of copied data or negative error code.

Param `buf`
data.

Param `len`
data length.

Param `ctx`
a pointer to an object that provides context for the operation.

typedef int (*cbvprintf_external_formatter_func)(cbprintf_cb out, void *ctx, const char *fmt, va_list ap)
Signature for a external formatter function identical to cbvprintf.

This function expects the following parameters:

Param `out`
the function used to emit each generated character.

Param `ctx`
a pointer to an object that provides context for the external formatter.

Param `fmt`
a standard ISO C format string with characters and conversion specifications.

Param `ap`
captured stack arguments corresponding to the conversion specifications found
within `fmt`.

Return
vprintf like return values: the number of characters printed, or a negative error
value returned from external formatter.

Functions

int cbprintf_package(void *packaged, size_t len, uint32_t flags, const char *format, ...)
Capture state required to output formatted data later.

Like `cbprintf()` but instead of processing the arguments and emitting the formatted results
immediately all arguments are captured so this can be done in a different context, e.g. when
the output function can block.

In addition to the values extracted from arguments this will ensure that copies are made of the
necessary portions of any string parameters that are not confirmed to be stored in read-only
memory (hence assumed to be safe to refer to directly later).

Parameters

• `packaged` – pointer to where the packaged data can be stored. Pass a null
pointer to store nothing but still calculate the total space required. The data
stored here is relocatable, that is it can be moved to another contiguous block
of memory. However, under condition that alignment is maintained. It must be
aligned to at least the size of a pointer.
• `len` – this must be set to the number of bytes available at `packaged` if it is not null. If `packaged` is null then it indicates hypothetical buffer alignment offset in bytes compared to `CBPRINTF_PACKAGE_ALIGNMENT` alignment. Buffer alignment offset impacts returned size of the package. Xtensa requires that buffer is always aligned to `CBPRINTF_PACKAGE_ALIGNMENT` so it must be multiply of `CBPRINTF_PACKAGE_ALIGNMENT` or 0 when `packaged` is null.

• `flags` – option flags. See Package flags.

• `format` – a standard ISO C format string with characters and conversion specifications.

• `...` – arguments corresponding to the conversion specifications found within `format`.

**Return values**

• `nonnegative` – the number of bytes successfully stored at `packaged`. This will not exceed `len`.

• `-EINVAL` – if `format` is not acceptable

• `-EFAULT` – if `packaged` alignment is not acceptable

• `-ENOSPC` – if `packaged` was not null and the space required to store exceed `len`.

```c
int cbvprintf_package(void *packaged, size_t len, uint32_t flags, const char *format, va_list ap)
```

Capture state required to output formatted data later.

Like `cbprintf()` but instead of processing the arguments and emitting the formatted results immediately all arguments are captured so this can be done in a different context, e.g. when the output function can block.

In addition to the values extracted from arguments this will ensure that copies are made of the necessary portions of any string parameters that are not confirmed to be stored in read-only memory (hence assumed to be safe to refer to directly later).

**Parameters**

• `packaged` – pointer to where the packaged data can be stored. Pass a null pointer to store nothing but still calculate the total space required. The data stored here is relocatable, that is it can be moved to another contiguous block of memory. The pointer must be aligned to a multiple of the largest element in the argument list.

• `len` – this must be set to the number of bytes available at `packaged`. Ignored if `packaged` is NULL.

• `flags` – option flags. See Package flags.

• `format` – a standard ISO C format string with characters and conversion specifications.

• `ap` – captured stack arguments corresponding to the conversion specifications found within `format`.

**Return values**

• `nonnegative` – the number of bytes successfully stored at `packaged`. This will not exceed `len`.

• `-EINVAL` – if `format` is not acceptable

• `-EFAULT` – if `packaged` was not null and the space required to store exceed `len`.

```c
int cbprintf_package_convert(void *in_packaged, size_t in_len, cbprintf_convert_cb cb, void *ctx, uint32_t flags, uint16_t *strl, size_t strl_len)
```

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Convert a package.

Converting may include appending strings used in the package to the package body. If input package was created with CBPRINTF_PACKAGE_ADD_RO_STR_POS or CBPRINTF_PACKAGE_ADD_RW_STR_POS, it contains information where strings are located within the package. This information can be used to copy strings during the conversion.

\texttt{cb} is called with portions of the output package. At the end of the conversion \texttt{cb} is called with null buffer.

**Parameters**

- \texttt{in\_packaged} – Input package.
- \texttt{in\_len} – Input package length. If 0 package length will be retrieved from the \texttt{in\_packaged}
- \texttt{cb} – callback called with portions of the converted package. If null only length of the output package is calculated.
- \texttt{ctx} – Context provided to the \texttt{cb}.
- \texttt{flags} – Flags. See Package flags..
- \texttt{strl} – [inout] if \texttt{packaged} is null, it is a pointer to the array where \texttt{strl\_len} first string lengths will is stored. If \texttt{packaged} is not null, it contains lengths of first \texttt{strl\_len} strings. It can be used to optimize copying so that string length is calculated only once (at length calculation phase when \texttt{packaged} is null.)
- \texttt{strl\_len} – Number of elements in \texttt{strl} array.

**Return values**

- Positive – output package size.
- \texttt{-ENOSPC} – if \texttt{packaged} was not null and the space required to store exceed \texttt{len}.

\begin{verbatim}
static inline int cbprintf_package_copy(void *in_packaged, size_t in_len, void *packaged, size_t len, uint32_t flags, uint16_t *strl, size_t strl_len)
\end{verbatim}

Copy package with optional appending of strings.

\texttt{cbprintf\_package\_convert} is used to convert and store converted package in the new location.

**Parameters**

- \texttt{in\_packaged} – Input package.
- \texttt{in\_len} – Input package length. If 0 package length will be retrieved from the \texttt{in\_packaged}
- \texttt{packaged} – [out] Output package. If null only length of the output package is calculated.
- \texttt{len} – Available space in the location pointed by \texttt{packaged}. Not used when \texttt{packaged} is null.
- \texttt{flags} – Flags. See Package flags..
- \texttt{strl} – [inout] if \texttt{packaged} is null, it is a pointer to the array where \texttt{strl\_len} first string lengths will is stored. If \texttt{packaged} is not null, it contains lengths of first \texttt{strl\_len} strings. It can be used to optimize copying so that string length is calculated only once (at length calculation phase when \texttt{packaged} is null.)
- \texttt{strl\_len} – Number of elements in \texttt{strl} array.

**Return values**

- Positive – Output package size.
- \texttt{-ENOSPC} – if \texttt{packaged} was not null and the space required to store exceed \texttt{len}. 

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static inline int cbprintf_fsc_package(void *in_packaged, size_t in_len, void *packaged, size_t len)

Convert package to fully self-contained (fsc) package.

Package may not be self contain since strings by default are stored by address. Package may be partially self-contained when transient (not read only) strings are appended to the package. Such package can be decoded only when there is an access to read-only strings.

Fully self-contained has (fsc) contains all strings used in the package. A package can be converted to fsc package if it was create with CBPRINTF_PACKAGE_ADD_RO_STR_POS flag. Such package will contain necessary data to find read only strings in the package and copy them into the package body.

Parameters

• in_packaged – pointer to original package created with CBPRINTF_PACKAGE_ADD_RO_STR_POS.
• in_len – in_packaged length.
• packaged – pointer to location where fully self-contained version of the input package will be written. Pass a null pointer to calculate space required.
• len – must be set to the number of bytes available at packaged. Not used if packaged is null.

Return values

• nonegative – the number of bytes successfully stored at packaged. This will not exceed len. If packaged is null, calculated length.
• -ENOSPC – if packaged was not null and the space required to store exceed len.
• -EINVAL – if in_packaged is null.

int cbprintf_external(cbprintf_cb out, cbprintf_external_formatter_func formatter, void *ctx, void *packaged)

Generate the output for a previously captured format operation using an external formatter.

Note: Memory indicated by packaged will be modified in a non-destructive way, meaning that it could still be reused with this function again.

Parameters

• out – the function used to emit each generated character.
• formatter – external formatter function.
• ctx – a pointer to an object that provides context for the external formatter.
• packaged – the data required to generate the formatted output, as captured by cbprintf_package() or cbvprintf_package(). The alignment requirement on this data is the same as when it was initially created.

Returns

printf like return values: the number of characters printed, or a negative error value returned from external formatter.

int cbprintf(cbprintf_cb out, *ctx, const char *format, ...)

*printf-like output through a callback.

This is essentially printf() except the output is generated character-by-character using the provided out function. This allows formatting text of unbounded length without incurring the cost of a temporary buffer.
All formatting specifiers of C99 are recognized, and most are supported if the functionality is enabled.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`.
- `format` – a standard ISO C format string with characters and conversion specifications.
- `...` – arguments corresponding to the conversion specifications found within `format`.

**Returns**
the number of characters printed, or a negative error value returned from invoking `out`.

```c
static inline int cbvprintf(cbprintf_cb out, void *ctx, const char *format, va_list ap)
```

varargs-aware `printf-like output through a callback.

This is essentially `vsprintf()` except the output is generated character-by-character using the provided `out` function. This allows formatting text of unbounded length without incurring the cost of a temporary buffer.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**
- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`.
- `format` – a standard ISO C format string with characters and conversion specifications.
- `ap` – a reference to the values to be converted.

**Returns**
the number of characters generated, or a negative error value returned from invoking `out`.

```c
static inline int cbvprintf_tagged_args(cbprintf_cb out, void *ctx, const char *format, va_list ap)
```

varargs-aware `printf-like output through a callback with tagged arguments.

This is essentially `vsprintf()` except the output is generated character-by-character using the provided `out` function. This allows formatting text of unbounded length without incurring the cost of a temporary buffer.

Note that the argument list `ap` are tagged.
Note: This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

Note: The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**

- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`.
- `format` – a standard ISO C format string with characters and conversion specifications.
- `ap` – a reference to the values to be converted.

**Returns**

the number of characters generated, or a negative error value returned from invoking `out`.

static inline int cbpprintf (cbprintf_cb out, void *ctx, void *packaged)

Generate the output for a previously captured format operation.

Note: Memory indicated by `packaged` will be modified in a non-destructive way, meaning that it could still be reused with this function again.

**Parameters**

- `out` – the function used to emit each generated character.
- `ctx` – context provided when invoking `out`.
- `packaged` – the data required to generate the formatted output, as captured by `cbprintf_package()` or `cbvprintf_package()`. The alignment requirement on this data is the same as when it was initially created.

**Returns**

the number of characters printed, or a negative error value returned from invoking `out`.

```c
int fprintfcb(FILE *stream, const char *format, ...)
```

fprintf using Zephyrs cbprintf infrastructure.

return The number of characters printed.

Note: This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

Note: The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

**Parameters**

- `stream` – the stream to which the output should be written.
• format – a standard ISO C format string with characters and conversion specifications.
• ... – arguments corresponding to the conversion specifications found within format.

```c
int vfprintfcb(FILE *stream, const char *format, va_list ap)
vfprintf using Zephyrs cbprintf infrastructure.
```

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

### Parameters
- stream – the stream to which the output should be written.
- format – a standard ISO C format string with characters and conversion specifications.
- ap – a reference to the values to be converted.

### Returns
The number of characters printed.

```c
int printfcb(const char *format, ...)
printf using Zephyrs cbprintf infrastructure.
```

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

```
Parameters
• format – a standard ISO C format string with characters and conversion specifications.
• ... – arguments corresponding to the conversion specifications found within format.

Returns
The number of characters printed.
```

```c
int vprintfcb(const char *format, va_list ap)
vprintf using Zephyrs cbprintf infrastructure.
```

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.
Parameters

- format – a standard ISO C format string with characters and conversion specifications.
- ap – a reference to the values to be converted.

Returns
The number of characters printed.

```c
int snprintfcb(char *str, size_t size, const char *format, ...)
```

snprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

Parameters

- str – where the formatted content should be written
- size – maximum number of characters for the formatted output, including the terminating null byte.
- format – a standard ISO C format string with characters and conversion specifications.
- ... – arguments corresponding to the conversion specifications found within format.

Returns
The number of characters that would have been written to str, excluding the terminating null byte. This is greater than the number actually written if size is too small.

```c
int vsnprintfcb(char *str, size_t size, const char *format, va_list ap)
```

vsnprintf using Zephyrs cbprintf infrastructure.

**Note:** This function is available only when `CONFIG_CBPRINTF_LIBC_SUBSTS` is selected.

**Note:** The functionality of this function is significantly reduced when `CONFIG_CBPRINTF_NANO` is selected.

Parameters

- str – where the formatted content should be written
- size – maximum number of characters for the formatted output, including the terminating null byte.
- format – a standard ISO C format string with characters and conversion specifications.
- ap – a reference to the values to be converted.
Returns

The number of characters that would have been written to `str`, excluding the terminating null byte. This is greater than the number actually written if `size` is too small.

## 4.6 Interprocessor Communication (IPC)

### 4.6.1 IPC service

The IPC service API provides an interface to exchange data between two domains or CPUs.

**Overview**

An IPC service communication channel consists of one instance and one or several endpoints associated with the instance.

An instance is the external representation of a physical communication channel between two domains or CPUs. The actual implementation and internal representation of the instance is peculiar to each backend.

An individual instance is not used to send data between domains/CPUs. To send and receive the data, the user must create (register) an endpoint in the instance. This allows for the connection of the two domains of interest.

It is possible to have zero or multiple endpoints for one single instance, possibly with different priorities, and to use each to exchange data. Endpoint prioritization and multi-instance ability highly depend on the backend used.

The endpoint is an entity the user must use to send and receive data between two domains (connected by the instance). An endpoint is always associated to an instance.

The creation of the instances is left to the backend, usually at init time. The registration of the endpoints is left to the user, usually at run time.

The API does not mandate a way for the backend to create instances but it is strongly recommended to use the devicetree to retrieve the configuration parameters for an instance. Currently, each backend defines its own DT-compatible configuration that is used to configure the interface at boot time.

The following usage scenarios are supported:

- Simple data exchange.
- Data exchange using the no-copy API.

**Simple data exchange**

To send data between domains or CPUs, an endpoint must be registered onto an instance.
See the following example:

```c
#include <zephyr/include/ipc_service.h>

static void bound_cb(void *priv)
{
    /* Endpoint bounded */
}

static void recv_cb(const void *data, size_t len, void *priv)
{
    /* Data received */
}

static struct ipc_ept_cfg ept0_cfg = {
    .name = "ept0",
    .cb = {
        .bound = bound_cb,
        .received = recv_cb,
    },
};

int main(void)
{
    const struct device *inst0;
    struct ipc_ept ept0;
    int ret;

    inst0 = DEVICE_DT_GET(DT_NODELABEL(ipc0));
    ret = ipc_service_open_instance(inst0);
    ret = ipc_service_register_endpoint(inst0, &ept0, &ept0_cfg);

    /* Wait for endpoint bound (bound_cb called) */

    unsigned char message[] = "hello world";
    ret = ipc_service_send(&ept0, &message, sizeof(message));
}
```

### Data exchange using the no-copy API

If the backend supports the no-copy API you can use it to directly write and read to and from shared memory regions.

See the following example:

```c
#include <zephyr/include/ipc_service.h>
#include <stdint.h>
#include <string.h>

static struct ipc_ept ept0;

static void bound_cb(void *priv)
```

(continues on next page)
static void recv_cb_nocopy(const void *data, size_t len, void *priv)
{
    int ret;
    ret = ipc_service_hold_rx_buffer(&ept0, (void *)data);
    /* Process directly or put the buffer somewhere else and release. */
    ret = ipc_service_release_rx_buffer(&ept0, (void *)data);
}

static struct ipc_ept_cfg ept0_cfg = {
    .name = "ept0",
    .cb = {
        .bound = bound_cb,
        .received = recv_cb,
    },
};

int main(void)
{
    const struct device *inst0;
    int ret;
    inst0 = DEVICE_DT_GET(DT_NODELABEL(ipc0));
    ret = ipc_service_open_instance(inst0);
    ret = ipc_service_register_endpoint(inst0, &ept0, &ept0_cfg);
    /* Wait for endpoint bound (bound_cb called) */
    void *data;
    unsigned char message[] = "hello world";
    uint32_t len = sizeof(message);
    ret = ipc_service_get_tx_buffer(&ept0, &data, &len, K_FOREVER);
    memcpy(data, message, len);
    ret = ipc_service_send_nocopy(&ept0, data, sizeof(message));
}

Backends  The requirements needed for implementing backends give flexibility to the IPC service. These allow for the addition of dedicated backends having only a subsets of features for specific use cases.

The backend must support at least the following:

- The init-time creation of instances.
- The run-time registration of an endpoint in an instance.

Additionally, the backend can also support the following:

- The run-time deregistration of an endpoint from the instance.
- The run-time closing of an instance.
- The no-copy API.
Each backend can have its own limitations and features that make the backend unique and dedicated to a specific use case. The IPC service API can be used with multiple backends simultaneously, combining the pros and cons of each backend.

**ICMsg backend**  The inter core messaging backend (ICMsg) is a lighter alternative to the heavier RPMsg static v rings backend. It offers a minimal feature set in a small memory footprint. The ICMsg backend is build on top of Single Producer Single Consumer Packet Buffer.

**Overview**  The ICMsg backend uses shared memory and MBOX devices for exchanging data. Shared memory is used to store the data, MBOX devices are used to signal that the data has been written. The backend supports the registration of a single endpoint on a single instance. If the application requires more than one communication channel, you must define multiple instances, each having its own dedicated endpoint.

**Configuration**  The backend is configured via devicetree. When configuring the backend, do the following:

- Define two memory regions and assign them to tx-region and rx-region of an instance. Ensure that the memory regions used for data exchange are unique (not overlapping any other region) and accessible by both domains (or CPUs).
- Define MBOX devices which are used to send the signal that informs the other domain (or CPU) that data has been written. Ensure that the other domain (or CPU) is able to receive the signal.

See the following configuration example for one of the instances:

```yaml
reserved-memory {
  tx: memory@20070000 {
    reg = <0x20070000 0x0800>;
  };
  rx: memory@20078000 {
    reg = <0x20078000 0x0800>;
  };

  ipc {
    ipc0: ipc0 {
      compatible = "zephyr,ipc-icmsg";
      tx-region = <&tx>;
      rx-region = <&rx>;
      mboxes = <&mbox 0>, <&mbox 1>;
      mbox-names = "tx", "rx";
      status = "okay";
    };
  };
}
```

You must provide a similar configuration for the other side of the communication (domain or CPU) but you must swap the MBOX channels and memory regions (tx-region and rx-region).

**Bonding**  When the endpoint is registered, the following happens on each domain (or CPU) connected through the IPC instance:

1. The domain (or CPU) writes a magic number to its tx-region of the shared memory. It then sends a signal to the other domain or CPU, informing that the data has been written. It then checks, regardless of the signal from the other side being received or not, if the magic number is already in its
If the magic number is not yet in the rx-region, the domain (or CPU) waits to receive the signal from the other side of the communication to finish the bonding process, and informs the application by calling `ipc_service_cb.bound`.

Since the ICMsg backend performs the first read from rx-region, regardless of the signaling mechanism, the shared memory areas must be cleared with zeroes before any side of the communication uses them.

**Samples**
- `ipc_icmsg_sample`

**API Reference**

**IPC service API**

```c
#include <zephyr/device.h>

__BEGIN_DECLS

/* Open an instance. */

int ipc_service_open_instance(const struct device *instance)
{
  return Kinesis::open_ipc_service_instance(instance);
}

/* Close an instance. */

int ipc_service_close_instance(const struct device *instance)
{
  return Kinesis::close_ipc_service_instance(instance);
}

__END_DECLS
```

**Functions**

### `ipc_service_open_instance`

\[ \text{Open an instance.} \]

Function to be used to open an instance before being able to register a new endpoint on it.

**Parameters**
- `instance` - [in] Instance to open.

**Return values**
- `-EINVAL` - when instance configuration is invalid.
- `-EIO` - when no backend is registered.
- `-EAGAIN` - when the instance is already opened (or being opened).
- `0` - on success or when not implemented on the backend (not needed).
- `other` - errno codes depending on the implementation of the backend.

### `ipc_service_close_instance`

\[ \text{Close an instance.} \]

Function to be used to close an instance. All endpoints must be deregistered using `ipc_service_deregister_endpoint` before this is called.

**Parameters**
- `instance` - [in] Instance to close.

**Return values**
- `-EINVAL` - when instance configuration is invalid.
- `-EIO` - when no backend is registered.
- `-EAGAIN` - when the instance is not already opened.
- `-EBUSY` - when an endpoint exists that hasn't been deregistered
- `0` - on success or when not implemented on the backend (not needed).
- `other` - errno codes depending on the implementation of the backend.
int ipc_service_register_endpoint(const struct device *instance, struct ipc_ept *ept, const struct ipc_ept_cfg *cfg)

Register IPC endpoint onto an instance.

Registers IPC endpoint onto an instance to enable communication with a remote device.
The same function registers endpoints for both host and remote devices.

**Note:** Keep the variable pointed by `cfg` alive when endpoint is in use.

**Parameters**
- `instance` – [in] Instance to register the endpoint onto.

**Return values**
- `-EIO` – when no backend is registered.
- `-EINVAL` – when instance, endpoint or configuration is invalid.
- `-EBUSY` – when the instance is busy.
- `0` – on success.
- `other` – errno codes depending on the implementation of the backend.

int ipc_service_deregister_endpoint(struct ipc_ept *ept)

Deregister an IPC endpoint from its instance.

Deregisters an IPC endpoint from its instance.
The same function deregisters endpoints for both host and remote devices.

**Parameters**

**Return values**
- `-EIO` – when no backend is registered.
- `-EINVAL` – when instance or endpoint is invalid.
- `-ENOENT` – when the endpoint is not registered with the instance.
- `-EBUSY` – when the instance is busy.
- `0` – on success.
- `other` – errno codes depending on the implementation of the backend.

int ipc_service_send(struct ipc_ept *ept, const void *data, size_t len)

Send data using given IPC endpoint.

**Parameters**
- `data` – [in] Pointer to the buffer to send.
- `len` – [in] Number of bytes to send.

**Return values**
- `-EIO` – when no backend is registered or send hook is missing from backend.
- `-EINVAL` – when instance or endpoint is invalid.
- ENOENT – when the endpoint is not registered with the instance.
- EBADMSG – when the data is invalid (i.e. invalid data format, invalid length, ...)
- EBUSY – when the instance is busy.
- ENOMEM – when no memory / buffers are available.

bytes – number of bytes sent.
other – errno codes depending on the implementation of the backend.

int ipc_service_get_tx_buffer_size(struct ipc_ept *ept)

Get the TX buffer size.

Get the maximal size of a buffer which can be obtained by \texttt{ipc_service_get_tx_buffer}

\textbf{Parameters}

\begin{itemize}
  \item \texttt{ept} – [in] Registered endpoint by \texttt{ipc_service_register_endpoint}.
\end{itemize}

\textbf{Return values}

\begin{itemize}
  \item -EIO – when no backend is registered or send hook is missing from backend.
  \item -EINVAL – when instance or endpoint is invalid.
  \item -ENOENT – when the endpoint is not registered with the instance.
  \item -ENOTSUP – when the operation is not supported by backend.
  \item \texttt{size} – TX buffer size on success.
  \item other – errno codes depending on the implementation of the backend.
\end{itemize}

int ipc_service_get_tx_buffer(struct ipc_ept *ept, void **data, uint32_t *size, k_timeout_t wait)

Get an empty TX buffer to be sent using \texttt{ipc_service_send_nocopy}.

This function can be called to get an empty TX buffer so that the application can directly put its data into the sending buffer without copy from an application buffer.

It is the application responsibility to correctly fill the allocated TX buffer with data and passing correct parameters to \texttt{ipc_service_send_nocopy} function to perform data no-copy-send mechanism.

The size parameter can be used to request a buffer with a certain size:

- if the size can be accommodated the function returns no errors and the buffer is allocated
- if the requested size is too big, the function returns -ENOMEM and the the buffer is not allocated.
- if the requested size is ‘0’ the buffer is allocated with the maximum allowed size.

In all the cases on return the size parameter contains the maximum size for the returned buffer.

When the function returns no errors, the buffer is intended as allocated and it is released under two conditions: (1) when sending the buffer using \texttt{ipc_service_send_nocopy} (and in this case the buffer is automatically released by the backend), (2) when using \texttt{ipc_service_drop_tx_buffer} on a buffer not sent.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{ept} – [in] Registered endpoint by \texttt{ipc_service_register_endpoint}.
  \item \texttt{data} – [out] Pointer to the empty TX buffer.
  \item \texttt{size} – [inout] Pointer to store the requested TX buffer size. If the function returns -ENOMEM, this parameter returns the maximum allowed size.
\end{itemize}
• `wait` – [in] Timeout waiting for an available TX buffer.

**Return values**

• `-EIO` – when no backend is registered or send hook is missing from backend.
• `-EINVAL` – when instance or endpoint is invalid.
• `-ENOTENT` – when the endpoint is not registered with the instance.
• `-ENOTSUP` – when the operation or the timeout is not supported by backend.
• `-ENOBUFS` – when there are no TX buffers available.
• `-EALREADY` – when a buffer was already claimed and not yet released.
• `-ENOMEM` – when the requested size is too big (and the size parameter contains the maximum allowed size).
• `0` – on success.
• `other` – errno codes depending on the implementation of the backend.

```c
int ipc_service_drop_tx_buffer(struct ipc_ept *ept, const void *data)
```

Drop and release a TX buffer. It is possible to drop only TX buffers obtained by using `ipc_service_get_tx_buffer`.

**Parameters**

• `ept` – [in] Registered endpoint by `ipc_service_register_endpoint`.
• `data` – [in] Pointer to the TX buffer.

**Return values**

• `-EIO` – when no backend is registered or send hook is missing from backend.
• `-EINVAL` – when instance or endpoint is invalid.
• `-ENOTENT` – when the endpoint is not registered with the instance.
• `-ENOTSUP` – when this is not supported by backend.
• `-EALREADY` – when the buffer was already dropped.
• `-ENXIO` – when the buffer was not obtained using `ipc_service_get_tx_buffer`
• `0` – on success.
• `other` – errno codes depending on the implementation of the backend.

```c
int ipc_service_send_nocopy(struct ipc_ept *ept, const void *data, size_t len)
```

Send data in a TX buffer reserved by `ipc_service_get_tx_buffer` using the given IPC endpoint. This is equivalent to `ipc_service_send` but in this case the TX buffer has been obtained by using `ipc_service_get_tx_buffer`.

The application has to take the responsibility for getting the TX buffer using `ipc_service_get_tx_buffer` and filling the TX buffer with the data.

After the `ipc_service_send_nocopy` function is issued the TX buffer is no more owned by the sending task and must not be touched anymore unless the function fails and returns an error.

If this function returns an error, `ipc_service_drop_tx_buffer` can be used to drop the TX buffer.

**Parameters**

• `ept` – [in] Registered endpoint by `ipc_service_register_endpoint`.
• `data` – [in] Pointer to the buffer to send obtained by `ipc_service_get_tx_buffer`.
• `len` – [in] Number of bytes to send.
Return values

- **-EIO** – when no backend is registered or send hook is missing from backend.
- **-EINVAL** – when instance or endpoint is invalid.
- **-ENOENT** – when the endpoint is not registered with the instance.
- **-EBADMSG** – when the data is invalid (i.e. invalid data format, invalid length, ...)
- **-EBUSY** – when the instance is busy.
- **bytes** – number of bytes sent.
- **other** – errno codes depending on the implementation of the backend.

```c
int ipc_service_hold_rx_buffer(struct ipc_ept *ept, void *data)
```

Holds the RX buffer for usage outside the receive callback.

Calling this function prevents the receive buffer from being released back to the pool of shmem buffers. This function can be called in the receive callback when the user does not want to copy the message out in the callback itself.

After the message is processed, the application must release the buffer using the `ipc_service_release_rx_buffer` function.

Parameters

- **ept** – [in] Registered endpoint by `ipc_service_register_endpoint`.
- **data** – [in] Pointer to the RX buffer to release.

Return values

- **-EIO** – when no backend is registered or release hook is missing from backend.
- **-EINVAL** – when instance or endpoint is invalid.
- **-ENOENT** – when the endpoint is not registered with the instance.
- **-EALREADY** – when the buffer data has been hold already.
- **-ENOTSUP** – when this is not supported by backend.
- **0** – on success.
- **other** – errno codes depending on the implementation of the backend.

```c
int ipc_service_release_rx_buffer(struct ipc_ept *ept, void *data)
```

Release the RX buffer for future reuse.

When supported by the backend, this function can be called after the received message has been processed and the buffer can be marked as reusable again.

It is possible to release only RX buffers on which `ipc_service_hold_rx_buffer` was previously used.

Parameters

- **ept** – [in] Registered endpoint by `ipc_service_register_endpoint`.
- **data** – [in] Pointer to the RX buffer to release.

Return values

- **-EIO** – when no backend is registered or release hook is missing from backend.
- **-EINVAL** – when instance or endpoint is invalid.
- **-ENOENT** – when the endpoint is not registered with the instance.
- **-EALREADY** – when the buffer data has been already released.
- `ENOTSUP` – when this is not supported by backend.
- `ENXIO` – when the buffer was not hold before using `ipc_service_hold_rx_buffer`
- 0 – on success.
- `other` – errno codes depending on the implementation of the backend.

```c
struct ipc_service_cb
#include <ipc_service.h>  // Event callback structure.
```

It is registered during endpoint registration. This structure is part of the endpoint configuration.

**Public Members**

```c
void (*bound)(void *priv)
    Bind was successful.
    This callback is called when the endpoint binding is successful.
    **Param priv**
    [in] Private user data.
```

```c
void (*received)(const void *data, size_t len, void *priv)
    New packet arrived.
    This callback is called when new data is received.
    **Note:** When `ipc_service_hold_rx_buffer` is not used, the data buffer is to be considered released and available again only when this callback returns.
    **Param data**
    [in] Pointer to data buffer.
    **Param len**
    [in] Length of data.
    **Param priv**
    [in] Private user data.
```

```c
void (*error)(const char *message, void *priv)
    An error occurred.
    **Param message**
    **Param priv**
    [in] Private user data.
```

```c
struct ipc_ept
#include <ipc_service.h>  // Endpoint instance.
```

Token is not important for user of the API. It is implemented in a specific backend.

**Public Members**

```c
const struct device *instance
    Instance this endpoint belongs to.
```

4.6. Interprocessor Communication (IPC)
void *token
    Backend-specific token used to identify an endpoint in an instance.

struct ipc_ept_cfg
    #include <ipc_service.h> Endpoint configuration structure.

Public Members

const char *name
    Name of the endpoint.

int prio
    Endpoint priority. If the backend supports priorities.

struct ipc_service_cb cb
    Event callback structure.

void *priv
    Private user data.

IPC service backend API

group ipc_service_backend
    IPC service backend.

struct ipc_service_backend
    #include <ipc_service_backend.h> IPC backend configuration structure.
    This structure is used for configuration backend during registration.

Public Members

int (*open_instance)(const struct device *instance)
    Pointer to the function that will be used to open an instance.

    Param instance
        [in] Instance pointer.

    Retval -EALREADY
        when the instance is already opened.

    Retval 0
        on success

    Retval other
        errno codes depending on the implementation of the backend.

int (*close_instance)(const struct device *instance)
    Pointer to the function that will be used to close an instance.

    Param instance
        [in] Instance pointer.

    Retval -EALREADY
        when the instance is not already initiated.
Retval 0
on success
Retval other
errno codes depending on the implementation of the backend.

int (*send)(const struct device *instance, void *token, const void *data, size_t len)
Pointer to the function that will be used to send data to the endpoint.

Param instance
[in] Instance pointer.

Param token

Param data
[in] Pointer to the buffer to send.

Param len
[in] Number of bytes to send.
Retval -EINVAL
when instance is invalid.
Retval -ENOENT
when the endpoint is not registered with the instance.
Retval -EBADMSG
when the message is invalid.
Retval -EBUSY
when the instance is busy or not ready.
Retval -ENOMEM
when no memory / buffers are available.

Retval bytes
number of bytes sent.
Retval other
errno codes depending on the implementation of the backend.

int (*register_endpoint)(const struct device *instance, void **token, const struct ipc_ept_cfg *cfg)
Pointer to the function that will be used to register endpoints.

Param instance
[in] Instance to register the endpoint onto.

Param token
[out] Backend-specific token.

Param cfg
[in] Endpoint configuration.
Retval -EINVAL
when the endpoint configuration or instance is invalid.
Retval -EBUSY
when the instance is busy or not ready.
Retval 0
on success
Retval other
errno codes depending on the implementation of the backend.

int (*deregister_endpoint)(const struct device *instance, void *token)
Pointer to the function that will be used to deregister endpoints.

Param instance
[in] Instance from which to deregister the endpoint.

Param token
Retval -EINVAL
when the endpoint configuration or instance is invalid.
Retval -ENOENT
  when the endpoint is not registered with the instance.
Retval -EBUSY
  when the instance is busy or not ready.
Retval 0
  on success
Retval other
  errno codes depending on the implementation of the backend.

int (*get_tx_buffer_size)(const struct device *instance, void *token)

  Pointer to the function that will return the TX buffer size.

  Param instance
    [in] Instance pointer.

  Param token

  Retval -EINVAL
    when instance is invalid.

  Retval -ENOENT
    when the endpoint is not registered with the instance.

  Retval -ENOTSUP
    when the operation is not supported.

  Retval size
    TX buffer size on success.

  Retval other
    errno codes depending on the implementation of the backend.

int (*get_tx_buffer)(const struct device *instance, void *token, void **data, uint32_t *len, k_timeout_t *wait)

  Pointer to the function that will return an empty TX buffer.

  Param instance
    [in] Instance pointer.

  Param token

  Param data
    [out] Pointer to the empty TX buffer.

  Param len
    [inout] Pointer to store the TX buffer size.

  Param wait
    [in] Timeout waiting for an available TX buffer.

  Retval -EINVAL
    when instance is invalid.

  Retval -ENOENT
    when the endpoint is not registered with the instance.

  Retval -ENOTSUP
    when the operation or the timeout is not supported.

  Retval -ENOBUFFS
    when there are no TX buffers available.

  Retval -EALREADY
    when a buffer was already claimed and not yet released.

  Retval -ENOMEM
    when the requested size is too big (and the size parameter contains the maximum allowed size).

  Retval 0
    on success

  Retval other
    errno codes depending on the implementation of the backend.

int (*drop_tx_buffer)(const struct device *instance, void *token, const void *data)
Pointer to the function that will drop a TX buffer.

**Param instance**
[in] Instance pointer.

**Param token**

**Param data**
[in] Pointer to the TX buffer.

**Retval**
- EINVAL when instance is invalid.
- ENOENT when the endpoint is not registered with the instance.
- ENOTSUP when this function is not supported.
- EALREADY when the buffer was already dropped.
- 0 on success
- other errno codes depending on the implementation of the backend.

```c
int (*send_nocopy)(const struct device *instance, void *token, const void *data, size_t len)
```

Pointer to the function that will be used to send data to the endpoint when the TX buffer has been obtained using `ipc_service_get_tx_buffer`.

**Param instance**
[in] Instance pointer.

**Param token**

**Param data**
[in] Pointer to the buffer to send.

**Param len**
[in] Number of bytes to send.

**Retval**
- EINVAL when instance is invalid.
- ENOENT when the endpoint is not registered with the instance.
- EBADMSG when the data is invalid (i.e. invalid data format, invalid length, ...)
- EBUSY when the instance is busy or not ready.
- bytes number of bytes sent.
- other errno codes depending on the implementation of the backend.

```c
int (*hold_rx_buffer)(const struct device *instance, void *token, void *data)
```

Pointer to the function that will hold the RX buffer.

**Param instance**
[in] Instance pointer.

**Param token**

**Param data**
[in] Pointer to the RX buffer to hold.

**Retval**
- EINVAL when instance is invalid.
- ENOENT when the endpoint is not registered with the instance.
Retval -EALREADY
when the buffer data has been already hold.
Retval -ENOTSUP
when this function is not supported.
Retval 0
on success
Retval other
errno codes depending on the implementation of the backend.

int (*release_rx_buffer)(const struct device *instance, void *token, void *data)

Pointer to the function that will release the RX buffer.

Param instance
[in] Instance pointer.

Param token

Param data
[in] Pointer to the RX buffer to release.

Retval -EINVAL
when instance is invalid.

Retval -ENOENT
when the endpoint is not registered with the instance.

Retval -EALREADY
when the buffer data has been already released.

Retval -ENOTSUP
when this function is not supported.

Retval 0
on success
Retval other
errno codes depending on the implementation of the backend.

4.7 Logging
The logging API provides a common interface to process messages issued by developers. Messages are passed through a frontend and are then processed by active backends. Custom frontend and backends can be used if needed.

Summary of the logging features:

- Deferred logging reduces the time needed to log a message by shifting time consuming operations to a known context instead of processing and sending the log message when called.
- Multiple backends supported (up to 9 backends).
- Custom frontend support. It can work together with backends.
- Compile time filtering on module level.
- Run time filtering independent for each backend.
- Additional run time filtering on module instance level.
- Timestamping with user provided function. Timestamp can have 32 or 64 bits.
- Dedicated API for dumping data.
- Dedicated API for handling transient strings.
- Panic support - in panic mode logging switches to blocking, synchronous processing.
- Printk support - printk message can be redirected to the logging.
- Design ready for multi-domain/multi-processor system.
- Support for logging floating point variables and long long arguments.
- Built-in copying of transient strings used as arguments.
- Support for multi-domain logging.

Logging API is highly configurable at compile time as well as at run time. Using Kconfig options (see [Global Kconfig Options](#)) logs can be gradually removed from compilation to reduce image size and execution time when logs are not needed. During compilation logs can be filtered out on module basis and severity level.

Logs can also be compiled in but filtered on run time using dedicate API. Run time filtering is independent for each backend and each source of log messages. Source of log messages can be a module or specific instance of the module.

There are four severity levels available in the system: error, warning, info and debug. For each severity level the logging API ([include/zephyr/logging/log.h](#)) has set of dedicated macros. Logger API also has macros for logging data.

For each level following set of macros are available:

- **LOG_X** for standard printf-like messages, e.g. `LOG_ERR`.
- **LOG_HEXDUMP_X** for dumping data, e.g. `LOG_HEXDUMP_WRN`.

---

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• LOG_INST_X for standard printf-like message associated with the particular instance, e.g. LOG_INST_INF.

• LOG_INST_HEXDUMP_X for dumping data associated with the particular instance, e.g. LOG_HEXDUMP_INST_dbg

There are two configuration categories: configurations per module and global configuration. When logging is enabled globally, it works for modules. However, modules can disable logging locally. Every module can specify its own logging level. The module must define the LOG_LEVEL macro before using the API. Unless a global override is set, the module logging level will be honored. The global override can only increase the logging level. It cannot be used to lower module logging levels that were previously set higher. It is also possible to globally limit logs by providing maximal severity level present in the system, where maximal means lowest severity (e.g. if maximal level in the system is set to info, it means that errors, warnings and info levels are present but debug messages are excluded).

Each module which is using the logging must specify its unique name and register itself to the logging. If module consists of more than one file, registration is performed in one file but each file must define a module name.

Logger's default frontend is designed to be thread safe and minimizes time needed to log the message. Time consuming operations like string formatting or access to the transport are not performed by default when logging API is called. When logging API is called a message is created and added to the list. Dedicated, configurable buffer for pool of log messages is used. There are 2 types of messages: standard and hexdump. Each message contain source ID (module or instance ID and domain ID which might be used for multiprocessor systems), timestamp and severity level. Standard message contains pointer to the string and arguments. Hexdump message contains copied data and string.

4.7.1 Global Kconfig Options

These options can be found in the following path subsys/logging/Kconfig.

CONFIG_LOG: Global switch, turns on/off the logging.

Mode of operations:

CONFIG_LOG_MODE_DEFERRED: Deferred mode.

CONFIG_LOG_MODE_IMMEDIATE: Immediate (synchronous) mode.

CONFIG_LOG_MODE_MINIMAL: Minimal footprint mode.

Filtering options:

CONFIG_LOG_RUNTIME_FILTERING: Enables runtime reconfiguration of the filtering.

CONFIG_LOG_DEFAULT_LEVEL: Default level, sets the logging level used by modules that are not setting their own logging level.

CONFIG_LOG_OVERRIDE_LEVEL: It overrides module logging level when it is not set of set lower than the override value.

CONFIG_LOG_MAX_LEVEL: Maximal (lowest severity) level which is compiled in.

Processing options:

CONFIG_LOG_MODE_OVERFLOW: When new message cannot be allocated, oldest one are discarded.

CONFIG_LOG_BLOCK_IN_THREAD: If enabled and new log message cannot be allocated thread context will block for up to CONFIG_LOG_BLOCK_IN_THREAD_TIMEOUT_MS or until log message is allocated.

CONFIG_LOG_PRINTK: Redirect printk calls to the logging.

CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD: When number of buffered log messages reaches the threshold dedicated thread (see log_thread_set()) is waken up. If CONFIG_LOG_PROCESS_THREAD is enabled then this threshold is used by the internal thread.

CONFIG_LOG_PROCESS_THREAD: When enabled, logging thread is created which handles log processing.
CONFIG_LOG_PROCESS_THREAD_STARTUP_DELAY_MS: Delay in milliseconds after which logging thread is started.

CONFIG_LOG_BUFFER_SIZE: Number of bytes dedicated for the circular packet buffer.

CONFIG_LOG_FRONTEND: Direct logs to a custom frontend.

CONFIG_LOG_FRONTEND_ONLY: No backends are used when messages go to frontend.

CONFIG_LOG_TIMESTAMP_64BIT: 64 bit timestamp.

Formatting options:

CONFIG_LOG_FUNC_NAME_PREFIX_ERR: Prepend standard ERROR log messages with function name. Hexdump messages are not prepended.

CONFIG_LOG_FUNC_NAME_PREFIX_WRN: Prepend standard WARNING log messages with function name. Hexdump messages are not prepended.

CONFIG_LOG_FUNC_NAME_PREFIX_INF: Prepend standard INFO log messages with function name. Hexdump messages are not prepended.

CONFIG_LOG_FUNC_NAME_PREFIX_DBG: Prepend standard DEBUG log messages with function name. Hexdump messages are not prepended.

CONFIG_LOG_BACKEND_SHOW_COLOR: Enables coloring of errors (red) and warnings (yellow).

CONFIG_LOG_BACKEND_FORMAT_TIMESTAMP: If enabled timestamp is formatted to \texttt{hh:mm:ss:mmm,uuu}. Otherwise is printed in raw format.

Backend options:

CONFIG_LOG_BACKEND_UART: Enabled built-in UART backend.

### 4.7.2 Usage

Logging in a module

In order to use logging in the module, a unique name of a module must be specified and module must be registered using \texttt{LOG_MODULE_REGISTER}. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (\texttt{CONFIG_LOG_DEFAULT_LEVEL}) is used if custom log level is not provided.

\begin{verbatim}
#include <zephyr/logging/log.h>
LOG_MODULE_REGISTER(foo, CONFIG_FOO_LOG_LEVEL);
\end{verbatim}

If the module consists of multiple files, then \texttt{LOG_MODULE_REGISTER()} should appear in exactly one of them. Each other file should use \texttt{LOG_MODULE_DECLARE} to declare its membership in the module. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (\texttt{CONFIG_LOG_DEFAULT_LEVEL}) is used if custom log level is not provided.

\begin{verbatim}
#include <zephyr/logging/log.h>
/* In all files comprising the module but one */
LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL);
\end{verbatim}

In order to use logging API in a function implemented in a header file \texttt{LOG_MODULE_DECLARE} macro must be used in the function body before logging API is called. Optionally, a compile time log level for the module can be specified as the second parameter. Default log level (\texttt{CONFIG_LOG_DEFAULT_LEVEL}) is used if custom log level is not provided.

\begin{verbatim}
#include <zephyr/logging/log.h>

static inline void foo(void)
\end{verbatim}

(continues on next page)
{  
    LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL);
    LOG_INF("foo");
}

Dedicated Kconfig template (subsys/logging/Kconfig.template.log_config) can be used to create local log level configuration.

Example below presents usage of the template. As a result CONFIG_FOO_LOG_LEVEL will be generated:

module = FOO
module-str = foo
source "subsys/logging/Kconfig.template.log_config"

Logging in a module instance

In case of modules which are multi-instance and instances are widely used across the system enabling logs will lead to flooding. Logger provide the tools which can be used to provide filtering on instance level rather than module level. In that case logging can be enabled for particular instance.

In order to use instance level filtering following steps must be performed:

• a pointer to specific logging structure is declared in instance structure. LOG_INSTANCE_PTR_DECLARE is used for that.

    #include <zephyr/logging/log_instance.h>

    struct foo_object {
        LOG_INSTANCE_PTR_DECLARE(log);
        uint32_t id;
    }

• module must provide macro for instantiation. In that macro, logging instance is registered and log instance pointer is initialized in the object structure.

    #define FOO_OBJECT_DEFINE(_name)   
        LOG_INSTANCE_REGISTER(foo, _name, CONFIG_FOO_LOG_LEVEL) \ 
        struct foo_object _name = { \ 
            LOG_INSTANCE_PTR_INIT(log, foo, _name) \ 
        }

Note that when logging is disabled logging instance and pointer to that instance are not created.

In order to use the instance logging API in a source file, a compile-time log level must be set using LOG_LEVEL_SET.

LOG_LEVEL_SET(CONFIG_FOO_LOG_LEVEL);

void foo_init(foo_object *f) {
    LOG_INST_INF(f->log, "Initialized.");
}

In order to use the instance logging API in a header file, a compile-time log level must be set using LOG_LEVEL_SET.

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Controlling the logging

By default, logging processing in deferred mode is handled internally by the dedicated task which starts automatically. However, it might not be available if multithreading is disabled. It can also be disabled by unsetting `CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD`. In that case, logging can be controlled using API defined in `include/zephyr/logging/log_ctrl.h`. Logging must be initialized before it can be used. Optionally, user can provide function which returns timestamp value. If not provided, `k_cycle_get` or `k_cycle_get_32` is used for timestamping. `log_process()` function is used to trigger processing of one log message (if pending). Function returns true if there is more messages pending. However, it is recommended to use macro wrappers (`LOG_INIT` and `LOG_PROCESS`) which handles case when logging is disabled.

Following snippet shows how logging can be processed in simple forever loop.

```c
#include <zephyr/log_ctrl.h>

void main(void)
{
    LOG_INIT();
    /* If multithreading is enabled provide thread id to the logging. */
    log_thread_set(k_current_get());

    while (true) {
        if (LOG_PROCESS() == false) {
            /* sleep */
        }
    }
}
```

If logs are processed from a thread (user or internal) then it is possible to enable a feature which will wake up processing thread when certain amount of log messages are buffered (see `CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD`).

### 4.7.3 Logging panic

In case of error condition system usually can no longer rely on scheduler or interrupts. In that situation deferred log message processing is not an option. Logger controlling API provides a function for entering into panic mode (`log_panic()`) which should be called in such situation.

When `log_panic()` is called, `_panic_` notification is sent to all active backends. Once all backends are notified, all buffered messages are flushed. Since that moment all logs are processed in a blocking way.

### 4.7.4 Printk

Typically, logging and `printk()` is using the same output for which they compete. This can lead to issues if the output does not support preemption but also it may result in the corrupted output because logging data is interleaved with printk data. However, it is possible to redirect printk messages to the logging subsystem by enabling `CONFIG_LOG_PRINTK`. In that case, printk entries are treated as log messages with
level 0 (they cannot be disabled). When enabled, logging manages the output so there is no interleaving. However, in the deferred mode it changes the behavior of the printk because output is delayed until logging thread processes the data. CONFIG_LOG_PRINTK is by default enabled.

4.7.5 Architecture

Logging consists of 3 main parts:

- Frontend
- Core
- Backends

Log message is generated by a source of logging which can be a module or instance of a module.

Default Frontend

Default frontend is engaged when logging API is called in a source of logging (e.g. `LOG_INF`) and is responsible for filtering a message (compile and run time), allocating buffer for the message, creating the message and committing that message. Since logging API can be called in an interrupt, frontend is optimized to log the message as fast as possible.

Log message: Log message contains message descriptor (source, domain and level), timestamp, formatted string details (see Cbprintf Packaging) and optional data. Log messages are stored in a continuous block of memory. Memory is allocated from a circular packet buffer (Multi Producer Single Consumer Packet Buffer). It has few consequences:

- Each message is self-contained, continuous block of memory thus it is suited for copying the message (e.g. for offline processing).
- Messages must be sequentially freed. Backend processing is synchronous. Backend can make a copy for deferred processing.

Log message has following format:

<table>
<thead>
<tr>
<th>Message Header</th>
<th>2 bits: MPSC packet buffer header</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>1 bit: Trace/Log message flag</td>
</tr>
<tr>
<td></td>
<td>3 bits: Domain ID</td>
</tr>
<tr>
<td></td>
<td>3 bits: Level</td>
</tr>
<tr>
<td></td>
<td>10 bits: Cbprintf Package Length</td>
</tr>
<tr>
<td></td>
<td>12 bits: Data length</td>
</tr>
<tr>
<td></td>
<td>1 bit: Reserved</td>
</tr>
<tr>
<td></td>
<td>pointer: Pointer to the source descriptor</td>
</tr>
<tr>
<td></td>
<td>32 or 64 bits: Timestamp</td>
</tr>
<tr>
<td></td>
<td>Optional padding</td>
</tr>
</tbody>
</table>

Cbprintf package (optional)  
Header  
Arguments  
Appended strings  
Hexdump data (optional)  
Alignment padding (optional)

1 Depending on the platform and the timestamp size fields may be swapped.  
2 It may be required for cbprintf package alignment
Log message allocation It may happen that frontend cannot allocate a message. It happens if system is generating more log messages than it can process in certain time frame. There are two strategies to handle that case:

- No overflow - new log is dropped if space for a message cannot be allocated.
- Overflow - oldest pending messages are freed, until new message can be allocated. Enabled by CONFIG_LOG_MODE_OVERFLOW. Note that it degrades performance thus it is recommended to adjust buffer size and amount of enabled logs to limit dropping.

Run-time filtering If run-time filtering is enabled, then for each source of logging a filter structure in RAM is declared. Such filter is using 32 bits divided into ten 3 bit slots. Except slot 0, each slot stores current filter for one backend in the system. Slot 0 (bits 0-2) is used to aggregate maximal filter setting for given source of logging. Aggregate slot determines if log message is created for given entry since it indicates if there is at least one backend expecting that log entry. Backend slots are examined when message is processed by the core to determine if message is accepted by the given backend. Contrary to compile time filtering, binary footprint is increased because logs are compiled in.

In the example below backend 1 is set to receive errors (slot 1) and backend 2 up to info level (slot 2). Slots 3-9 are not used. Aggregated filter (slot 0) is set to info level and up to this level message from that particular source will be buffered.

```
<table>
<thead>
<tr>
<th>slot 0</th>
<th>slot 1</th>
<th>slot 2</th>
<th>slot 3</th>
<th>...</th>
<th>slot 9</th>
</tr>
</thead>
<tbody>
<tr>
<td>INF</td>
<td>ERR</td>
<td>INF</td>
<td>OFF</td>
<td>...</td>
<td>OFF</td>
</tr>
</tbody>
</table>
```

Custom Frontend

Custom frontend is enabled using CONFIG_LOG_FRONTEND. Logs are directed to functions declared in include/zephyr/logging/log_frontend.h. If option CONFIG_LOG_FRONTEND_ONLY is enabled then log message is not created and no backend is handled. Otherwise, custom frontend can coexist with backends.

Logging strings

String arguments are handled by Cbprintf Packaging. See Limitations and recommendations for limitations and recommendations.

Multi-domain support

More complex systems can consist of multiple domains where each domain is an independent binary. Examples of domains are a core in a multicore SoC or one of the binaries (Secure or Nonsecure) on an ARM TrustZone core.

Tracing and debugging on a multi-domain system is more complex and requires an efficient logging system. Two approaches can be used to structure this logging system:

- Log inside each domain independently. This option is not always possible as it requires that each domain has an available backend (for example, UART). This approach can also be troublesome to use and not scalable, as logs are presented on independent outputs.
- Use a multi-domain logging system where log messages from each domain end up in one root domain, where they are processed exactly as in a single domain case. In this approach, log messages are passed between domains using a connection between domains created from the backend on one side and linked to the other.

The Log link is an interface introduced in this multi-domain approach. The Log link is responsible for receiving any log message from another domain, creating a copy, and putting that local log message copy (including remote data) into the message queue. This specific log link implementation
matches the complementary backend implementation to allow log messages exchange and logger control like configuring filtering, getting log source names, and so on.

There are three types of domains in a multi-domain system:

- The end domain has the logging core implementation and a cross-domain backend. It can also have other backends in parallel.
- The relay domain has one or more links to other domains but does not have backends that output logs to the user. It has a cross-domain backend either to another relay or to the root domain.
- The root domain has one or multiple links and a backend that outputs logs to the user.

See the following image for an example of a multi-domain setup:

![Fig. 4.1: Multi-domain example](image)

In this architecture, a link can handle multiple domains. For example, let's consider an SoC with two ARM Cortex-M33 cores with TrustZone: cores A and B (see Fig. 4.1). There are four domains in the system, as each core has both a Secure and a Nonsecure domain. If core A nonsecure (A_NS) is the root domain, it has two links: one to core A secure (A_NS-A_S) and one to core B nonsecure (A_NS-B_NS). B_NS domain has one link, to core B secure B_NS-B_S), and a backend to A_NS.

Since in all instances there is a standard logging subsystem, it is always possible to have multiple backends and simultaneously output messages to them. An example of this is shown on Fig. 4.1 as a dotted UART backend on the B_NS domain.

**Domain ID** The source of each log message can be identified by the following fields in the header: source_id and domain_id.

The value assigned to the domain_id is relative. Whenever a domain creates a log message, it sets its domain_id to 0. When a message crosses the domain, domain_id changes as it is increased by the link offset. The link offset is assigned during the initialization, where the logger core is iterating over all the registered links and assigned offsets.

The first link has the offset set to 1. The following offset equals the previous link offset plus the number of domains in the previous link.

The following example is shown on Fig. 4.2, where the assigned domain_ids are shown for each domain:

Let's consider a log message created on the B_S domain:
1. Initially, it has its `domain_id` set to 0.
2. When the `B_NS-B_S` link receives the message, it increases the `domain_id` to 1 by adding the `B_NS-B_S` offset.
3. The message is passed to `A_NS`.
4. When the `A_NS-B_NS` link receives the message, it adds the offset (2) to the `domain_id`. The message ends up with the `domain_id` set to 3, which uniquely identifies the message originator.

**Cross-domain log message**  In most cases, the address space of each domain is unique, and one domain cannot access directly the data in another domain. For this reason, the backend can partially process the message before it is passed to another domain. Partial processing can include converting a string package to a **fully self-contained** version (copying read-only strings to the package body).

Each domain can have a different timestamp source in terms of frequency and offset. Logging does not perform any timestamp conversion.

**Runtime filtering**  In the single-domain case, each log source has a dedicated variable with runtime filtering for each backend in the system. In the multi-domain case, the originator of the log message is not aware of the number of backends in the root domain.

As such, to filter logs in multiple domains, each source requires a runtime filtering setting in each domain on the way to the root domain. As the number of sources in other domains is not known during the compilation, the runtime filtering of remote sources must use dynamically allocated memory (one word per source). When a backend in the root domain changes the filtering of the module from a remote domain, the local filter is updated. After the update, the aggregated filter (the maximum from all the local backends) is checked and, if changed, the remote domain is informed about this change. With this approach, the runtime filtering works identically in both multi-domain and single-domain scenarios.

**Message ordering**  Logging does not provide any mechanism for synchronizing timestamps across multiple domains:

- If domains have different timestamp sources, messages will be processed in the order of arrival to the buffer in the root domain.
• If domains have the same timestamp source or if there is an out-of-bound mechanism that recalculates timestamps, there are 2 options:
  – Messages are processed as they arrive in the buffer in the root domain. Messages are unordered but they can be sorted by the host as the timestamp indicates the time of the message generation.
  – Links have dedicated buffers. During processing, the head of each buffer is checked and the oldest message is processed first.

With this approach, it is possible to maintain the order of the messages at the cost of a sub-optimal memory utilization (since the buffer is not shared) and increased processing latency (see `CONFIG_LOG_PROCESSING_LATENCY_US`).

Logging backends

Logging backends are registered using `LOG_BACKEND_DEFINE`. The macro creates an instance in the dedicated memory section. Backends can be dynamically enabled (`log_backend_enable()`) and disabled. When `Run-time filtering` is enabled, `log_filter_set()` can be used to dynamically change filtering of a module logs for given backend. Module is identified by source ID and domain ID. Source ID can be retrieved if source name is known by iterating through all registered sources.

Logging supports up to 9 concurrent backends. Log message is passed to the each backend in processing phase. Additionally, backend is notified when logging enter panic mode with `log_backend_panic()`. On that call backend should switch to synchronous, interrupt-less operation or shut down itself if that is not supported. Occasionally, logging may inform backend about number of dropped messages with `log_backend_dropped()`. Message processing API is version specific.

`log_backend_msg2_process()` is used for processing message. It is common for standard and hexdump messages because log message hold string with arguments and data. It is also common for deferred and immediate logging.

Message formatting

Logging provides set of function that can be used by the backend to format a message. Helper functions are available in `include/zephyr/logging/log_output.h`.

Example message formatted using `log_output_msg2_process()`.

```
[00:00:00.000,274] <info> sample_instance.inst1: logging message
```

Dictionary-based Logging

Dictionary-based logging, instead of human readable texts, outputs the log messages in binary format. This binary format encodes arguments to formatted strings in their native storage formats which can be more compact than their text equivalents. For statically defined strings (including the format strings and any string arguments), references to the ELF file are encoded instead of the whole strings. A dictionary created at build time contains the mappings between these references and the actual strings. This allows the offline parser to obtain the strings from the dictionary to parse the log messages. This binary format allows a more compact representation of log messages in certain scenarios. However, this requires the use of an offline parser and is not as intuitive to use as text-based log messages.

Note that `long double` is not supported by Python's `struct` module. Therefore, log messages with `long double` will not display the correct values.

Configuration

Here are kconfig options related to dictionary-based logging:

- `CONFIG_LOG_DICTIONARY_SUPPORT` enables dictionary-based logging support. This should be selected by the backends which require it.
• The UART backend can be used for dictionary-based logging. These are additional config for the UART backend:
  – CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_HEX tells the UART backend to output hexadecimal characters for dictionary based logging. This is useful when the log data needs to be captured manually via terminals and consoles.
  – CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_BIN tells the UART backend to output binary data.

Usage When dictionary-based logging is enabled via enabling related logging backends, a JSON database file, named log_dictionary.json, will be created in the build directory. This database file contains information for the parser to correctly parse the log data. Note that this database file only works with the same build, and cannot be used for any other builds.

To use the log parser:

```
./scripts/logging/dictionary/log_parser.py <build dir>/log_dictionary.json <log data file>
```

The parser takes two required arguments, where the first one is the full path to the JSON database file, and the second part is the file containing log data. Add an optional argument --hex to the end if the log data file contains hexadecimal characters (e.g. when CONFIG_LOG_BACKEND_UART_OUTPUT_DICTIONARY_HEX=y). This tells the parser to convert the hexadecimal characters to binary before parsing.

Please refer to logging_dictionary_sample on how to use the log parser.

4.7.6 Recommendations

The are following recommendations:

• Enable CONFIG_LOG_SPEED to slightly speed up deferred logging at the cost of slight increase in memory footprint.

• Compiler with C11 _Generic keyword support is recommended. Logging performance is significantly degraded without it. See Cprintf Packaging.

• It is recommended to cast pointer to const char * when it is used with %s format specifier and it points to a constant string.

• It is recommended to cast pointer to char * when it is used with %s format specifier and it points to a transient string.

• It is recommended to cast character pointer to non character pointer (e.g., void *) when it is used with %p format specifier.

```c
LOG_WRN("%s", str);
LOG_WRN("%p", (void *)str);
```

4.7.7 Benchmark

Benchmark numbers from tests/subsys/logging/log_benchmark performed on qemu_x86. It is a rough comparison to give a general overview.
### Benchmark details

#### 4.7.8 Stack usage

When logging is enabled it impacts stack usage of the context that uses logging API. If stack is optimized it may lead to stack overflow. Stack usage depends on mode and optimization. It also significantly varies between platforms. In general, when CONFIG_LOG_MODE_DEFERRED is used stack usage is smaller since logging is limited to creating and storing log message. When CONFIG_LOG_MODE_IMMEDIATE is used then log message is processed by the backend which includes string formatting. In case of that mode, stack usage will depend on which backends are used.

The `tests/subsys/logging/log_stack` test is used to characterize stack usage depending on mode, optimization and platform used. Test is using only the default backend.

Some of the platforms characterization for log message with two integer arguments listed below:

<table>
<thead>
<tr>
<th>Platform</th>
<th>Deferred</th>
<th>Deferred (no optimization)</th>
<th>Immediate</th>
<th>Immediate (no optimization)</th>
</tr>
</thead>
<tbody>
<tr>
<td>ARM Cortex-M3</td>
<td>40</td>
<td>152</td>
<td>412</td>
<td>783</td>
</tr>
<tr>
<td>x86</td>
<td>12</td>
<td>224</td>
<td>388</td>
<td>796</td>
</tr>
<tr>
<td>riscv32</td>
<td>24</td>
<td>208</td>
<td>456</td>
<td>844</td>
</tr>
<tr>
<td>xtensa</td>
<td>72</td>
<td>336</td>
<td>504</td>
<td>944</td>
</tr>
<tr>
<td>x86_64</td>
<td>32</td>
<td>528</td>
<td>1088</td>
<td>1440</td>
</tr>
</tbody>
</table>

#### 4.7.9 API Reference

**Logger API**

```c
#include <log_api.h>

#define LOG_ERR(...) 
        /* Writes an ERROR level message to the log. */ 
        /* It’s meant to report severe errors, such as those from which it’s not possible to recover. */
```

---

3 CONFIG_LOG_SPEED enabled.
4 Number of log messages with various number of arguments that fits in 2048 bytes dedicated for logging.
5 Logging subsystem memory footprint in `tests/subsys/logging/log_benchmark` where filtering and formatting features are not used.
6 Logging subsystem memory footprint in `samples/subsys/logging/logger`.
7 Average size of a log message (excluding string) with 2 arguments on Cortex M3
Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_WRN(...)

Writes a WARNING level message to the log.
It's meant to register messages related to unusual situations that are not necessarily errors.

Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INF(...)

Writes an INFO level message to the log.
It's meant to write generic user oriented messages.

Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_DBG(...)

Writes a DEBUG level message to the log.
It's meant to write developer oriented information.

Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_PRINTK(...)

Unconditionally print raw log message.
The result is same as if printk was used but it goes through logging infrastructure thus utilizes logging mode, e.g. deferred mode.

Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_RAW(...)

Unconditionally print raw log message.
Provided string is printed as is without appending any characters (e.g., color or newline).

Parameters

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_ERR(_log_inst, ...)

Writes an ERROR level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to report severe errors, such as those from which it's not possible to recover.

Parameters

• _log_inst – Pointer to the log structure associated with the instance.

• . . . – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.
LOG_INST_WRN(_log_inst, ...)  
Writes a WARNING level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to register messages related to unusual situations that are not necessarily errors.

Parameters
• _log_inst – Pointer to the log structure associated with the instance.
• ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_INF(_log_inst, ...)  
Writes an INFO level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to write generic user oriented messages.

Parameters
• _log_inst – Pointer to the log structure associated with the instance.
• ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_INST_DBG(_log_inst, ...)  
Writes a DEBUG level message associated with the instance to the log.
Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>.<instance_name>). It's meant to write developer oriented information.

Parameters
• _log_inst – Pointer to the log structure associated with the instance.
• ... – A string optionally containing printk valid conversion specifier, followed by as many values as specifiers.

LOG_HEXDump_ERR(_data, _length, _str)  
Writes an ERROR level hexdump message to the log.
It's meant to report severe errors, such as those from which it's not possible to recover.

Parameters
• _data – Pointer to the data to be logged.
• _length – Length of data (in bytes).
• _str – Persistent, raw string.

LOG_HEXDump_WRN(_data, _length, _str)  
Writes a WARNING level message to the log.
It's meant to register messages related to unusual situations that are not necessarily errors.

Parameters
• _data – Pointer to the data to be logged.
• _length – Length of data (in bytes).
• _str – Persistent, raw string.
LOG_HEXDUMP_INF(_data, _length, _str)
  Writes an INFO level message to the log.
  It’s meant to write generic user oriented messages.

  Parameters
  • _data – Pointer to the data to be logged.
  • _length – Length of data (in bytes).
  • _str – Persistent, raw string.

LOG_HEXDUMP_DBG(_data, _length, _str)
  Writes a DEBUG level message to the log.
  It’s meant to write developer oriented information.

  Parameters
  • _data – Pointer to the data to be logged.
  • _length – Length of data (in bytes).
  • _str – Persistent, raw string.

LOG_INST_HEXDUMP_ERR(_log_inst, _data, _length, _str)
  Writes an ERROR hexdump message associated with the instance to the log.
  Message is associated with specific instance of the module which has independent filtering settings (if runtime filtering is enabled) and message prefix (<module_name>_<instance_name>). It’s meant to report severe errors, such as those from which it’s not possible to recover.

  Parameters
  • _log_inst – Pointer to the log structure associated with the instance.
  • _data – Pointer to the data to be logged.
  • _length – Length of data (in bytes).
  • _str – Persistent, raw string.

LOG_INST_HEXDUMP_WRN(_log_inst, _data, _length, _str)
  Writes a WARNING level hexdump message associated with the instance to the log.
  It’s meant to register messages related to unusual situations that are not necessarily errors.

  Parameters
  • _log_inst – Pointer to the log structure associated with the instance.
  • _data – Pointer to the data to be logged.
  • _length – Length of data (in bytes).
  • _str – Persistent, raw string.

LOG_INST_HEXDUMP_INF(_log_inst, _data, _length, _str)
  Writes an INFO level hexdump message associated with the instance to the log.
  It’s meant to write generic user oriented messages.

  Parameters
  • _log_inst – Pointer to the log structure associated with the instance.
  • _data – Pointer to the data to be logged.
  • _length – Length of data (in bytes).
  • _str – Persistent, raw string.
LOG_INST.HEXDUMP_DBG(_log_inst, _data, _length, _str)

Writes a DEBUG level hexdump message associated with the instance to the log.

It's meant to write developer oriented information.

**Parameters**

- `_log_inst` – Pointer to the log structure associated with the instance.
- `_data` – Pointer to the data to be logged.
- `_length` – Length of data (in bytes).
- `_str` – Persistent, raw string.

LOG_MODULE_REGISTER(...)  
Create module-specific state and register the module with Logger.

This macro normally must be used after including `<zephyr/logging/log.h>` to complete the initialization of the module.

Module registration can be skipped in two cases:

- The module consists of more than one file, and another file invokes this macro.  
  *(LOG_MODULE_DECLARE() should be used instead in all of the module's other files.)*  
- Instance logging is used and there is no need to create module entry.  In that case  
  LOG_LEVEL_SET() should be used to set log level used within the file.

Macro accepts one or two parameters:

- module name
- optional log level. If not provided then default log level is used in the file.

Example usage:

- `LOG_MODULE_REGISTER(foo, CONFIG_FOO_LOG_LEVEL)`
- `LOG_MODULE_REGISTER(foo)`  

**See also:**

*LOG_MODULE_DECLARE*

---

**Note:** The module's state is defined, and the module is registered, only if LOG_LEVEL for  
the current source file is non-zero or it is not defined and CONFIG_LOG_DEFAULT_LEVEL is non-zero. In other cases, this macro has no effect.

---

LOG_MODULE_DECLARE(...)  
Macro for declaring a log module (not registering it).

Modules which are split up over multiple files must have exactly one file use  
LOG_MODULE_REGISTER() to create module-specific state and register the module with the  
logger core.

The other files in the module should use this macro instead to declare that same state. (Othe-  
wise, LOG_INF() etc. will not be able to refer to module-specific state variables.)

Macro accepts one or two parameters:

- module name
- optional log level. If not provided then default log level is used in the file.

Example usage:
• `LOG_MODULE_DECLARE(foo, CONFIG_FOO_LOG_LEVEL)`
• `LOG_MODULE_DECLARE(foo)`

**See also:**

`LOG_MODULE_REGISTER`

---

**Note:** The module's state is declared only if LOG_LEVEL for the current source file is non-zero or it is not defined and CONFIG_LOG_DEFAULT_LEVEL is non-zero. In other cases, this macro has no effect.

`LOG_LEVEL_SET(level)`

Macro for setting log level in the file or function where instance logging API is used.

**Parameters**

- `level` – Level used in file or in function.

**Logger control**

`group log_ctrl`

Logger control API.

**Defines**

- `LOG_CORE_INIT()`
- `LOG_INIT()`
- `LOG_PANIC()`
- `LOG_PROCESS()`

**Typedefs**

typedef `log_timestamp_t (*log_timestamp_get_t)(void)`

**Functions**

- `void log_core_init(void)`
  Function system initialization of the logger.
  Function is called during start up to allow logging before user can explicitly initialize the logger.
- `void log_init(void)`
  Function for user initialization of the logger.
void log_thread_set(k_tid_t process_tid)
Function for providing thread which is processing logs.
See CONFIG_LOG_PROCESS_TRIGGER_THRESHOLD.

Note: Function has asserts and has no effect when CONFIG_LOG_PROCESS_THREAD is set.

Parameters
• process_tid – Process thread id. Used to wake up the thread.

int log_set_timestamp_func(log_timestamp_get_t timestamp_getter, uint32_t freq)
Function for providing timestamp function.

Parameters
• timestamp_getter – Timestamp function.
• freq – Timestamping frequency.

Returns
0 on success or error.

void log_panic(void)
Switch the logger subsystem to the panic mode.

Returns immediately if the logger is already in the panic mode.

On panic the logger subsystem informs all backends about panic mode. Backends must switch to blocking mode or halt. All pending logs are flushed after switching to panic mode. In panic mode, all log messages must be processed in the context of the call.

bool log_process(void)
Process one pending log message.

Return values
• true – There is more messages pending to be processed.
• false – No messages pending.

uint32_t log_buffered_cnt(void)
Return number of buffered log messages.

Returns
Number of currently buffered log messages.

uint32_t log_src_cnt_get(uint32_t domain_id)
Get number of independent logger sources (modules and instances)

Parameters
• domain_id – Domain ID.

Returns
Number of sources.

const char *log_source_name_get(uint32_t domain_id, uint32_t source_id)
Get name of the source (module or instance).

Parameters
• domain_id – Domain ID.
• source_id – Source ID.
Returns
Source name or NULL if invalid arguments.

static inline uint8_t log_domains_count(void)
Return number of domains present in the system.
There will be at least one local domain.

Returns
Number of domains.

const char *log_domain_name_get(uint32_t domain_id)
Get name of the domain.

Parameters
• domain_id – Domain ID.

Returns
Domain name.

int log_source_id_get(const char *name)
Function for finding source ID based on source name.

Parameters
• name – Source name

Returns
Source ID or negative number when source ID is not found.

uint32_t log_filter_get(struct log_backend const *const backend, uint32_t domain_id, int16_t source_id, bool runtime)
Get source filter for the provided backend.

Parameters
• backend – Backend instance.
• domain_id – ID of the domain.
• source_id – Source (module or instance) ID.
• runtime – True for runtime filter or false for compiled in.

Returns
Severity level.

uint32_t log_filter_set(struct log_backend const *const backend, uint32_t domain_id, int16_t source_id, uint32_t level)
Set filter on given source for the provided backend.

Parameters
• backend – Backend instance. NULL for all backends.
• domain_id – ID of the domain.
• source_id – Source (module or instance) ID.
• level – Severity level.

Returns
Actual level set which may be limited by compiled level. If filter was set for all backends then maximal level that was set is returned.

void log_backend_enable(struct log_backend const *const backend, void *ctx, uint32_t level)
Enable backend with initial maximum filtering level.

Parameters
• `backend` – Backend instance.
• `ctx` – User context.
• `level` – Severity level.

```c
void log_backend_disable(const log_backend *const backend)
```
Disable backend.

**Parameters**

• `backend` – Backend instance.

```c
const struct log_backend *
log_backend_get_by_name(const char *backend_name)
```
Get backend by name.

**Parameters**

• `backend_name` – [in] Name of the backend as defined by the LOG_BACKEND_DEFINE.

**Return values**

Pointer – to the backend instance if found, NULL if backend is not found.

```c
const struct log_backend *
log_format_set_all_active_backends(size_t log_type)
```
Sets logging format for all active backends.

**Parameters**

• `log_type` – Log format.

**Return values**

Pointer – to the last backend that failed, NULL for success.

```c
uint32_t log_get_strdup_pool_current_utilization(void)
```
Get current number of allocated buffers for string duplicates.

```c
uint32_t log_get_strdup_pool_utilization(void)
```
Get maximal number of simultaneously allocated buffers for string duplicates.

Value can be used to determine pool size.

```c
uint32_t log_get_strdup_longest_string(void)
```
Get length of the longest string duplicated.

Value can be used to determine buffer size in the string duplicates pool.

```c
static inline bool log_data_pending(void)
```
Check if there is pending data to be processed by the logging subsystem.

Function can be used to determine if all logs have been flushed. Function returns false when deferred mode is not enabled.

**Return values**

• `true` – There is pending data.
• `false` – No pending data to process.

```c
int log_set_tag(const char *tag)
```
Configure tag used to prefix each message.

**Parameters**

• `tag` – Tag.

**Return values**

• `0` – on successful operation.
• `-ENOTSUP` – if feature is disabled.
-ENOMEM – if string is longer than the buffer capacity. Tag will be trimmed.

```c
int log_mem_get_usage(uint32_t *buf_size, uint32_t *usage)
Get current memory usage.
```

**Parameters**

- `buf_size` – [out] Capacity of the buffer used for storing log messages.
- `usage` – [out] Number of bytes currently containing pending log messages.

**Return values**

- EINVAL – if logging mode does not use the buffer.
- 0 – successfully collected usage data.

```c
int log_mem_get_max_usage(uint32_t *max)
Get maximum memory usage.
```

Requires CONFIG_LOG_MEM_UTILIZATION option.

**Parameters**

- `max` – [out] Maximum number of bytes used for pending log messages.

**Return values**

- EINVAL – if logging mode does not use the buffer.
- ENOTSUP – if instrumentation is not enabled. not been enabled.
- 0 – successfully collected usage data.

### Log message

**group log_msg**

Log message API.

**Defines**

LOG_MSG2_GENERIC_HDR

**Functions**

```c
static inline uint32_t log_msg_get_total_wlen(const struct log_msg_desc desc)
Get total length (in 32 bit words) of a log message.
```

**Parameters**

- `desc` – Log message descriptor.

**Returns**

Length.

```c
static inline uint32_t log_msg_generic_get_wlen(const union mpsc_pbuf_generic *item)
Get length of the log item.
```

**Parameters**

- `item` – Item.

**Returns**

Length in 32 bit words.
static inline uint8_t log_msg_get_domain(struct log_msg *msg)
    Get log message domain ID.

    **Parameters**
    
    • msg – Log message.

    **Returns**
    Domain ID

static inline uint8_t log_msg_get_level(struct log_msg *msg)
    Get log message level.

    **Parameters**
    
    • msg – Log message.

    **Returns**
    Log level.

static inline const void *log_msg_get_source(struct log_msg *msg)
    Get message source data.

    **Parameters**
    
    • msg – Log message.

    **Returns**
    Pointer to the source data.

static inline log_timestamp_t log_msg_get_timestamp(struct log_msg *msg)
    Get timestamp.

    **Parameters**
    
    • msg – Log message.

    **Returns**
    Timestamp.

static inline uint8_t *log_msg_get_data(struct log_msg *msg, size_t *len)
    Get data buffer.

    **Parameters**
    
    • msg – log message.
    • len – location where data length is written.

    **Returns**
    pointer to the data buffer.

static inline uint8_t *log_msg_get_package(struct log_msg *msg, size_t *len)
    Get string package.

    **Parameters**
    
    • msg – log message.
    • len – location where string package length is written.

    **Returns**
    pointer to the package.

struct log_msg_desc
# include <log_msg.h>

union log_msg_source
# include <log_msg.h>
Public Members

const struct log_source_const_data *fixed

struct log_source_dynamic_data *dynamic

void *raw

struct log_msg_hdr
#include <log_msg.h>

struct log_msg
#include <log_msg.h>

struct log_msg_generic_hdr
#include <log_msg.h>

union log_msg_generic
#include <log_msg.h>

Public Members

union mpsc_pbuf_generic buf

struct log_msg_generic_hdr generic

struct log_msg log

Logger backend interface

group log_backend
Logger backend interface.

Defines

LOG_BACKEND_DEFINE(_name, _api, _autostart, ...)
Macro for creating a logger backend instance.

Parameters

• _name – Name of the backend instance.
• _api – Logger backend API.
• _autostart – If true backend is initialized and activated together with the logger subsystem.
• ... – Optional context.

4.7. Logging
Enums

enum log_backend_evt
   Backend events.
   Values:

   enumerator LOG_BACKEND_EVT_PROCESS_THREAD_DONE
      Event when process thread finishes processing.
      This event is emitted when the process thread finishes processing pending log messages.

      Note: This is not emitted when there are no pending log messages being processed.

      Note: Deferred mode only.

   enumerator LOG_BACKEND_EVT_MAX
      Maximum number of backend events.

Functions

static inline void log_backend_init(const struct log_backend *const backend)
   Initialize or initiate the logging backend.
   If backend initialization takes longer time it could block logging thread if backend is autostarted. That is because all backends are initialized in the context of the logging thread. In that case, backend shall provide function for polling for readiness (log_backend_is_ready).

   Parameters
   • backend – [in] Pointer to the backend instance.

static inline int log_backend_is_ready(const struct log_backend *const backend)
   Poll for backend readiness.
   If backend is ready immediately after initialization then backend may not provide this function.

   Parameters
   • backend – [in] Pointer to the backend instance.

   Return values
   • 0 – if backend is ready.
   • -EBUSY – if backend is not yet ready.

static inline void log_backend_msg_process(const struct log_backend *const backend,
                                           union log_msg_generic *msg)
   Process message.
   Function is used in deferred and immediate mode. On return, message content is processed by the backend and memory can be freed.

   Parameters
   • backend – [in] Pointer to the backend instance.
   • msg – [in] Pointer to message with log entry.
static inline void log_backend_dropped(const struct log_backend *const backend, uint32_t cnt)
    Notify backend about dropped log messages.
    Function is optional.

    Parameters
    • backend – [in] Pointer to the backend instance.
    • cnt – [in] Number of dropped logs since last notification.

static inline void log_backend_panic(const struct log_backend *const backend)
    Reconfigure backend to panic mode.

    Parameters
    • backend – [in] Pointer to the backend instance.

static inline void log_backend_id_set(const struct log_backend *const backend, uint8_t id)
    Set backend id.

    Note: It is used internally by the logger.

    Parameters
    • backend – Pointer to the backend instance.
    • id – ID.

static inline uint8_t log_backend_id_get(const struct log_backend *const backend)
    Get backend id.

    Note: It is used internally by the logger.

    Parameters
    • backend – [in] Pointer to the backend instance.

static inline const struct log_backend *log_backend_get(uint32_t idx)
    Get backend.

    Parameters
    • idx – [in] Pointer to the backend instance.

    Returns
    Id.

static inline int log_backend_count_get(void)
    Get number of backends.

    Returns
    Number of backends.

static inline void log_backend_activate(const struct log_backend *const backend, void *ctx)
    Activate backend.

    Parameters
    • backend – [in] Pointer to the backend instance.
• ctx – [in] User context.

static inline void log_backend_deactivate(const struct log_backend *const backend)
    Deactivate backend.

Parameters
• backend – [in] Pointer to the backend instance.

static inline bool log_backend_is_active(const struct log_backend *const backend)
    Check state of the backend.

Parameters
• backend – [in] Pointer to the backend instance.

Returns
True if backend is active, false otherwise.

static inline int log_backend_format_set(const struct log_backend *backend, uint32_t log_type)
    Set logging format.

Parameters
• backend – Pointer to the backend instance.
• log_type – Log format.

Return values
• -ENOTSUP – If the backend does not support changing format types.
• -EINVAL – If the input is invalid.
• 0 – for success.

static inline void log_backend_notify(const struct log_backend *const backend, enum log_backend_evt event, union log_backend_evt_arg *arg)
    Notify a backend of an event.

Parameters
• backend – Pointer to the backend instance.
• event – Event to be notified.
• arg – Pointer to the argument(s).

union log_backend_evt_arg
    #include <log_backend.h> Argument(s) for backend events.

Public Members

void *raw
    Unspecified argument(s).

struct log_backend_api
    #include <log_backend.h> Logger backend API.

struct log_backend_control_block
    #include <log_backend.h> Logger backend control block.

struct log_backend
    #include <log_backend.h> Logger backend structure.
Logger output formatting

`group log_output`

Log output API.

**Unnamed Group**

`void log_custom_output_msg_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)`

Custom logging output formatting.

Process log messages from an external output function set with `log_custom_output_msg_set`.

Function is using provided context with the buffer and output function to process formatted string and output the data.

**Parameters**

- `log_output` – Pointer to the log output instance.
- `msg` – Log message.
- `flags` – Optional flags.

`void log_custom_output_msg_set(log_format_func_t format)`

Set the formatting log function that will be applied with LOG_OUTPUT_CUSTOM.

**Parameters**

- `format` – Pointer to the external formatter function

**Defines**

LOG_OUTPUT_TEXT

Supported backend logging format types for use with `log_format_set()` API to switch log format at runtime.

LOG_OUTPUT_SYST

LOG_OUTPUT_DICT

LOG_OUTPUT_CUSTOM

LOG_OUTPUT_DEFINE(_name, _func, _buf, _size)

Create `log_output` instance.

**Parameters**

- `_name` – Instance name.
- `_func` – Function for processing output data.
- `_buf` – Pointer to the output buffer.
- `_size` – Size of the output buffer.
**Typedefs**

```c
typedef int (*log_output_func_t)(uint8_t *buf, size_t size, void *ctx)
Prototype of the function processing output data.
```

**Note:** If the log output function cannot process all of the data, it is its responsibility to mark them as dropped or discarded by returning the corresponding number of bytes dropped or discarded to the caller.

- **Param buf**
  The buffer data.
- **Param size**
  The buffer size.
- **Param ctx**
  User context.
- **Return**
  Number of bytes processed, dropped or discarded.

```c
typedef void (*log_format_func_t)(const struct log_output *output, struct log_msg *msg, uint32_t flags)
Typedef of the function pointer table “format_table”.
```

- **Param output**
  Pointer to `log_output` struct.
- **Param msg**
  Pointer to `log_msg` struct.
- **Param flags**
  Flags used for text formatting options.
- **Return**
  Function pointer based on Kconfigs defined for backends.

**Functions**

```c
log_format_func_t log_format_func_t_get(uint32_t log_type)
Declaration of the get routine for function pointer table format_table.
```

```c
void log_output_msg_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)
Process log messages v2 to readable strings.
Function is using provided context with the buffer and output function to process formatted string and output the data.
```

- **Parameters**
  - `log_output` – Pointer to the log output instance.
  - `msg` – Log message.
  - `flags` – Optional flags. See Log output formatting flags.
void log_output_process(const struct log_output *log_output, log_timestamp_t timestamp, const char *domain, const char *source, uint8_t level, const uint8_t *package, const uint8_t *data, size_t data_len, uint32_t flags)

Process input data to a readable string.

Parameters

- `log_output` – Pointer to the log output instance.
- `timestamp` – Timestamp.
- `domain` – Domain name string. Can be NULL.
- `source` – Source name string. Can be NULL.
- `level` – Criticality level.
- `package` – Cbprintf package with a logging message string.
- `data` – Data passed to hexdump API. Can be NULL.
- `data_len` – Data length.
- `flags` – Formatting flags. See Log output formatting flags.

void log_output_msg_syst_process(const struct log_output *log_output, struct log_msg *msg, uint32_t flags)

Process log messages v2 to SYS-T format.

Function is using provided context with the buffer and output function to process formatted string and output the data in sys-t log output format.

Parameters

- `log_output` – Pointer to the log output instance.
- `msg` – Log message.
- `flags` – Optional flags. See Log output formatting flags.

void log_output_dropped_process(const struct log_output *output, uint32_t cnt)

Process dropped messages indication.

Function prints error message indicating lost log messages.

Parameters

- `output` – Pointer to the log output instance.
- `cnt` – Number of dropped messages.

void log_output_flush(const struct log_output *output)

Flush output buffer.

Parameters

- `output` – Pointer to the log output instance.

static inline void log_output_ctx_set(const struct log_output *output, void *ctx)

Function for setting user context passed to the output function.

Parameters

- `output` – Pointer to the log output instance.
- `ctx` – User context.

static inline void log_output_hostname_set(const struct log_output *output, const char *hostname)

Function for setting hostname of this device.
Parameters

- output – Pointer to the log output instance.
- hostname – Hostname of this device

void log_output_timestamp_freq_set(uint32_t freq)
Set timestamp frequency.

Parameters

- freq – Frequency in Hz.

uint64_t log_output_timestamp_to_us(uint32_t timestamp)
Convert timestamp of the message to us.

Parameters

- timestamp – Message timestamp

Returns

Timestamp value in us.

struct log_output_control_block
#include <log_output.h>

struct log_output
#include <log_output.h> Log_output instance structure.

4.8 Tracing

4.8.1 Overview

The tracing feature provides hooks that permits you to collect data from your application and allows tools running on a host to visualize the inner-working of the kernel and various subsystems.

Every system has application-specific events to trace out. Historically, that has implied:

1. Determining the application-specific payload,
2. Choosing suitable serialization-format,
3. Writing the on-target serialization code,
4. Deciding on and writing the I/O transport mechanics,
5. Writing the PC-side deserializer/parser,
6. Writing custom ad-hoc tools for filtering and presentation.

An application can use one of the existing formats or define a custom format by overriding the macros declared in include/zephyr/tracing/tracing.h.

Different formats, transports and host tools are available and supported in Zephyr.

In fact, I/O varies greatly from system to system. Therefore, it is instructive to create a taxonomy for I/O types when we must ensure the interface between payload/format (Top Layer) and the transport mechanics (bottom Layer) is generic and efficient enough to model these. See the I/O taxonomy section below.
4.8.2 Serialization Formats

Common Trace Format (CTF) Support

Common Trace Format, CTF, is an open format and language to describe trace formats. This enables tool reuse, of which line-textual (babeltrace) and graphical (TraceCompass) variants already exist.

CTF should look familiar to C programmers but adds stronger typing. See CTF - A Flexible, High-performance Binary Trace Format.

CTF allows us to formally describe application specific payload and the serialization format, which enables common infrastructure for host tools and parsers and tools for filtering and presentation.

A Generic Interface  In CTF, an event is serialized to a packet containing one or more fields. As seen from I/O taxonomy section below, a bottom layer may:

- perform actions at transaction-start (e.g. mutex-lock),
- process each field in some way (e.g. sync-push emit, concat, enqueue to thread-bound FIFO),
- perform actions at transaction-stop (e.g. mutex-release, emit of concat buffer).

CTF Top-Layer Example The CTF_EVENT macro will serialize each argument to a field:

```c
/* Example for illustration */
static inline void ctf_top_foo(uint32_t thread_id, ctf_bounded_string_t name)
{
    CTF_EVENT(
        CTF_LITERAL(uint8_t, 42),
        thread_id,
        name,
        "hello, I was emitted from function: ",
        __func__ /* __func__ is standard since C99 */
    );
}
```

How to serialize and emit fields as well as handling alignment, can be done internally and statically at compile-time in the bottom-layer.

The CTF top layer is enabled using the configuration option CONFIG_TRACING_CTF and can be used with the different transport backends both in synchronous and asynchronous modes.

SEGGER SystemView Support

Zephyr provides built-in support for SEGGER SystemView that can be enabled in any application for platforms that have the required hardware support.

The payload and format used with SystemView is custom to the application and relies on RTT as a transport. Newer versions of SystemView support other transports, for example UART or using snapshot mode (both still not supported in Zephyr).

To enable tracing support with SEGGER SystemView add the configuration option CONFIG_SEGGER_SYSTEMVIEW to your project configuration file and set it to y. For example, this can be added to the synchronization_sample to visualize fast switching between threads. SystemView can also be used for post-mortem tracing, which can be enabled with CONFIG_SEGGER_SYSVIEW_POST_MORTEM_MODE. In this mode, a debugger can be attached after the system has crashed using west attach after which the latest data from the internal RAM buffer can be loaded into SystemView.
Recent versions of SEGGER SystemView come with an API translation table for Zephyr which is incomplete and does not match the current level of support available in Zephyr. To use the latest Zephyr API description table, copy the file available in the tree to your local configuration directory to override the builtin table:

```bash
# On Linux and MacOS
cp ZEPHYR_BASE/subsys/tracing/sysview/SYSVIEW_Zephyr.txt ~/.config/SEGGER/
```

User-Defined Tracing

This tracing format allows the user to define functions to perform any work desired when a task is switched in or out, when an interrupt is entered or exited, and when the cpu is idle.

Examples include:
- simple toggling of GPIO for external scope tracing while minimizing extra cpu load
- generating/outputting trace data in a non-standard or proprietary format that can not be supported by the other tracing systems

The following functions can be defined by the user:
- `void sys_trace_thread_create_user(struct k_thread *thread)`
- `void sys_trace_thread_abort_user(struct k_thread *thread)`
- `void sys_trace_thread_suspend_user(struct k_thread *thread)`
- `void sys_trace_thread_resume_user(struct k_thread *thread)`
- `void sys_trace_thread_name_set_user(struct k_thread *thread)`
- `void sys_trace_thread_switched_in_user(struct k_thread *thread)`
- `void sys_trace_thread_switched_out_user(struct k_thread *thread)`
- `void sys_trace_thread_info_user(struct k_thread *thread)`
- `void sys_trace_thread_sched_ready_user(struct k_thread *thread)`
- `void sys_trace_thread_pend_user(struct k_thread *thread)`
- `void sys_trace_thread_priority_set_user(struct k_thread *thread)`
k_thread *thread, int prio) - void sys_trace_isr_enter_user(int nested_interrupts) - void
sys_trace_isr_exit_user(int nested_interrupts) - void sys_trace_idle_user()

Enable this format with the CONFIG_TRACING_USER option.

4.8.3 Transport Backends

The following backends are currently supported:

- UART
- USB
- File (Using native posix port)
- RTT (With SystemView)
- RAM (buffer to be retrieved by a debugger)

4.8.4 Using Tracing

The sample samples/subsys/tracing demonstrates tracing with different formats and backends.

To get started, the simplest way is to use the CTF format with the native_posix port, build the sample as follows:

Using west:

```
w west build -b native_posix samples/subsys/tracing -- -DCONF_FILE=prj_native_posix_ctf.conf
```

Using CMake and ninja:

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=native_posix -DCONF_FILE=prj_native_posix_ctf.conf
   samples/subsys/tracing

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

You can then run the resulting binary with the option -trace-file to generate the tracing data:

```
mkdir data
cp $ZEPHYR_BASE/subsys/tracing/ctf/tsdl/metadata data/
cp $ZEPHYR_BASE/subsys/tracing/ctf/tsdl/metadata data/
./build/zephyr/zephyr.exe -trace-file=data/channel0_0
```

The resulting CTF output can be visualized using babeltrace or TraceCompass by pointing the tool to the data directory with the metadata and trace files.

Using RAM backend

For devices that do not have available I/O for tracing such as USB or UART but have enough RAM to collect trace data, the ram backend can be enabled with configuration CONFIG_TRACING_BACKEND_RAM. Adjust CONFIG_RAM_TRACING_BUFFER_SIZE to be able to record enough traces for your needs. Then thanks to a runtime debugger such as gdb this buffer can be fetched from the target to an host computer:

```
(gdb) dump binary memory data/channel0_0 <ram_tracing_start> <ram_tracing_end>
```

The resulting channel0_0 file have to be placed in a directory with the metadata file like the other backend.
4.8.5 Visualisation Tools

TraceCompass

TraceCompass is an open source tool that visualizes CTF events such as thread scheduling and interrupts, and is helpful to find unintended interactions and resource conflicts on complex systems. See also the presentation by Ericsson, Advanced Trouble-shooting Of Real-time Systems.

4.8.6 Future LTTng Inspiration

Currently, the top-layer provided here is quite simple and bare-bones, and needlessly copied from Zephyr’s Segger SystemView debug module.

For an OS like Zephyr, it would make sense to draw inspiration from Linux’s LTTng and change the top-layer to serialize to the same format. Doing this would enable direct reuse of TraceCompass’ canned analyses for Linux. Alternatively, LTTng-analyses in TraceCompass could be customized to Zephyr. It is ongoing work to enable TraceCompass visibility of Zephyr in a target-agnostic and open source way.

I/O Taxonomy

- Atomic Push/Produce/Write/Enqueue:
  - synchronous:
    means data-transmission has completed with the return of the call.
  - asynchronous:
    means data-transmission is pending or ongoing with the return of the call. Usually, interrupts/callbacks/signals or polling is used to determine completion.
  - buffered:
    means data-transmissions are copied and grouped together to form a larger ones. Usually for amortizing overhead (burst dequeue) or jitter-mitigation (steady dequeue).

Examples:

- sync unbuffered
  E.g. PIO via GPIOs having steady stream, no extra FIFO memory needed. Low jitter but may be less efficient (can’t amortize the overhead of writing).

- sync buffered
  E.g. fwrite() or enqueuing into FIFO. Blockingly burst the FIFO when its buffer-waterlevel exceeds threshold. Jitter due to bursts may lead to missed deadlines.

- async unbuffered
  E.g. DMA, or zero-copying in shared memory. Be careful of data hazards, race conditions, etc!

- async buffered
  E.g. enqueuing into FIFO.

- Atomic Pull/Consume/Read/Dequeue:
  - synchronous:
    means data-reception has completed with the return of the call.
  - asynchronous:
    means data-reception is pending or ongoing with the return of the call. Usually, interrupts/callbacks/signals or polling is used to determine completion.
  - buffered:
    means data is copied-in in larger chunks than request-size. Usually for amortizing wait-time.
Examples:

- **sync unbuffered**
  E.g. Blocking read-call, `fread()` or SPI-read, zero-copying in shared memory.

- **sync buffered**
  E.g. Blocking read-call with caching applied. Makes sense if read pattern exhibits
  spatial locality.

- **async unbuffered**
  E.g. zero-copying in shared memory. Be careful of data hazards, race conditions, etc!

- **async buffered**
  E.g. `aio_read()` or DMA.

Unfortunately, I/O may not be atomic and may, therefore, require locking. Locking may not be needed if
multiple independent channels are available.

- **The system has non-atomic write and one shared channel**
  E.g. UART. Locking required.
  
  ```
  lock(); emit(a); emit(b); emit(c); release();
  ```

- **The system has non-atomic write but many channels**
  E.g. Multi-UART. Lock-free if the bottom-layer maps each Zephyr thread+ISR to its own
  channel, thus alleviating races as each thread is sequentially consistent with itself.
  
  ```
  emit(a,thread_id); emit(b,thread_id); emit(c,thread_id);
  ```

- **The system has atomic write but one shared channel**
  E.g. native_posix or board with DMA. May or may not need locking.
  
  ```
  emit(a ## b ## c); /* Concat to buffer */
  lock(); emit(a); emit(b); emit(c); release(); /* No extra mem */
  ```

- **The system has atomic write and many channels**
  E.g. native_posix or board with multi-channel DMA. Lock-free.
  
  ```
  emit(a ## b ## c, thread_id);
  ```

### 4.8.7 Object tracking

The kernel can also maintain lists of objects that can be used to track their usage. Currently, the following
lists can be enabled:

```
struct k_timer * _track_list_k_timer;
struct k_mem_slab * _track_list_k_mem_slab;
struct k_sem * _track_list_k_sem;
struct k_mutex * _track_list_k_mutex;
struct k_stack * _track_list_k_stack;
struct k_msgq * _track_list_k_msgq;
struct k_mbox * _track_list_k_mbox;
struct k_pipe * _track_list_k_pipe;
struct k_queue * _track_list_k_queue;
```

Those global variables are the head of each list - they can be traversed with the help of macro
`SYS_PORT_TRACK_NEXT`. For instance, to traverse all initialized mutexes, one can write:

```
struct k_mutex * cur = _track_list_k_mutex;
while (cur != NULL) {
    /* Do something */
}
```

(continues on next page)
To enable object tracking, enable `CONFIG_TRACING_OBJECT_TRACKING`. Note that each list can be enabled or disabled via their tracing configuration. For example, to disable tracking of semaphores, one can disable `CONFIG_TRACING_SEMAPHORE`.

Object tracking is behind tracing configuration as it currently leverages tracing infrastructure to perform the tracking.

### 4.8.8 API

**Common**

**group subsys_tracing_apis**
Tracing APIs.

**Functions**

```c
void sys_trace_isr_enter(void)
Called when entering an ISR.

void sys_trace_isr_exit(void)
Called when exiting an ISR.

void sys_trace_isr_exit_to_scheduler(void)
Called when exiting an ISR and switching to scheduler.

void sys_trace_idle(void)
Called when the cpu enters the idle state.
```

**Threads**

**group subsys_tracing_apis_thread**
Thread Tracing APIs.

**Defines**

```c
sys_port_trace_k_thread_foreach_enter()
Called when entering a k_thread_foreach call.

sys_port_trace_k_thread_foreach_exit()
Called when exiting a k_thread_foreach call.

sys_port_trace_k_thread_foreach_unlocked_enter()
Called when entering a k_thread_foreach_unlocked.

sys_port_trace_k_thread_foreach_unlocked_exit()
Called when exiting a k_thread_foreach_unlocked.
```
sys_port_trace_k_thread_create(new_thread)
Trace creating a Thread.

Parameters
• new_thread – Thread object

sys_port_trace_k_thread_user_mode_enter()
Trace Thread entering user mode.

sys_port_trace_k_thread_join_enter(thread, timeout)
Called when entering a k_thread_join.

Parameters
• thread – Thread object
• timeout – Timeout period

sys_port_trace_k_thread_join_blocking(thread, timeout)
Called when k_thread_join blocks.

Parameters
• thread – Thread object
• timeout – Timeout period

sys_port_trace_k_thread_join_exit(thread, timeout, ret)
Called when exiting k_thread_join.

Parameters
• thread – Thread object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_thread_sleep_enter(timeout)
Called when entering k_thread_sleep.

Parameters
• timeout – Timeout period

sys_port_trace_k_thread_sleep_exit(timeout, ret)
Called when exiting k_thread_sleep.

Parameters
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_thread_msleep_enter(ms)
Called when entering k_thread_msleep.

Parameters
• ms – Duration in milliseconds

sys_port_trace_k_thread_msleep_exit(ms, ret)
Called when exiting k_thread_msleep.

Parameters
• ms – Duration in milliseconds
• ret – Return value
sys_port_trace_k_thread_usleep_enter(us)
    Called when entering k_thread_usleep.

    **Parameters**
    - us – Duration in microseconds

sys_port_trace_k_thread_usleep_exit(us, ret)
    Called when exiting k_thread_usleep.

    **Parameters**
    - us – Duration in microseconds
    - ret – Return value

sys_port_trace_k_thread_busy_wait_enter(usec_to_wait)
    Called when entering k_thread_busy_wait.

    **Parameters**
    - usec_to_wait – Duration in microseconds

sys_port_trace_k_thread_busy_wait_exit(usec_to_wait)
    Called when exiting k_thread_busy_wait.

    **Parameters**
    - usec_to_wait – Duration in microseconds

sys_port_trace_k_thread_yield()
    Called when a thread yields.

sys_port_trace_k_thread_wakeup(thread)
    Called when a thread wakes up.

    **Parameters**
    - thread – Thread object

sys_port_trace_k_thread_start(thread)
    Called when a thread is started.

    **Parameters**
    - thread – Thread object

sys_port_trace_k_thread_abort(thread)
    Called when a thread is being aborted.

    **Parameters**
    - thread – Thread object

sys_port_trace_k_thread_abort_enter(thread)
    Called when a thread enters the k_thread_abort routine.

    **Parameters**
    - thread – Thread object

sys_port_trace_k_thread_abort_exit(thread)
    Called when a thread exits the k_thread_abort routine.

    **Parameters**
    - thread – Thread object
sys_port_trace_k_thread_priority_set(thread)
   Called when setting priority of a thread.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_suspend_enter(thread)
   Called when a thread enters the k_thread_suspend function.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_suspend_exit(thread)
   Called when a thread exits the k_thread_suspend function.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_resume_enter(thread)
   Called when a thread enters the resume from suspension function.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_resume_exit(thread)
   Called when a thread exits the resumed from suspension function.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_lock()
   Called when the thread scheduler is locked.

sys_port_trace_k_thread_sched_unlock()
   Called when the thread scheduler is unlocked.

sys_port_trace_k_thread_name_set(thread, ret)
   Called when a thread name is set.

   Parameters
   • thread – Thread object
   • ret – Return value

sys_port_trace_k_thread_switched_out()
   Called before a thread has been selected to run.

sys_port_trace_k_thread_switched_in()
   Called after a thread has been selected to run.

sys_port_trace_k_thread_ready(thread)
   Called when a thread is ready to run.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_pend(thread)
   Called when a thread is pending.

   Parameters
   • thread – Thread object
sys_port_trace_k_thread_info(thread)
   Provide information about specific thread.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_wakeup(thread)
   Trace implicit thread wakeup invocation by the scheduler.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_abort(thread)
   Trace implicit thread abort invocation by the scheduler.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_priority_set(thread, prio)
   Trace implicit thread set priority invocation by the scheduler.

   Parameters
   • thread – Thread object
   • prio – Thread priority

sys_port_trace_k_thread_sched_ready(thread)
   Trace implicit thread ready invocation by the scheduler.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_pend(thread)
   Trace implicit thread pend invocation by the scheduler.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_resume(thread)
   Trace implicit thread resume invocation by the scheduler.

   Parameters
   • thread – Thread object

sys_port_trace_k_thread_sched_suspend(thread)
   Trace implicit thread suspend invocation by the scheduler.

   Parameters
   • thread – Thread object

Work Queues

group subsys_tracing_apis_work
   Work Tracing APIs.
Defines

sys_port_trace_k_work_init(work)
    Trace initialisation of a Work structure.

    Parameters
    • work – Work structure

sys_port_trace_k_work_submit_to_queue_enter(queue, work)
    Trace submit work to work queue call entry.

    Parameters
    • queue – Work queue structure
    • work – Work structure

sys_port_trace_k_work_submit_to_queue_exit(queue, work, ret)
    Trace submit work to work queue call exit.

    Parameters
    • queue – Work queue structure
    • work – Work structure
    • ret – Return value

sys_port_trace_k_work_submit_enter(work)
    Trace submit work to system work queue call entry.

    Parameters
    • work – Work structure

sys_port_trace_k_work_submit_exit(work, ret)
    Trace submit work to system work queue call exit.

    Parameters
    • work – Work structure
    • ret – Return value

sys_port_trace_k_work_flush_enter(work)
    Trace flush work call entry.

    Parameters
    • work – Work structure

sys_port_trace_k_work_flush_blocking(work, timeout)
    Trace flush work call blocking.

    Parameters
    • work – Work structure
    • timeout – Timeout period

sys_port_trace_k_work_flush_exit(work, ret)
    Trace flush work call exit.

    Parameters
    • work – Work structure
    • ret – Return value
sys_port_trace_k_work_cancel_enter(work)
Trace cancel work call entry.

**Parameters**
- **work** – Work structure

sys_port_trace_k_work_cancel_exit(work, ret)
Trace cancel work call exit.

**Parameters**
- **work** – Work structure
- **ret** – Return value

sys_port_trace_k_work_cancel_sync_enter(work, sync)
Trace cancel sync work call entry.

**Parameters**
- **work** – Work structure
- **sync** – Sync object

sys_port_trace_k_work_cancel_sync_blocking(work, sync)
Trace cancel sync work call blocking.

**Parameters**
- **work** – Work structure
- **sync** – Sync object

sys_port_trace_k_work_cancel_sync_exit(work, sync, ret)
Trace cancel sync work call exit.

**Parameters**
- **work** – Work structure
- **sync** – Sync object
- **ret** – Return value

Poll

**group** subsys_tracingapis_poll
Poll Tracing APIs.

**Defines**

sys_port_trace_k_poll_api_event_init(event)
Trace initialisation of a Poll Event.

**Parameters**
- **event** – Poll Event

sys_port_trace_k_poll_api_poll_enter(events)
Trace Polling call start.

**Parameters**
- **events** – Poll Events
sys_port_trace_k_poll_api_poll_exit(events, ret)
  Trace Polling call outcome.
  **Parameters**
  - events – Poll Events
  - ret – Return value

sys_port_trace_k_poll_api_signal_init(signal)
  Trace initialisation of a Poll Signal.
  **Parameters**
  - signal – Poll Signal

sys_port_trace_k_poll_api_signal_reset(signal)
  Trace resetting of Poll Signal.
  **Parameters**
  - signal – Poll Signal

sys_port_trace_k_poll_api_signal_check(signal)
  Trace checking of Poll Signal.
  **Parameters**
  - signal – Poll Signal

sys_port_trace_k_poll_api_signal_raise(signal, ret)
  Trace raising of Poll Signal.
  **Parameters**
  - signal – Poll Signal
  - ret – Return value

**Semaphore**

group subsys_tracing_apis_sem
  Semaphore Tracing APIs.

**Defines**

sys_port_trace_k_sem_init(sem, ret)
  Trace initialisation of a Semaphore.
  **Parameters**
  - sem – Semaphore object
  - ret – Return value

sys_port_trace_k_sem_give_enter(sem)
  Trace giving a Semaphore entry.
  **Parameters**
  - sem – Semaphore object
sys_port_trace_k_sem_give_exit(sem)
  Trace giving a Semaphore exit.

  Parameters
  • sem – Semaphore object

sys_port_trace_k_sem_take_enter(sem, timeout)
  Trace taking a Semaphore attempt start.

  Parameters
  • sem – Semaphore object
  • timeout – Timeout period

sys_port_trace_k_sem_take_blocking(sem, timeout)
  Trace taking a Semaphore attempt blocking.

  Parameters
  • sem – Semaphore object
  • timeout – Timeout period

sys_port_trace_k_sem_take_exit(sem, timeout, ret)
  Trace taking a Semaphore attempt outcome.

  Parameters
  • sem – Semaphore object
  • timeout – Timeout period
  • ret – Return value

sys_port_trace_k_sem_reset(sem)
  Trace resetting a Semaphore.

  Parameters
  • sem – Semaphore object

Mutex

`group subsys_tracing_apis_mutex`

Mutex Tracing APIs.

Defines

sys_port_trace_k_mutex_init(mutex, ret)
  Trace initialization of Mutex.

  Parameters
  • mutex – Mutex object
  • ret – Return value

sys_port_trace_k_mutex_lock_enter(mutex, timeout)
  Trace Mutex lock attempt start.

  Parameters
  • mutex – Mutex object
timeout – Timeout period

\texttt{sys\_port\_trace\_k\_mutex\_lock\_blocking(mutex, timeout)}

Trace Mutex lock attempt blocking.

**Parameters**

- \texttt{mutex} – Mutex object
- \texttt{timeout} – Timeout period

\texttt{sys\_port\_trace\_k\_mutex\_lock\_exit(mutex, timeout, ret)}

Trace Mutex lock attempt outcome.

**Parameters**

- \texttt{mutex} – Mutex object
- \texttt{timeout} – Timeout period
- \texttt{ret} – Return value

\texttt{sys\_port\_trace\_k\_mutex\_unlock\_enter(mutex)}

Trace Mutex unlock entry.

**Parameters**

- \texttt{mutex} – Mutex object

\texttt{sys\_port\_trace\_k\_mutex\_unlock\_exit(mutex, ret)}

Trace Mutex unlock exit.

**Condition Variables**

**group** subsys\_tracing\_apis\_condvar

Conditional Variable Tracing APIs.

**Defines**

\texttt{sys\_port\_trace\_k\_condvar\_init(condvar, ret)}

Trace initialization of Conditional Variable.

**Parameters**

- \texttt{condvar} – Conditional Variable object
- \texttt{ret} – Return value

\texttt{sys\_port\_trace\_k\_condvar\_signal\_enter(condvar)}

Trace Conditional Variable signaling start.

**Parameters**

- \texttt{condvar} – Conditional Variable object

\texttt{sys\_port\_trace\_k\_condvar\_signal\_blocking(condvar, timeout)}

Trace Conditional Variable signaling blocking.

**Parameters**

- \texttt{condvar} – Conditional Variable object
- \texttt{timeout} – Timeout period

4.8. Tracing
sys_port_trace_k_condvar_signal_exit(condvar, ret)
  Trace Conditional Variable signaling outcome.
  
  **Parameters**
  - condvar – Conditional Variable object
  - ret – Return value

sys_port_trace_k_condvar_broadcast_enter(condvar)
  Trace Conditional Variable broadcast enter.
  
  **Parameters**
  - condvar – Conditional Variable object

sys_port_trace_k_condvar_broadcast_exit(condvar, ret)
  Trace Conditional Variable broadcast exit.
  
  **Parameters**
  - condvar – Conditional Variable object
  - ret – Return value

sys_port_trace_k_condvar_wait_enter(condvar)
  Trace Conditional Variable wait enter.
  
  **Parameters**
  - condvar – Conditional Variable object

sys_port_trace_k_condvar_wait_exit(condvar, ret)
  Trace Conditional Variable wait exit.
  
  **Parameters**
  - condvar – Conditional Variable object
  - ret – Return value

**Queues**

group subsys_tracing_apis_queue
  Queue Tracing APIs.

**Defines**

sys_port_trace_k_queue_init(queue)
  Trace initialization of Queue.
  
  **Parameters**
  - queue – Queue object

sys_port_trace_k_queue_cancel_wait(queue)
  Trace Queue cancel wait.
  
  **Parameters**
  - queue – Queue object
sys_port_trace_k_queue_queue_insert_enter(queue, alloc)
Trace Queue insert attempt entry.

Parameters
- queue – Queue object
- alloc – Allocation flag

sys_port_trace_k_queue_queue_insert_blocking(queue, alloc, timeout)
Trace Queue insert attempt blocking.

Parameters
- queue – Queue object
- alloc – Allocation flag
- timeout – Timeout period

sys_port_trace_k_queue_queue_insert_exit(queue, alloc, ret)
Trace Queue insert attempt outcome.

Parameters
- queue – Queue object
- alloc – Allocation flag
- ret – Return value

sys_port_trace_k_queue_append_enter(queue)
Trace Queue append enter.

Parameters
- queue – Queue object

sys_port_trace_k_queue_append_exit(queue)
Trace Queue append exit.

Parameters
- queue – Queue object

sys_port_trace_k_queue_alloc_append_enter(queue)
Trace Queue alloc append enter.

Parameters
- queue – Queue object

sys_port_trace_k_queue_alloc_append_exit(queue, ret)
Trace Queue alloc append exit.

Parameters
- queue – Queue object
- ret – Return value

sys_port_trace_k_queue_prepend_enter(queue)
Trace Queue prepend enter.

Parameters
- queue – Queue object

4.8. Tracing
sys_port_trace_k_queue_prepend_exit(queue)
   Trace Queue prepend exit.
   **Parameters**
   - queue – Queue object

sys_port_trace_k_queue_alloc_prepend_enter(queue)
   Trace Queue alloc prepend enter.
   **Parameters**
   - queue – Queue object

sys_port_trace_k_queue_alloc_prepend_exit(queue, ret)
   Trace Queue alloc prepend exit.
   **Parameters**
   - queue – Queue object
   - ret – Return value

sys_port_trace_k_queue_insert_enter(queue)
   Trace Queue insert attempt entry.
   **Parameters**
   - queue – Queue object

sys_port_trace_k_queue_insert_blocking(queue, timeout)
   Trace Queue insert attempt blocking.
   **Parameters**
   - queue – Queue object
   - timeout – Timeout period

sys_port_trace_k_queue_insert_exit(queue)
   Trace Queue insert attempt exit.
   **Parameters**
   - queue – Queue object

sys_port_trace_k_queue_append_list_enter(queue)
   Trace Queue append list enter.
   **Parameters**
   - queue – Queue object

sys_port_trace_k_queue_append_list_exit(queue, ret)
   Trace Queue append list exit.
   **Parameters**
   - queue – Queue object
   - ret – Return value

sys_port_trace_k_queue_merge_slist_enter(queue)
   Trace Queue merge slist enter.
   **Parameters**
   - queue – Queue object
sys_port_trace_k_queue_merge_slist_exit(queue, ret)
Trace Queue merge slist exit.

Parameters
• queue – Queue object
• ret – Return value

docs_port_trace_k_queue_get_enter(queue, timeout)
Trace Queue get attempt enter.

Parameters
• queue – Queue object
• timeout – Timeout period

docs_port_trace_k_queue_get_blocking(queue, timeout)
Trace Queue get attempt blockings.

Parameters
• queue – Queue object
• timeout – Timeout period

docs_port_trace_k_queue_get_exit(queue, timeout, ret)
Trace Queue get attempt outcome.

Parameters
• queue – Queue object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_queue_remove_enter(queue)
Trace Queue remove enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_remove_exit(queue, ret)
Trace Queue remove exit.

Parameters
• queue – Queue object
• ret – Return value

sys_port_trace_k_queue_unique_append_enter(queue)
Trace Queue unique append enter.

Parameters
• queue – Queue object

sys_port_trace_k_queue_unique_append_exit(queue, ret)
Trace Queue unique append exit.

Parameters
• queue – Queue object
• ret – Return value
sys_port_trace_k_queue.Peek head.

Parameters

- queue – Queue object
- ret – Return value

sys_port_trace_k_queue.Peek tail.

Parameters

- queue – Queue object
- ret – Return value

FIFO

group subsystem_tracingApis_fifo

FIFO Tracing APIs.

Defines

sys_port_trace_k_fifo.init.enter(fifo)

Trace initialization of FIFO Queue entry.

Parameters

- fifo – FIFO object

sys_port_trace_k_fifo.init.exit(fifo)

Trace initialization of FIFO Queue exit.

Parameters

- fifo – FIFO object

sys_port_trace_k_fifo.cancel.wait.enter(fifo)

Trace FIFO Queue cancel wait entry.

Parameters

- fifo – FIFO object

sys_port_trace_k_fifo.cancel.wait.exit(fifo)

Trace FIFO Queue cancel wait exit.

Parameters

- fifo – FIFO object

sys_port_trace_k_fifo.put.enter(fifo, data)

Trace FIFO Queue put entry.

Parameters

- fifo – FIFO object
- data – Data item
sys_port_trace_k_fifo_put_exit(fifo, data)
Trace FIFO Queue put exit.

**Parameters**
- fifo – FIFO object
- data – Data item

sys_port_trace_k_fifo_alloc_put_enter(fifo, data)
Trace FIFO Queue alloc put entry.

**Parameters**
- fifo – FIFO object
- data – Data item

sys_port_trace_k_fifo_alloc_put_exit(fifo, data, ret)
Trace FIFO Queue alloc put exit.

**Parameters**
- fifo – FIFO object
- data – Data item
- ret – Return value

sys_port_trace_k_fifo_put_list_enter(fifo, head, tail)
Trace FIFO Queue put list entry.

**Parameters**
- fifo – FIFO object
- head – First ll-node
- tail – Last ll-node

sys_port_trace_k_fifo_put_list_exit(fifo, head, tail)
Trace FIFO Queue put list exit.

**Parameters**
- fifo – FIFO object
- head – First ll-node
- tail – Last ll-node

sys_port_trace_k_fifo_alloc_put_slist_enter(fifo, list)
Trace FIFO Queue put slist entry.

**Parameters**
- fifo – FIFO object
- list – Syslist object

sys_port_trace_k_fifo_alloc_put_slist_exit(fifo, list)
Trace FIFO Queue put slist exit.

**Parameters**
- fifo – FIFO object
- list – Syslist object
sys_port_trace_k_fifo_get_enter(fifo, timeout)
Trace FIFO Queue get entry.

Parameters
• fifo – FIFO object
• timeout – Timeout period

sys_port_trace_k_fifo_get_exit(fifo, timeout, ret)
Trace FIFO Queue get exit.

Parameters
• fifo – FIFO object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_fifo_peek_head_entry(fifo)
Trace FIFO Queue peek head entry.

Parameters
• fifo – FIFO object

sys_port_trace_k_fifo_peek_head_exit(fifo, ret)
Trace FIFO Queue peek head exit.

Parameters
• fifo – FIFO object
• ret – Return value

sys_port_trace_k_fifo_peek_tail_entry(fifo)
Trace FIFO Queue peek tail entry.

Parameters
• fifo – FIFO object

sys_port_trace_k_fifo_peek_tail_exit(fifo, ret)
Trace FIFO Queue peek tail exit.

Parameters
• fifo – FIFO object
• ret – Return value

LIFO

group subsys_tracingApis_lifo
LIFO Tracing APIs.

Defines

sys_port_trace_k_lifo_init_enter(lifo)
Trace initialization of LIFO Queue entry.

Parameters
• lifo – LIFO object
sys_port_trace_k_lifo_init_exit(lifo)
Trace initialization of LIFO Queue exit.

Parameters
• lifo – LIFO object

sys_port_trace_k_lifo_put_enter(lifo, data)
Trace LIFO Queue put entry.

Parameters
• lifo – LIFO object
• data – Data item

sys_port_trace_k_lifo_put_exit(lifo, data)
Trace LIFO Queue put exit.

Parameters
• lifo – LIFO object
• data – Data item

sys_port_trace_k_lifo_alloc_put_enter(lifo, data)
Trace LIFO Queue alloc put entry.

Parameters
• lifo – LIFO object
• data – Data item

sys_port_trace_k_lifo_alloc_put_exit(lifo, data, ret)
Trace LIFO Queue alloc put exit.

Parameters
• lifo – LIFO object
• data – Data item
• ret – Return value

sys_port_trace_k_lifo_get_enter(lifo, timeout)
Trace LIFO Queue get entry.

Parameters
• lifo – LIFO object
• timeout – Timeout period

sys_port_trace_k_lifo_get_exit(lifo, timeout, ret)
Trace LIFO Queue get exit.

Parameters
• lifo – LIFO object
• timeout – Timeout period
• ret – Return value

Stacks

/group subsys_tracingapis_stack
Stack Tracing APIs.
Defines

sys_port_trace_k_stack_init(stack)
Trace initialization of Stack.

Parameters
  * stack – Stack object

sys_port_trace_k_stack_alloc_init_enter(stack)
Trace Stack alloc init attempt entry.

Parameters
  * stack – Stack object

sys_port_trace_k_stack_alloc_init_exit(stack, ret)
Trace Stack alloc init outcome.

Parameters
  * stack – Stack object
  * ret – Return value

sys_port_trace_k_stack_cleanup_enter(stack)
Trace Stack cleanup attempt entry.

Parameters
  * stack – Stack object

sys_port_trace_k_stack_cleanup_exit(stack, ret)
Trace Stack cleanup outcome.

Parameters
  * stack – Stack object
  * ret – Return value

sys_port_trace_k_stack_push_enter(stack)
Trace Stack push attempt entry.

Parameters
  * stack – Stack object

sys_port_trace_k_stack_push_exit(stack, ret)
Trace Stack push attempt outcome.

Parameters
  * stack – Stack object
  * ret – Return value

sys_port_trace_k_stack_pop_enter(stack, timeout)
Trace Stack pop attempt entry.

Parameters
  * stack – Stack object
  * timeout – Timeout period
sys_port_trace_k_stack_pop_blocking(stack, timeout)
Trace Stack pop attempt blocking.

Parameters
• stack – Stack object
• timeout – Timeout period

sys_port_trace_k_stack_pop_exit(stack, timeout, ret)
Trace Stack pop attempt outcome.

Parameters
• stack – Stack object
• timeout – Timeout period
• ret – Return value

Message Queues

group subsys_tracing_apis_msgq
Message Queue Tracing APIs.

Defines

sys_port_trace_k_msgq_init(msgq)
Trace initialization of Message Queue.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_alloc_init_enter(msgq)
Trace Message Queue alloc init attempt entry.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_alloc_init_exit(msgq, ret)
Trace Message Queue alloc init attempt outcome.

Parameters
• msgq – Message Queue object
• ret – Return value

sys_port_trace_k_msgq_cleanup_enter(msgq)
Trace Message Queue cleanup attempt entry.

Parameters
• msgq – Message Queue object

sys_port_trace_k_msgq_cleanup_exit(msgq, ret)
Trace Message Queue cleanup attempt outcome.

Parameters
• msgq – Message Queue object
• ret – Return value
sys_port_trace_k_msgq_put_enter(msgq, timeout)
   Trace Message Queue put attempt entry.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period

sys_port_trace_k_msgq_put_blocking(msgq, timeout)
   Trace Message Queue put attempt blocking.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period

sys_port_trace_k_msgq_put_exit(msgq, timeout, ret)
   Trace Message Queue put attempt outcome.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period
   • ret – Return value

sys_port_trace_k_msgq_get_enter(msgq, timeout)
   Trace Message Queue get attempt entry.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period

sys_port_trace_k_msgq_get_blocking(msgq, timeout)
   Trace Message Queue get attempt blockings.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period

sys_port_trace_k_msgq_get_exit(msgq, timeout, ret)
   Trace Message Queue get attempt outcome.

Parameters
   • msgq – Message Queue object
   • timeout – Timeout period
   • ret – Return value

sys_port_trace_k_msgq_peek(msgq, ret)
   Trace Message Queue peek.

Parameters
   • msgq – Message Queue object
   • ret – Return value

sys_port_trace_k_msgq_purge(msgq)
   Trace Message Queue purge.

Parameters
   • msgq – Message Queue object
Mailbox

group subsys_tracing.Apis_mbox
Mailbox Tracing APIs.

Defines

sys_port_trace_k_mbox_init(mbox)
Trace initialization of Mailbox.

Parameters
• mbox – Mailbox object

sys_port_trace_k_mbox_message_put_enter(mbox, timeout)
Trace Mailbox message put attempt entry.

Parameters
• mbox – Mailbox object
• timeout – Timeout period

sys_port_trace_k_mbox_message_put_blocking(mbox, timeout)
Trace Mailbox message put attempt blocking.

Parameters
• mbox – Mailbox object
• timeout – Timeout period

sys_port_trace_k_mbox_message_put_exit(mbox, timeout, ret)
Trace Mailbox message put attempt outcome.

Parameters
• mbox – Mailbox object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_mbox_put_enter(mbox, timeout)
Trace Mailbox put attempt entry.

Parameters
• mbox – Mailbox object
• timeout – Timeout period

sys_port_trace_k_mbox_put_exit(mbox, timeout, ret)
Trace Mailbox put attempt blocking.

Parameters
• mbox – Mailbox object
• timeout – Timeout period
• ret – Return value
sys_port_trace_k_mbox_async_put_enter(mbox, sem)
Trace Mailbox async put entry.

Parameters
• mbox – Mailbox object
• sem – Semaphore object

sys_port_trace_k_mbox_async_put_exit(mbox, sem)
Trace Mailbox async put exit.

Parameters
• mbox – Mailbox object
• sem – Semaphore object

sys_port_trace_k_mbox_get_enter(mbox, timeout)
Trace Mailbox get attempt entry.

Parameters
• mbox – Mailbox entry
• timeout – Timeout period

sys_port_trace_k_mbox_get_blocking(mbox, timeout)
Trace Mailbox get attempt blocking.

Parameters
• mbox – Mailbox entry
• timeout – Timeout period

sys_port_trace_k_mbox_get_exit(mbox, timeout, ret)
Trace Mailbox get attempt outcome.

Parameters
• mbox – Mailbox entry
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_mbox_data_get(rx_msg)
Trace Mailbox data get.

rx_msg Receive Message object

Pipes

group subsys_tracing.Apis_pipe
Pipe Tracing APIs.

Defines

sys_port_trace_k_pipe_init(pipe)
Trace initialization of Pipe.

Parameters
• pipe – Pipe object
sys_port_trace_k_pipe_cleanup_enter(pipe)
  Trace Pipe cleanup entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_cleanup_exit(pipe, ret)
  Trace Pipe cleanup exit.

  Parameters
  • pipe – Pipe object
  • ret – Return value

sys_port_trace_k_pipe_alloc_init_enter(pipe)
  Trace Pipe alloc init entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_alloc_init_exit(pipe, ret)
  Trace Pipe alloc init exit.

  Parameters
  • pipe – Pipe object
  • ret – Return value

sys_port_trace_k_pipe_flush_enter(pipe)
  Trace Pipe flush entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_flush_exit(pipe)
  Trace Pipe flush exit.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_buffer_flush_enter(pipe)
  Trace Pipe buffer flush entry.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_buffer_flush_exit(pipe)
  Trace Pipe buffer flush exit.

  Parameters
  • pipe – Pipe object

sys_port_trace_k_pipe_put_enter(pipe, timeout)
  Trace Pipe put attempt entry.

  Parameters
  • pipe – Pipe object
  • timeout – Timeout period
sys_port_trace_k_pipe_put_blocking(pipe, timeout)
Trace Pipe put attempt blocking.

Parameters
• pipe – Pipe object
• timeout – Timeout period

sys_port_trace_k_pipe_put_exit(pipe, timeout, ret)
Trace Pipe put attempt outcome.

Parameters
• pipe – Pipe object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_pipe_get_enter(pipe, timeout)
Trace Pipe get attempt entry.

Parameters
• pipe – Pipe object
• timeout – Timeout period

sys_port_trace_k_pipe_get_blocking(pipe, timeout)
Trace Pipe get attempt blocking.

Parameters
• pipe – Pipe object
• timeout – Timeout period

sys_port_trace_k_pipe_get_exit(pipe, timeout, ret)
Trace Pipe get attempt outcome.

Parameters
• pipe – Pipe object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_pipe_block_put_enter(pipe, sem)
Trace Pipe block put enter.

Parameters
• pipe – Pipe object
• sem – Semaphore object

sys_port_trace_k_pipe_block_put_exit(pipe, sem)
Trace Pipe block put exit.

Parameters
• pipe – Pipe object
• sem – Semaphore object
Heaps

group subsys_tracing.Apis_heap

Heap Tracing APIs.

Defines

sys_port_trace_k_heap_init(h)

Trace initialization of Heap.

Parameters
• h – Heap object

sys_port_trace_k_heapAligned_alloc_enter(h, timeout)

Trace Heap aligned alloc attempt entry.

Parameters
• h – Heap object
• timeout – Timeout period

sys_port_trace_k_heapAligned_alloc_blocking(h, timeout)

Trace Heap align alloc attempt blocking.

Parameters
• h – Heap object
• timeout – Timeout period

sys_port_trace_k_heapAligned_alloc_exit(h, timeout, ret)

Trace Heap align alloc attempt outcome.

Parameters
• h – Heap object
• timeout – Timeout period
• ret – Return value

sys_port_trace_k_heap_alloc enter(h, timeout)

Trace Heap alloc enter.

Parameters
• h – Heap object
• timeout – Timeout period

sys_port_trace_k_heap_alloc exit(h, timeout, ret)

Trace Heap alloc exit.

Parameters
• h – Heap object
• timeout – Timeout period
• ret – Return value
sys_port_trace_k_heap_free(h)
Trace Heap free.

Parameters
• h – Heap object

sys_port_trace_k_heap_sys_k_aligned_alloc_enter(heap)
Trace System Heap aligned alloc enter.

Parameters
• heap – Heap object

sys_port_trace_k_heap_sys_k_aligned_alloc_exit(heap, ret)
Trace System Heap aligned alloc exit.

Parameters
• heap – Heap object
• ret – Return value

sys_port_trace_k_heap_sys_k_malloc_enter(heap)
Trace System Heap aligned alloc enter.

Parameters
• heap – Heap object

sys_port_trace_k_heap_sys_k_malloc_exit(heap, ret)
Trace System Heap aligned alloc exit.

Parameters
• heap – Heap object
• ret – Return value

sys_port_trace_k_heap_sys_k_free_enter(heap, heap_ref)
Trace System Heap free entry.

Parameters
• heap – Heap object
• heap_ref – Heap reference

sys_port_trace_k_heap_sys_k_free_exit(heap, heap_ref)
Trace System Heap free exit.

Parameters
• heap – Heap object
• heap_ref – Heap reference

sys_port_trace_k_heap_sys_k_calloc_enter(heap)
Trace System heap calloc enter.

Parameters
• heap –

sys_port_trace_k_heap_sys_k_calloc_exit(heap, ret)
Trace System heap calloc exit.

Parameters
• heap – Heap object
• ret – Return value
Memory Slabs

`group subsys_tracing_apis_mslab`
Memory Slab Tracing APIs.

**Defines**

`sys_port_trace_k_mem_slab_init(slab, rc)`
Trace initialization of Memory Slab.

**Parameters**
- `slab` – Memory Slab object
- `rc` – Return value

`sys_port_trace_k_mem_slab_alloc_enter(slab, timeout)`
Trace Memory Slab alloc attempt entry.

**Parameters**
- `slab` – Memory Slab object
- `timeout` – Timeout period

`sys_port_trace_k_mem_slab_alloc_blocking(slab, timeout)`
Trace Memory Slab alloc attempt blocking.

**Parameters**
- `slab` – Memory Slab object
- `timeout` – Timeout period

`sys_port_trace_k_mem_slab_alloc_exit(slab, timeout, ret)`
Trace Memory Slab alloc attempt outcome.

**Parameters**
- `slab` – Memory Slab object
- `timeout` – Timeout period
- `ret` – Return value

`sys_port_trace_k_mem_slab_free_enter(slab)`
Trace Memory Slab free entry.

**Parameters**
- `slab` – Memory Slab object

`sys_port_trace_k_mem_slab_free_exit(slab)`
Trace Memory Slab free exit.

**Parameters**
- `slab` – Memory Slab object

Timers

`group subsys_tracing_apis_timer`
Timer Tracing APIs.
Defines

```c
sys_port_trace_k_timer_init(timer)
    Trace initialization of Timer.

Parameters
    • timer – Timer object
```

```c
sys_port_trace_k_timer_start(timer, duration, period)
    Trace Timer start.

Parameters
    • timer – Timer object
    • duration – Timer duration
    • period – Timer period
```

```c
sys_port_trace_k_timer_stop(timer)
    Trace Timer stop.

Parameters
    • timer – Timer object
```

```c
sys_port_trace_k_timer_status_sync_enter(timer)
    Trace Timer status sync entry.

Parameters
    • timer – Timer object
```

```c
sys_port_trace_k_timer_status_sync_blocking(timer, timeout)
    Trace Timer Status sync blocking.

Parameters
    • timer – Timer object
    • timeout – Timeout period
```

```c
sys_port_trace_k_timer_status_sync_exit(timer, result)
    Trace Time Status sync outcome.

Parameters
    • timer – Timer object
    • result – Return value
```

Object tracking

```c
group subsys_tracing_object_tracking
    Object tracking.
```

Object tracking provides lists to kernel objects, so their existence and current status can be tracked. The following global variables are the heads of available lists:

```c
• _track_list_k_timer
• _track_list_k_mem_slab
• _track_list_k_sem
• _track_list_k_mutex
```
• _track_list_k_stack
• _track_list_k_msgq
• _track_list_k_mbox
• _track_list_k_pipe
• _track_list_k_queue

Defines

SYS_PORT_TRACK_NEXT(list)
Gets node's next element in an object tracking list.

Parameters

• list – Node to get next element from.

Syscalls

group subsys_tracing_apis_syscall
Syscall Tracing APIs.

Defines

sys_port_trace_syscall_enter(id, name, ...)
Trace syscall entry.

Parameters

• id – Syscall ID (as defined in the generated syscall_list.h)
• name – Syscall name as a token (ex: k_thread_create)
• ... – Other parameters passed to the syscall

sys_port_trace_syscall_exit(id, name, ...)
Trace syscall exit.

Parameters

• id – Syscall ID (as defined in the generated syscall_list.h)
• name – Syscall name as a token (ex: k_thread_create)
• ... – Other parameters passed to the syscall, if the syscall has a return, the return value is the last parameter in the list

4.9 Resource Management

There are various situations where it's necessary to coordinate resource use at runtime among multiple clients. These include power rails, clocks, other peripherals, and binary device power management. The complexity of properly managing multiple consumers of a device in a multithreaded system, especially when transitions may be asynchronous, suggests that a shared implementation is desirable.

Zephyr provides managers for several coordination policies. These managers are embedded into services that use them for specific functions.
4.9.1 On-Off Manager

An on-off manager supports an arbitrary number of clients of a service which has a binary state. Example applications are power rails, clocks, and binary device power management.

The manager has the following properties:

- The stable states are off, on, and error. The service always begins in the off state. The service may also be in a transition to a given state.
- The core operations are request (add a dependency) and release (remove a dependency). Supporting operations are reset (to clear an error state) and cancel (to reclaim client data from an in-progress transition). The service manages the state based on calls to functions that initiate these operations.
- The service transitions from off to on when first client request is received.
- The service transitions from on to off when last client release is received.
- Each service configuration provides functions that implement the transition from off to on, from on to off, and optionally from an error state to off. Transitions must be invokable from both thread and interrupt context.
- The request and reset operations are asynchronous using Asynchronous Notifications. Both operations may be cancelled, but cancellation has no effect on the in-progress transition.
- Requests to turn on may be queued while a transition to off is in progress: when the service has turned off successfully it will be immediately turned on again (where context allows) and waiting clients notified when the start completes.

Requests are reference counted, but not tracked. That means clients are responsible for recording whether their requests were accepted, and for initiating a release only if they have previously successfully completed a request. Improper use of the API can cause an active client to be shut out, and the manager does not maintain a record of specific clients that have been granted a request.

Failures in executing a transition are recorded and inhibit further requests or releases until the manager is reset. Pending requests are notified (and cancelled) when errors are discovered.

Transition operation completion notifications are provided through Asynchronous Notifications.

Clients and other components interested in tracking all service state changes, including when a service begins turning off or enters an error state, can be informed of state transitions by registering a monitor with onoff_monitor_register(). Notification of changes are provided before issuing completion notifications associated with the new state.

Note: A generic API may be implemented by multiple drivers where the common case is asynchronous. The on-off client structure may be an appropriate solution for the generic API. Where drivers that can guarantee synchronous context-independent transitions a driver may use onoff_sync_service and its supporting API rather than onoff_manager, with only a small reduction in functionality (primarily no support for the monitor API).

defines group resource_mgmt_onoff_apis
ONOFF_FLAG_ERROR
Flag indicating an error state.
Error states are cleared using onoff_reset().

ONOFF_FLAG_ONOFF

ONOFF_FLAG_TRANSITION

ONOFF_STATE_MASK
Mask used to isolate bits defining the service state.
Mask a value with this then test for ONOFF_FLAG_ERROR to determine whether the machine has an unfixed error, or compare against ONOFF_STATE_ON, ONOFF_STATE_OFF, ONOFF_STATE_TO_ON, ONOFF_STATE_TO_OFF, or ONOFF_STATE_RESETTING.

ONOFF_STATE_OFF
Value exposed by ONOFF_STATE_MASK when service is off.

ONOFF_STATE_ON
Value exposed by ONOFF_STATE_MASK when service is on.

ONOFF_STATE_ERROR
Value exposed by ONOFF_STATE_MASK when the service is in an error state (and not in the process of resetting its state).

ONOFF_STATE_TO_ON
Value exposed by ONOFF_STATE_MASK when service is transitioning to on.

ONOFF_STATE_TO_OFF
Value exposed by ONOFF_STATE_MASK when service is transitioning to off.

ONOFF_STATE_RESETTING
Value exposed by ONOFF_STATE_MASK when service is in the process of resetting.

ONOFF_TRANSITIONS_INITIALIZER(_start, _stop, _reset)
Initializer for a onoff_transitions object.

Parameters
• _start – a function used to transition from off to on state.
• _stop – a function used to transition from on to off state.
• _reset – a function used to clear errors and force the service to an off state. Can be null.

ONOFF_MANAGER_INITIALIZER(_transitions)

ONOFF_CLIENT_EXTENSION_POS
Identify region of sys_notify flags available for containing services.
Bits of the flags field of the sys_notify structure contained within the queued_operation structure at and above this position may be used by extensions to the onoff_client structure.
These bits are intended for use by containing service implementations to record client-specific information and are subject to other conditions of use specified on the sys_notify API.
Typedefs

typedef void (\*onoff_notify_fn)(struct onoff_manager *mgr, int res)

Signature used to notify an on-off manager that a transition has completed.

Functions of this type are passed to service-specific transition functions to be used to report
the completion of the operation. The functions may be invoked from any context.

**Param mgr**
the manager for which transition was requested.

**Param res**
the result of the transition. This shall be non-negative on success, or a negative
error code. If an error is indicated the service shall enter an error state.

typedef void (\*onoff_transition_fn)(struct onoff_manager *mgr, onoff_notify_fn notify)

Signature used by service implementations to effect a transition.

Service definitions use two required function pointers of this type to be notified that a transi-
tion is required, and a third optional one to reset the service when it is in an error state.
The start function will be called only from the off state.
The stop function will be called only from the on state.
The reset function (where supported) will be called only when onoff_has_error() returns true.

**Note:** All transitions functions must be isr-ok.

**Param mgr**
the manager for which transition was requested.

**Param notify**
the function to be invoked when the transition has completed. If the transition is
synchronous, notify shall be invoked by the implementation before the transition
function returns. Otherwise the implementation shall capture this parameter and
invoke it when the transition completes.

typedef void (\*onoff_client_callback)(struct onoff_manager *mgr, struct onoff_client *cli,
uint32_t state, int res)

Signature used to notify an on-off service client of the completion of an operation.

These functions may be invoked from any context including pre-kernel, ISR, or cooperative or
pre-emptible threads. Compatible functions must be isr-ok and not sleep.

**Param mgr**
the manager for which the operation was initiated. This may be null if the on-off
service uses synchronous transitions.

**Param cli**
the client structure passed to the function that initiated the operation.

**Param state**
the state of the machine at the time of completion, restricted by
ONOFF_STATE_MASK. ONOFF_FLAG_ERROR must be checked independently of
whether res is negative as a machine error may indicate that all future operations
except onoff_reset() will fail.

**Param res**
the result of the operation. Expected values are service-specific, but the value
shall be non-negative if the operation succeeded, and negative if the operation failed. If res is negative ONOFF_FLAG_ERROR will be set in state, but if res is non-negative ONOFF_FLAG_ERROR may still be set in state.

typedef void (*onoff_monitor_callback)(struct onoff_manager *mgr, struct onoff_monitor *mon, uint32_t state, int res)

Signature used to notify a monitor of an onoff service of errors or completion of a state transition.

This is similar to onoff_client_callback but provides information about all transitions, not just ones associated with a specific client. Monitor callbacks are invoked before any completion notifications associated with the state change are made.

These functions may be invoked from any context including pre-kernel, ISR, or cooperative or pre-emptible threads. Compatible functions must be isr-ok and not sleep.

The callback is permitted to unregister itself from the manager, but must not register or unregister any other monitors.

Param mgr
the manager for which a transition has completed.

Param mon
the monitor instance through which this notification arrived.

Param state
the state of the machine at the time of completion, restricted by ONOFF_STATE_MASK. All valid states may be observed.

Param res
the result of the operation. Expected values are service- and state-specific, but the value shall be non-negative if the operation succeeded, and negative if the operation failed.

Functions

int onoff_manager_init(struct onoff_manager *mgr, const struct onoff_transitions *transitions)
Initialize an on-off service to off state.

This function must be invoked exactly once per service instance, by the infrastructure that provides the service, and before any other on-off service API is invoked on the service.

This function should never be invoked by clients of an on-off service.

Parameters

• mgr – the manager definition object to be initialized.
• transitions – pointer to a structure providing transition functions. The referenced object must persist as long as the manager can be referenced.

Return values

• 0 – on success
• -EINVAL – if start, stop, or flags are invalid

static inline bool onoff_has_error(const struct onoff_manager *mgr)
Test whether an on-off service has recorded an error.

This function can be used to determine whether the service has recorded an error. Errors may be cleared by invoking onoff_reset().

This is an unlocked convenience function suitable for use only when it is known that no other process might invoke an operation that transitions the service between an error and non-error state.
Returns
true if and only if the service has an uncleared error.

```c
int onoff_request(struct onoff_manager *mgr, struct onoff_client *cli)
```
Request a reservation to use an on-off service.

The return value indicates the success or failure of an attempt to initiate an operation to request the resource be made available. If initiation of the operation succeeds the result of the request operation is provided through the configured client notification method, possibly before this call returns.

Note that the call to this function may succeed in a case where the actual request fails. Always check the operation completion result.

**Parameters**
- `mgr` – the manager that will be used.
- `cli` – a non-null pointer to client state providing instructions on synchronous expectations and how to notify the client when the request completes. Behavior is undefined if client passes a pointer object associated with an incomplete service operation.

**Return values**
- non-negative – the observed state of the machine at the time the request was processed, if successful.
- -EIO – if service has recorded an error.
- -EINVAL – if the parameters are invalid.
- -EAGAIN – if the reference count would overflow.

```c
int onoff_release(struct onoff_manager *mgr)
```
Release a reserved use of an on-off service.

This synchronously releases the caller's previous request. If the last request is released the manager will initiate a transition to off, which can be observed by registering an `onoff_monitor`.

**Note:** Behavior is undefined if this is not paired with a preceding `onoff_request()` call that completed successfully.

**Parameters**
- `mgr` – the manager for which a request was successful.

**Return values**
- non-negative – the observed state (ONOFF_STATE_ON) of the machine at the time of the release, if the release succeeds.
- -EIO – if service has recorded an error.
- -ENOTSUP – if the machine is not in a state that permits release.

```c
int onoff_cancel(struct onoff_manager *mgr, struct onoff_client *cli)
```
Attempt to cancel an in-progress client operation.

It may be that a client has initiated an operation but needs to shut down before the operation has completed. For example, when a request was made and the need is no longer present.

Cancelling is supported only for `onoff_request()` and `onoff_reset()` operations, and is a synchronous operation. Be aware that any transition that was initiated on behalf of the client will continue to progress to completion: it is only notification of transition completion that
may be eliminated. If there are no active requests when a transition to on completes the manager will initiate a transition to off.

Client notification does not occur for cancelled operations.

**Parameters**
- `mgr` – the manager for which an operation is to be cancelled.
- `cli` – a pointer to the same client state that was provided when the operation to be cancelled was issued.

**Return values**
- `non-negative` – the observed state of the machine at the time of the cancellation, if the cancellation succeeds. On successful cancellation ownership of `cli` reverts to the client.
- `-EINVAL` – if the parameters are invalid.
- `-EALREADY` – if `cli` was not a record of an uncompleted notification at the time the cancellation was processed. This likely indicates that the operation and client notification had already completed.

```c
static inline int onoff_cancel_or_release(struct onoff_manager *mgr, struct onoff_client *cli)
```

Helper function to safely cancel a request.

Some applications may want to issue requests on an asynchronous event (such as connection to a USB bus) and to release on a paired event (such as loss of connection to a USB bus). Applications cannot precisely determine that an in-progress request is still pending without using `onoff_monitor` and carefully avoiding race conditions.

This function is a helper that attempts to cancel the operation and issues a release if cancellation fails because the request was completed. This synchronously ensures that ownership of the client data reverts to the client so is available for a future request.

**Parameters**
- `mgr` – the manager for which an operation is to be cancelled.
- `cli` – a pointer to the same client state that was provided when `onoff_request()` was invoked. Behavior is undefined if this is a pointer to client data associated with an `onoff_reset()` request.

**Return values**
- `ONOFF_STATE_TO_ON` – if the cancellation occurred before the transition completed.
- `ONOFF_STATE_ON` – if the cancellation occurred after the transition completed.
- `-EINVAL` – if the parameters are invalid.
- `negative` – other errors produced by `onoff_release()`.

```c
int onoff_reset(struct onoff_manager *mgr, struct onoff_client *cli)
```

Clear errors on an on-off service and reset it to its off state.

A service can only be reset when it is in an error state as indicated by `onoff_has_error()`.

The return value indicates the success or failure of an attempt to initiate an operation to reset the resource. If initiation of the operation succeeds the result of the reset operation itself is provided through the configured client notification method, possibly before this call returns. Multiple clients may request a reset; all are notified when it is complete.

Note that the call to this function may succeed in a case where the actual reset fails. Always check the operation completion result.
Due to the conditions on state transition all incomplete asynchronous operations will have been informed of the error when it occurred. There need be no concern about dangling requests left after a reset completes.

Parameters
- `mgr` – the manager to be reset.
- `cli` – pointer to client state, including instructions on how to notify the client when reset completes. Behavior is undefined if cli references an object associated with an incomplete service operation.

Return values
- non-negative – the observed state of the machine at the time of the reset, if the reset succeeds.
- -ENOTSUP – if reset is not supported by the service.
- -EINVAL – if the parameters are invalid.
- -EALREADY – if the service does not have a recorded error.

```c
int onoff_monitor_register(struct onoff_manager *mgr, struct onoff_monitor *mon)
```
Add a monitor of state changes for a manager.

Parameters
- `mgr` – the manager for which a state changes are to be monitored.
- `mon` – a linkable node providing a non-null callback to be invoked on state changes.

Returns
non-negative on successful addition, or a negative error code.

```c
int onoff_monitor_unregister(struct onoff_manager *mgr, struct onoff_monitor *mon)
```
Remove a monitor of state changes from a manager.

Parameters
- `mgr` – the manager for which a state changes are to be monitored.
- `mon` – a linkable node providing the callback to be invoked on state changes.

Returns
non-negative on successful removal, or a negative error code.

```c
int onoff_sync_lock(struct onoff_sync_service *srv, k_spinlock_key_t *keyp)
```
Lock a synchronous onoff service and provide its state.

Note: If an error state is returned it is the caller's responsibility to decide whether to preserve it (finalize with the same error state) or clear the error (finalize with a non-error result).

Parameters
- `srv` – pointer to the synchronous service state.
- `keyp` – pointer to where the lock key should be stored.

Returns
negative if the service is in an error state, otherwise the number of active requests at the time the lock was taken. The lock is held on return regardless of whether a negative state is returned.
int onoff_sync_finalize(struct onoff_sync_service *srv, k_spinlock_key_t key, struct onoff_client *cli, int res, bool on)

Process the completion of a transition in a synchronous service and release lock.

This function updates the service state on the res and on parameters then releases the lock. If cli is not null it finalizes the client notification using res.

If the service was in an error state when locked, and res is non-negative when finalized, the count is reset to zero before completing finalization.

Parameters

- srv – pointer to the synchronous service state
- key – the key returned by the preceding invocation of onoff_sync_lock().
- cli – pointer to the onoff client through which completion information is returned. If a null pointer is passed only the state of the service is updated. For compatibility with the behavior of callbacks used with the manager API cli must be null when on is false (the manager does not support callbacks when turning off devices).
- res – the result of the transition. A negative value places the service into an error state. A non-negative value increments or decrements the reference count as specified by on.
- on – Only when res is non-negative, the service reference count will be incremented if on is true, and decremented if on is false.

Returns

negative if the service is left or put into an error state, otherwise the number of active requests at the time the lock was released.

struct onoff_transitions

#include <onoff.h> On-off service transition functions.

struct onoff_manager

#include <onoff.h> State associated with an on-off manager.

No fields in this structure are intended for use by service providers or clients. The state is to be initialized once, using onoff_manager_init(), when the service provider is initialized. In case of error it may be reset through the onoff_reset() API.

struct onoff_client

#include <onoff.h> State associated with a client of an on-off service.

Objects of this type are allocated by a client, which is responsible for zero-initializing the node field and invoking the appropriate sys_notify init function to configure notification.

Control of the object content transfers to the service provider when a pointer to the object is passed to any on-off manager function. While the service provider controls the object the client must not change any object fields. Control reverts to the client concurrent with release of the owned sys_notify structure, or when indicated by an onoff_cancel() return value.

After control has reverted to the client the notify field must be reinitialized for the next operation.

Public Members

struct sys_notify notify

Notification configuration.
struct onoff_monitor

#include <onoff.h> Registration state for notifications of onoff service transitions.

Any given onoff_monitor structure can be associated with at most one onoff_manager instance.

Public Members

onoff_monitor_callback callback

Callback to be invoked on state change.

This must not be null.

struct onoff_sync_service

#include <onoff.h> State used when a driver uses the on-off service API for synchronous operations.

This is useful when a subsystem API uses the on-off API to support asynchronous operations but the transitions required by a particular driver are isr-ok and not sleep. It serves as a substitute for onoff_manager, with locking and persisted state updates supported by onoff_sync_lock() and onoff_sync_finalize().

4.10 Modbus

Modbus is an industrial messaging protocol. The protocol is specified for different types of networks or buses. Zephyr OS implementation supports communication over serial line and may be used with different physical interfaces, like RS485 or RS232. TCP support is not implemented directly, but there are helper functions to realize TCP support according to the application's needs.

Modbus communication is based on client/server model. Only one client may be present on the bus. Client can communicate with several server devices. Server devices themselves are passive and must not send requests or unsolicited responses. Services requested by the client are specified by function codes (FCxx), and can be found in the specification or documentation of the API below.

Zephyr RTOS implementation supports both client and server roles.

More information about Modbus and Modbus RTU can be found on the website MODBUS Protocol Specifications.

4.10.1 Samples

modbus-rtu-server-sample and modbus-rtu-client-sample give the possibility to try out RTU server and RTU client implementation with an evaluation board.

modbus-tcp-server-sample is a simple Modbus TCP server.

modbus-gateway-sample is an example how to build a TCP to serial line gateway with Zephyr OS.

4.10.2 API Reference

group modbus

MODBUS transport protocol API.
**Defines**

MODBUS_MBAP_LENGTH
Length of MBAP Header

MODBUS_MBAP_AND_FC_LENGTH
Length of MBAP Header plus function code

**Typedefs**

typedef int (*modbus_raw_cb_t)(const int iface, const struct modbus_adu *adu, void *user_data)
ADU raw callback function signature.

- **Param iface**
  Modbus RTU interface index

- **Param adu**
  Pointer to the RAW ADU struct to send

- **Param user_data**
  Pointer to the user data

- **Retval 0**
  If transfer was successful

**Enums**

class modbus_mode
Modbus interface mode.

**Values:**

class enumerator MODBUS_MODE_RTU
  Modbus over serial line RTU mode

class enumerator MODBUS_MODE_ASCII
  Modbus over serial line ASCII mode

class enumerator MODBUS_MODE_RAW
  Modbus raw ADU mode

**Functions**

int modbus_read_coils(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint8_t *const coil_tbl, const uint16_t num_coils)
Coil read (FC01)
Sends a Modbus message to read the status of coils from a server.

**Parameters**

- **iface** – Modbus interface index
- **unit_id** – Modbus unit ID of the server
• start_addr – Coil starting address

• coil_tbl – Pointer to an array of bytes containing the value of the coils read. The format is:

<table>
<thead>
<tr>
<th>MSB</th>
<th>LSB</th>
</tr>
</thead>
<tbody>
<tr>
<td>B7</td>
<td>B6</td>
</tr>
<tr>
<td>B5</td>
<td>B4</td>
</tr>
<tr>
<td>B3</td>
<td>B2</td>
</tr>
<tr>
<td>B1</td>
<td>B0</td>
</tr>
</tbody>
</table>

| coil_tbl[0] | #8 #7 | #1 |
| coil_tbl[1] | #16 #15 | #9 |
| :           | :     | :  |

Note that the array that will be receiving the coil values must be greater than or equal to: \((\text{num\_coils} - 1) / 8 + 1\)

• num_coils – Quantity of coils to read

Return values

0 – If the function was successful

```c
int modbus_read_dinputs(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint8_t *const di_tbl, const uint16_t num_di)
```

Read discrete inputs (FC02)

Sends a Modbus message to read the status of discrete inputs from a server.

Parameters

• iface – Modbus interface index

• unit_id – Modbus unit ID of the server

• start_addr – Discrete input starting address

• di_tbl – Pointer to an array that will receive the state of the discrete inputs. The format of the array is as follows:

<table>
<thead>
<tr>
<th>MSB</th>
<th>LSB</th>
</tr>
</thead>
<tbody>
<tr>
<td>B7</td>
<td>B6</td>
</tr>
<tr>
<td>B5</td>
<td>B4</td>
</tr>
<tr>
<td>B3</td>
<td>B2</td>
</tr>
<tr>
<td>B1</td>
<td>B0</td>
</tr>
</tbody>
</table>

| di_tbl[0] | #8 #7 | #1 |
| di_tbl[1] | #16 #15 | #9 |
| :           | :     | :  |

Note that the array that will be receiving the discrete input values must be greater than or equal to: \((\text{num\_di} - 1) / 8 + 1\)

• num_di – Quantity of discrete inputs to read

Return values

0 – If the function was successful

```c
int modbus_read_holding_regs(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint16_t *const reg_buf, const uint16_t num_regs)
```

Read holding registers (FC03)

Sends a Modbus message to read the value of holding registers from a server.

Parameters

• iface – Modbus interface index

• unit_id – Modbus unit ID of the server

• start_addr – Register starting address
• `reg_buf` – Is a pointer to an array that will receive the current values of the holding registers from the server. The array pointed to by `reg_buf` needs to be able to hold at least `num_regs` entries.

• `num_regs` – Quantity of registers to read

**Return values**

- `0` – If the function was successful

```c
int modbus_read_input_regs(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint16_t *const reg_buf, const uint16_t num_regs)
```

Read input registers (FC04)

Sends a Modbus message to read the value of input registers from a server.

**Parameters**

- `iface` – Modbus interface index
- `unit_id` – Modbus unit ID of the server
- `start_addr` – Register starting address
- `reg_buf` – Is a pointer to an array that will receive the current value of the holding registers from the server. The array pointed to by `reg_buf` needs to be able to hold at least `num_regs` entries.
- `num_regs` – Quantity of registers to read

**Return values**

- `0` – If the function was successful

```c
int modbus_write_coil(const int iface, const uint8_t unit_id, const uint16_t coil_addr, const bool coil_state)
```

Write single coil (FC05)

Sends a Modbus message to write the value of single coil to a server.

**Parameters**

- `iface` – Modbus interface index
- `unit_id` – Modbus unit ID of the server
- `coil_addr` – Coils starting address
- `coil_state` – Is the desired state of the coil

**Return values**

- `0` – If the function was successful

```c
int modbus_write_holding_reg(const int iface, const uint8_t unit_id, const uint16_t start_addr, const uint16_t reg_val)
```

Write single holding register (FC06)

Sends a Modbus message to write the value of single holding register to a server unit.

**Parameters**

- `iface` – Modbus interface index
- `unit_id` – Modbus unit ID of the server
- `start_addr` – Coils starting address
- `reg_val` – Desired value of the holding register

**Return values**

- `0` – If the function was successful
int modbus_request_diagnostic(const int iface, const uint8_t unit_id, const uint16_t sfunc, const uint16_t data, uint16_t *const data_out)

Read diagnostic (FC08)
Sends a Modbus message to perform a diagnostic function of a server unit.

Parameters
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- sfunc – Diagnostic sub-function code
- data – Sub-function data
- data_out – Pointer to the data value

Return values
0 – If the function was successful

int modbus_write_coils(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint8_t *const coil_tbl, const uint16_t num_coils)

Write coils (FC15)
Sends a Modbus message to write to coils on a server unit.

Parameters
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Coils starting address
- coil_tbl – Pointer to an array of bytes containing the value of the coils to write. The format is:
<table>
<thead>
<tr>
<th>MSB</th>
<th>LSB</th>
</tr>
</thead>
<tbody>
<tr>
<td>B7</td>
<td>B0</td>
</tr>
<tr>
<td>B6</td>
<td>B1</td>
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<tr>
<td>B5</td>
<td>B2</td>
</tr>
<tr>
<td>B4</td>
<td>B3</td>
</tr>
</tbody>
</table>

Note that the array that will be receiving the coil values must be greater than or equal to: (num_coils - 1) / 8 + 1
- num_coils – Quantity of coils to write

Return values
0 – If the function was successful

int modbus_write_holding_regs(const int iface, const uint8_t unit_id, const uint16_t start_addr, uint16_t *const reg_buf, const uint16_t num_regs)

Write holding registers (FC16)
Sends a Modbus message to write to integer holding registers to a server unit.

Parameters
- iface – Modbus interface index
- unit_id – Modbus unit ID of the server
- start_addr – Register starting address
• **reg_buf** – Is a pointer to an array containing the value of the holding registers to write. Note that the array containing the register values must be greater than or equal to ‘num_regs’

• **num_regs** – Quantity of registers to write

**Return values**

0 – If the function was successful

```c
int modbus_read_holding_regs_fp(const int iface, const uint8_t unit_id, const uint16_t start_addr, float *const reg_buf, const uint16_t num_regs)
```

Read floating-point holding registers (FC03)

Sends a Modbus message to read the value of floating-point holding registers from a server unit.

**Parameters**

• **iface** – Modbus interface index

• **unit_id** – Modbus unit ID of the server

• **start_addr** – Register starting address

• **reg_buf** – Is a pointer to an array that will receive the current values of the holding registers from the server. The array pointed to by ‘reg_buf’ needs to be able to hold at least ‘num_regs’ entries.

• **num_regs** – Quantity of registers to read

**Return values**

0 – If the function was successful

```c
int modbus_write_holding_regs_fp(const int iface, const uint8_t unit_id, const uint16_t start_addr, float *const reg_buf, const uint16_t num_regs)
```

Write floating-point holding registers (FC16)

Sends a Modbus message to write to floating-point holding registers to a server unit.

**Parameters**

• **iface** – Modbus interface index

• **unit_id** – Modbus unit ID of the server

• **start_addr** – Register starting address

• **reg_buf** – Is a pointer to an array containing the value of the holding registers to write. Note that the array containing the register values must be greater than or equal to ‘num_regs’

• **num_regs** – Quantity of registers to write

**Return values**

0 – If the function was successful

```c
int modbus_iface_get_by_name(const char *iface_name)
```

Get Modbus interface index according to interface name.

If there is more than one interface, it can be used to clearly identify interfaces in the application.

**Parameters**

• **iface_name** – Modbus interface name

**Return values**

Modbus – interface index or negative error value.
int modbus_init_server(const int iface, struct modbus_iface_param *param)
Configure Modbus Interface as raw ADU server.

Parameters
• iface – Modbus RTU interface index
• param – Configuration parameter of the server interface

Return values
0 – If the function was successful

int modbus_init_client(const int iface, struct modbus_iface_param *param)
Configure Modbus Interface as raw ADU client.

Parameters
• iface – Modbus RTU interface index
• param – Configuration parameter of the client interface

Return values
0 – If the function was successful

int modbus_disable(const uint8_t iface)
Disable Modbus Interface.

This function is called to disable Modbus interface.

Parameters
• iface – Modbus interface index

Return values
0 – If the function was successful

int modbus_raw_submit_rx(const int iface, const struct modbus_adu *adu)
Submit raw ADU.

Parameters
• iface – Modbus RTU interface index
• adu – Pointer to the RAW ADU struct that is received

Return values
0 – If transfer was successful

void modbus_raw_put_header(const struct modbus_adu *adu, uint8_t *header)
Put MBAP header into a buffer.

Parameters
• adu – Pointer to the RAW ADU struct
• header – Pointer to the buffer in which MBAP header will be placed.

void modbus_raw_get_header(struct modbus_adu *adu, const uint8_t *header)
Get MBAP header from a buffer.

Parameters
• adu – Pointer to the RAW ADU struct
• header – Pointer to the buffer containing MBAP header

void modbus_raw_set_server_failure(struct modbus_adu *adu)
Set Server Device Failure exception.

This function modifies ADU passed by the pointer.
int modbus_raw_backend_txn(const int iface, struct modbus_adu *adu)

Use interface as backend to send and receive ADU.

This function overwrites ADU passed by the pointer and generates exception responses if backend interface is misconfigured or target device is unreachable.

Parameters

• iface – Modbus client interface index

• adu – Pointer to the RAW ADU struct

Return values

0 – If transfer was successful

#include <modbus.h>

Frame struct used internally and for raw ADU support.

Public Members

uint16_t trans_id
Transaction Identifier

uint16_t proto_id
Protocol Identifier

uint16_t length
Length of the data only (not the length of unit ID + PDU)

uint8_t unit_id
Unit Identifier

uint8_t fc
Function Code

uint8_t data[CONFIG_MODBUS_BUFFER_SIZE - 4]
Transaction Data

uint16_t crc
RTU CRC

#include <modbus.h>

Modbus Server User Callback structure

Public Members

int (*coil_rd)(uint16_t addr, bool *state)
Coil read callback
int (*coil_wr)(uint16_t addr, bool state)
  Coil write callback

int (*discrete_input_rd)(uint16_t addr, bool *state)
  Discrete Input read callback

int (*input_reg_rd)(uint16_t addr, uint16_t *reg)
  Input Register read callback

int (*input_reg_rd_fp)(uint16_t addr, float *reg)
  Floating Point Input Register read callback

int (*holding_reg_rd)(uint16_t addr, uint16_t *reg)
  Holding Register read callback

int (*holding_reg_wr)(uint16_t addr, uint16_t reg)
  Holding Register write callback

int (*holding_reg_rd_fp)(uint16_t addr, float *reg)
  Floating Point Holding Register read callback

int (*holding_reg_wr_fp)(uint16_t addr, float reg)
  Floating Point Holding Register write callback

struct modbus_serial_param
  #include <modbus.h> Modbus serial line parameter.

Public Members

uint32_t baud
  Baudrate of the serial line

enum uart_config_parity parity
  parity UART's parity setting: UART_CFG_PARITY_NONE, UART_CFG_PARITY_EVEN, UART_CFG_PARITY_ODD

enum uart_config_stop_bits stop_bits_client
  stop_bits_client UART's stop bits setting if in client mode: UART_CFG_STOP_BITS_0_5, UART_CFG_STOP_BITS_1, UART_CFG_STOP_BITS_1_5, UART_CFG_STOP_BITS_2,

struct modbus_server_param
  #include <modbus.h> Modbus server parameter.

Public Members

struct modbus_user_callbacks *user_cb
  Pointer to the User Callback structure
```c
uint8_t unit_id
   Modbus unit ID of the server

struct modbus_raw_cb
#include <modbus.h>

struct modbus_iface_param
#include <modbus.h> User parameter structure to configure Modbus interface as client or server.

Public Members

enum modbus_mode mode
   Mode of the interface

uint32_t rx_timeout
   Amount of time client will wait for a response from the server.

struct modbus_serial_param serial
   Serial support parameter of the interface

struct modbus_raw_cb rawcb
   Pointer to raw ADU callback function
```

4.11 Asynchronous Notifications

Zephyr APIs often include async functions where an operation is initiated and the application needs to be informed when it completes, and whether it succeeded. Using \texttt{k.poll()} is often a good method, but some application architectures may be more suited to a callback notification, and operations like enabling clocks and power rails may need to be invoked before kernel functions are available so a busy-wait for completion may be needed.

This API is intended to be embedded within specific subsystems such as \textit{On-Off Manager} and other APIs that support async transactions. The subsystem wrappers are responsible for extracting operation-specific data from requests that include a notification element, and for invoking callbacks with the parameters required by the API.

A limitation is that this API is not suitable for \textit{System Calls} because:

- \texttt{sys.notify} is not a kernel object;
- copying the notification content from userspace will break use of \texttt{CONTAINER_OF} in the implementing function;
- neither the spin-wait nor callback notification methods can be accepted from userspace callers.

Where a notification is required for an asynchronous operation invoked from a user mode thread the subsystem or driver should provide a syscall API that uses \texttt{k.poll.signal} for notification.

4.11.1 API Reference

\texttt{group sys_notify_apis}
Typedefs

typedef void (*sys_notify_generic_callback)()

Generic signature used to notify of result completion by callback.

Functions with this role may be invoked from any context including pre-kernel, ISR, or co-op-
erative or pre-emptible threads. Compatible functions must be isr-ok and not sleep.

Parameters that should generally be passed to such functions include:

- a pointer to a specific client request structure, i.e. the one that contains the sys_notify
  structure.
- the result of the operation, either as passed to sys_notify_finalize() or extracted afterwards
  using sys_notify_fetch_result(). Expected values are service-specific, but the value shall be
  non-negative if the operation succeeded, and negative if the operation failed.

Functions

static inline uint32_t sys_notify_get_method(const struct sys_notify *notify)

int sys_notify_validate(struct sys_notify *notify)

Validate and initialize the notify structure.

This should be invoked at the start of any service-specific configuration validation. It ensures
that the basic asynchronous notification configuration is consistent, and clears the result.

Note that this function does not validate extension bits (zeroed by async notify API init func-
tions like sys_notify_init_callback()). It may fail to recognize that an uninitialized structure
has been passed because only method bits of flags are tested against method settings. To
reduce the chance of accepting an uninitialized operation service validation of structures that
contain an sys_notify instance should confirm that the extension bits are set or cleared as
expected.

Return values

- 0 – on successful validation and reinitialization
- -EINVAL – if the configuration is not valid.

sys_notify_generic_callback sys_notify_finalize(struct sys_notify *notify, int res)

Record and signal the operation completion.

Parameters

- notify – pointer to the notification state structure.
- res – the result of the operation. Expected values are service-specific, but the
  value shall be non-negative if the operation succeeded, and negative if the
  operation failed.

Returns

If the notification is to be done by callback this returns the generic version of the
function to be invoked. The caller must immediately invoke that function with
whatever arguments are expected by the callback. If notification is by spin-wait
or signal, the notification has been completed by the point this function returns,
and a null pointer is returned.

static inline int sys_notify_fetch_result(const struct sys_notify *notify, int *result)

Check for and read the result of an asynchronous operation.

Parameters
• notify – pointer to the object used to specify asynchronous function behavior
  and store completion information.
• result – pointer to storage for the result of the operation. The result is stored
  only if the operation has completed.

Return values
• 0 – if the operation has completed.
• -EAGAIN – if the operation has not completed.

static inline void sys_notify_init_spinwait(struct sys_notify *notify)
Initialize a notify object for spin-wait notification.
Clients that use this initialization receive no asynchronous notification, and instead must pe-
riodically check for completion using sys_notify_fetch_result().
On completion of the operation the client object must be reinitialized before it can be re-used.

Parameters
• notify – pointer to the notification configuration object.

static inline void sys_notify_init_signal(struct sys_notify *notify, struct k_poll_signal *sigp)
Initialize a notify object for (k_poll) signal notification.
Clients that use this initialization will be notified of the completion of operations through the
provided signal.
On completion of the operation the client object must be reinitialized before it can be re-used.

Note: This capability is available only when CONFIG_POLL is selected.

Parameters
• notify – pointer to the notification configuration object.
• sigp – pointer to the signal to use for notification. The value must not be null.
  The signal must be reset before the client object is passed to the on-off service
  API.

static inline void sys_notify_init_callback(struct sys_notify *notify, sys_notify_generic_callback handler)
Initialize a notify object for callback notification.
Clients that use this initialization will be notified of the completion of operations through the
provided callback. Note that callbacks may be invoked from various contexts depending on
the specific service; see sys_notify_generic_callback.
On completion of the operation the client object must be reinitialized before it can be re-used.

Parameters
• notify – pointer to the notification configuration object.
• handler – a function pointer to use for notification.

static inline bool sys_notify_uses_callback(const struct sys_notify *notify)
Detect whether a particular notification uses a callback.

The generic handler does not capture the signature expected by the callback, and the transla-
tion to a service-specific callback must be provided by the service. This check allows abstracted
services to reject callback notification requests when the service doesn’t provide a translation
function.
Returns

true if and only if a callback is to be used for notification.

struct sys_notify
#include <notify.h> State associated with notification for an asynchronous operation.

Objects of this type are allocated by a client, which must use an initialization function (e.g. sys_notify_init_signal()) to configure them. Generally the structure is a member of a service-specific client structure, such as onoff_client.

Control of the containing object transfers to the service provider when a pointer to the object is passed to a service function that is documented to take control of the object, such as onoff_service_request(). While the service provider controls the object the client must not change any object fields. Control reverts to the client:

- if the call to the service API returns an error;
- when operation completion is posted. This may occur before the call to the service API returns.

Operation completion is technically posted when the flags field is updated so that sys_notify_fetch_result() returns success. This will happen before the signal is posted or callback is invoked. Note that although the manager will no longer reference the sys_notify object past this point, the containing object may have state that will be referenced within the callback. Where callbacks are used control of the containing object does not revert to the client until the callback has been invoked. (Re-use within the callback is explicitly permitted.)

After control has reverted to the client the notify object must be reinitialized for the next operation.

The content of this structure is not public API to clients: all configuration and inspection should be done with functions like sys_notify_init_callback() and sys_notify_fetch_result(). However, services that use this structure may access certain fields directly.

union
#include <notify.h>

Public Members

struct k_poll_signal *signal

sys_notify_generic_callback callback

4.12 Power Management

Zephyr RTOS power management subsystem provides several means for a system integrator to implement power management support that can take full advantage of the power saving features of SOCs.

4.12.1 Overview

The interfaces and APIs provided by the power management subsystem are designed to be architecture and SOC independent. This enables power management implementations to be easily adapted to different SOCs and architectures.
The architecture and SOC independence is achieved by separating the core infrastructure and the SOC specific implementations. The SOC specific implementations are abstracted to the application and the OS using hardware abstraction layers.

The power management features are classified into the following categories.

- System Power Management
- Device Power Management

### 4.12.2 System Power Management

The kernel enters the idle state when it has nothing to schedule. If enabled via the `CONFIG_PM` Kconfig option, the Power Management Subsystem can put an idle system in one of the supported power states, based on the selected power management policy and the duration of the idle time allotted by the kernel.

It is an application responsibility to set up a wake up event. A wake up event will typically be an interrupt triggered by one of the SoC peripheral modules such as a SysTick, RTC, counter, or GPIO. Depending on the power mode entered, only some SoC peripheral modules may be active and can be used as a wake up source.

The following diagram describes system power management:
Idle Thread

arch_irq_lock()

CONFIG_PM

no

yes

k_cpu_idle()

pm_system_supspend (ticks)

pm_policy_next_state()

pm_suspend_devices()

k_schedule_lock()

pm_state_notify()

pm_power_state_set(state)

pm_resume_devices()

pm_state_exit_post_ops()

pm_state_notify()

k_sched_unlock()
Some handful examples using different power management features:

- samples/boards/stm32/power_mgmt/blinky/
- samples/boards/nrf/system_off/
- samples/subsys/pm/device_pm/
- tests/subsys/pm/power_mgmt/
- tests/subsys/pm/power_mgmt_soc/
- tests/subsys/pm/power_states_api/

**Power States**

The power management subsystem contains a set of states based on power consumption and context retention.

The list of available power states is defined by `pm_state`. In general power states with higher indexes will offer greater power savings and have higher wake latencies.

**Power Management Policies**

The power management subsystem supports the following power management policies:

- Residency based
- Application defined

The policy manager is responsible for informing the power subsystem which power state the system should transition to based on states defined by the platform and other constraints such as a list of allowed states.

More details on the states definition can be found in the zephyr, power-state binding documentation.

**Residency** The power management system enters the power state which offers the highest power savings, and with a minimum residency value (see zephyr, power-state) less than or equal to the scheduled system idle time duration.

This policy also accounts for the time necessary to become active again. The core logic used by this policy to select the best power state is:

```c
if (time_to_next_scheduled_event >= (state.min_residency_us + state.exit_latency)) {
    return state
}
```

**Application** The application defines the power management policy by implementing the `pm_policy_next_state()` function. In this policy the application is free to decide which power state the system should transition to based on the remaining time for the next scheduled timeout.

An example of an application that defines its own policy can be found in tests/subsys/pm/power_mgmt/.

**Policy and Power States** The power management subsystem allows different Zephyr components and applications to configure the policy manager to block system from transitioning into certain power states. This can be used by devices when executing tasks in background to prevent the system from going to a specific state where it would lose context.
4.12.3 Device Power Management

Introduction

Device power management (PM) on Zephyr is a feature that enables devices to save energy when they are not being used. This feature can be enabled by setting `CONFIG_PM_DEVICE` to y. When this option is selected, device drivers implementing power management will be able to take advantage of the device power management subsystem.

Zephyr supports two types of device power management:

- Device Runtime Power Management
- System Power Management

Device Runtime Power Management

In this method, the application or any component that deals with devices directly and has the best knowledge of their use, performs the device power management. This saves power if some devices that are not in use can be turned off or put in power saving mode. This method allows saving power even when the CPU is active. The components that use the devices need to be power aware and should be able to make decisions related to managing device power.

When using this type of device power management, the kernel can change CPU power states quickly when `pm_system_suspend()` gets called. This is because it does not need to spend time doing device power management if the devices are already put in the appropriate power state by the application or component managing the devices.

For more information, see Device Runtime Power Management.

System Power Management

When using this type, device power management is mostly done inside `pm_system_suspend()` along with entering a CPU or SOC power state.

If a decision to enter a CPU lower power state is made, the power management subsystem will suspend devices before changing state. The subsystem takes care of suspending devices following their initialization order, ensuring that possible dependencies between them are satisfied. As soon as the CPU wakes up from a sleep state, devices are resumed in the opposite order that they were suspended.

**Note:** When using System Power Management, device transitions can be run from the idle thread. As functions in this context cannot block, transitions that intend to use blocking APIs must check whether they can do so with `k_can_yield()`.

This type of device power management can be useful when the application is not power aware and does not implement runtime device power management. Though, Device Runtime Power Management is the preferred option for device power management.

**Note:** When using this type of device power management, the CPU will only enter a low power state only if no device is in the middle of a hardware transaction that cannot be interrupted.

**Note:** This type of device power management is disabled when `CONFIG_PM_DEVICE_RUNTIME_EXCLUSIVE` is set to y (that is the default value when `CONFIG_PM_DEVICE_RUNTIME` is enabled).
Device Power Management States

The power management subsystem defines device states in `pm_device_state`. This type is used to track power states of a particular device. It is important to emphasize that, although the state is tracked by the subsystem, it is the responsibility of each device driver to handle device actions( `pm_device_action` ) which change device state.

Each `pm_device_action` have a direct an unambiguous relationship with a `pm_device_state`.

As mentioned above, device drivers do not directly change between these states. This is entirely done by the power management subsystem. Instead, drivers are responsible for implementing any hardware-specific tasks needed to handle state changes.

Device Model with Power Management Support

Drivers initialize devices using macros. See `Device Driver Model` for details on how these macros are used. A driver which implements device power management support must provide these macros with arguments that describe its power management implementation.

Use `PM_DEVICE_DEFINE` or `PM_DEVICE_DT_DEFINE` to define the power management resources required by a driver. These macros allocate the driver-specific state which is required by the power management subsystem.

Drivers can use `PM_DEVICE_GET` or `PM_DEVICE_DT_GET` to get a pointer to this state. These pointers should be passed to `DEVICE_DEFINE` or `DEVICE_DT_DEFINE` to initialize the power management field in each device.

Here is some example code showing how to implement device power management support in a device driver.

```c
#define DT_DRV_COMPAT dummy_device

static int dummy_driver_pm_action(const struct device *dev,      
enum pm_device_action *action)
{
    switch (action) {
(continues on next page)```
case PM_DEVICE_ACTION_SUSPEND:
    /* suspend the device */
    ...
    break;
case PM_DEVICE_ACTION_RESUME:
    /* resume the device */
    ...
    break;
case PM_DEVICE_ACTION_TURN_ON:
    /* powered on the device, used when the power
     * domain this device belongs is resumed.
     */
    ...
    break;
case PM_DEVICE_ACTION_TURN_OFF:
    /* power off the device, used when the power
     * domain this device belongs is suspended.
     */
    ...
    break;
default:
    return -ENOTSUP;
}

return 0;

PM_DEVICE_DT_INST_DEFINE(0, dummy_driver_pm_action);

DEVICE_DT_INST_DEFINE(0, &dummy_init,
    PM_DEVICE_DT_INST_GET(0), NULL, NULL, POST_KERNEL,
    CONFIG_KERNEL_INIT_PRIORITY_DEFAULT, NULL);

Busy Status Indication

When the system is idle and the SoC is going to sleep, the power management subsystem can suspend
devices, as described in System Power Management. This can cause device hardware to lose some states.
Suspending a device which is in the middle of a hardware transaction, such as writing to a flash memory,
may lead to undefined behavior or inconsistent states. This API guards such transactions by indicating
to the kernel that the device is in the middle of an operation and should not be suspended.

When pm_device_busy_set() is called, the device is marked as busy and the system will not do power
management on it. After the device is no longer doing an operation and can be suspended, it should call
pm_device_busy_clear().

Wakeup capability

Some devices are capable of waking the system up from a sleep state. When a device has
such capability, applications can enable or disable this feature on a device dynamically using
pm_device_wakeup_enable().

This property can be set on device declaring the property "wakeup-source" in the device node in device-
tree. For example, this devicetree fragment sets the gpio0 device as a "wakeup" source:
By default, “wakeup” capable devices do not have this functionality enabled during the device initialization. Applications can enable this functionality later calling `pm_device_wakeup_enable()`.

Note: This property is only used by the system power management to identify devices that should not be suspended. It is responsibility of driver or the application to do any additional configuration required by the device to support it.

Power Domain

Power domain on Zephyr is represented as a regular device. The power management subsystem ensures that a domain is resumed before and suspended after devices using it. For more details, see Power Domain.

4.12.4 Device Runtime Power Management

Introduction

The device runtime power management (PM) framework is an active power management mechanism which reduces the overall system power consumption by suspending the devices which are idle or not used independently of the system state. It can be enabled by setting `CONFIG_PM_DEVICE_RUNTIME`. In this model the device driver is responsible to indicate when it needs the device and when it does not. This information is used to determine when to suspend or resume a device based on usage count.

When device runtime power management is enabled on a device, its state will be initially set to a `PM_DEVICE_STATE_SUSPENDED` indicating it is not used. On the first device request, it will be resumed and so put into the `PM_DEVICE_STATE_ACTIVE` state. The device will remain in this state until it is no longer used. At this point, the device will be suspended until the next device request. If the suspension is performed synchronously the device will be immediately put into the `PM_DEVICE_STATE_SUSPENDED` state, whereas if it is performed asynchronously, it will be put into the `PM_DEVICE_STATE_SUSPENDING` state first and then into the `PM_DEVICE_STATE_SUSPENDED` state when the action is run.

The device runtime power management framework has been designed to minimize devices power consumption with minimal application work. Device drivers are responsible for indicating when they need the device to be operational and when they do not. Therefore, applications can not manually suspend or resume a device. An application can, however, decide when to disable or enable runtime power management for a device. This can be useful, for example, if an application wants a particular device to be always active.

Design principles

When runtime PM is enabled on a device it will no longer be resumed or suspended during system power transitions. Instead, the device is fully responsible to indicate when it needs a device and when it does not. The device runtime PM API uses reference counting to keep track of device’s usage. This allows
the API to determine when a device needs to be resumed or suspended. The API uses the `get` and `put` terminology to indicate when a device is needed or not, respectively. This mechanism plays a key role when we account for device dependencies. For example, if a bus device is used by multiple sensors, we can keep the bus active until the last sensor has finished using it.

**Note:** As of today, the device runtime power management API does not manage device dependencies. This effectively means that, if a device depends on other devices to operate (e.g., a sensor may depend on a bus device), the bus will be resumed and suspended on every transaction. In general, it is more efficient to keep parent devices active when their children are used, since the children may perform multiple transactions in a short period of time. Until this feature is added, devices can manually `get` or `put` their dependencies.

The `pm_device_runtime_get()` function can be used by a device driver to indicate it needs the device to be active or operational. This function will increase device usage count and resume the device if necessary. Similarly, the `pm_device_runtime_put()` function can be used to indicate that the device is no longer needed. This function will decrease the device usage count and suspend the device if necessary. It is worth to note that in both cases, the operation is carried out synchronously. The sequence diagram shown in Fig. 4.5 illustrates how a device can use this API and the expected sequence of events.

The synchronous model is as simple as it gets. However, it may introduce unnecessary delays since the application will not get the operation result until the device is suspended (in case device is no longer used). It will likely not be a problem if the operation is fast, e.g., a register toggle. However, the situation will not be the same if suspension involves sending packets through a slow bus. For this reason the device drivers can also make use of the `pm_device_runtime_put_async()` function. This function will schedule the suspend operation, again, if device is no longer used. The suspension will then be carried out when the system work queue gets the chance to run. The sequence diagram in Fig. 4.6 illustrates this scenario.
Fig. 4.5: Synchronous operation on a single device
Application
Device
PM Subsystem
System Workqueue

operation(dev)

pm_device_runtime_get(dev)

Increase usage

alt [usage == 1]

PM_DEVICE_ACTION_RESUME

alt [usage == 0]

Schedule suspend

pm_device_runtime_put_async(dev)

Decrease usage

alt [Scheduled suspend]

PM_DEVICE_ACTION_SUSPEND

Fig. 4.6: Asynchronous operation on a single device

Chapter 4. OS Services
Implementation guidelines

In a first place, a device driver needs to implement the PM action callback used by the PM subsystem to suspend or resume devices.

```c
static int mydev_pm_action(const struct device *dev, enum pm_device_action *action)
{
    switch (action) {
    case PM_DEVICE_ACTION_SUSPEND:
        /* suspend the device */
        ...
        break;
    case PM_DEVICE_ACTION_RESUME:
        /* resume the device */
        ...
        break;
    default:
        return -ENOTSUP;
    }
    return 0;
}
```

The PM action callback calls are serialized by the PM subsystem, therefore, no special synchronization is required.

To enable device runtime power management on a device, the driver needs to call `pm_device_runtime_enable()` at initialization time. Note that this function will suspend the device if its state is `PM_DEVICE_STATE_ACTIVE`. In case the device is physically suspended, the init function should call `pm_device_init_suspended()` before calling `pm_device_runtime_enable()`.

```c
/* device driver initialization function */
static int mydev_init(const struct device *dev)
{
    int ret;
    ...

    /* OPTIONAL: mark device as suspended if it is physically suspended */
    pm_device_init_suspended(dev);

    /* enable device runtime power management */
    ret = pm_device_runtime_enable(dev);
    if ((ret < 0) && (ret != -ENOSYS)) {
        return ret;
    }
}
```

Assuming an example device driver that implements an operation API call, the `get` and `put` operations could be carried out as follows:

```c
static int mydev_operation(const struct device *dev)
{
    int ret;

    /* "get" device (increases usage count, resumes device if suspended) */
    ret = pm_device_runtime_get(dev);
    if (ret < 0) {
        return ret;
    }
}
```

(continues on next page)
In case the suspend operation is slow, the device driver can use the asynchronous API:

```c
static int mydev_operation(const struct device *dev)
{
    int ret;

    /* "get" device (increases usage count, resumes device if suspended) */
    ret = pm_device_runtime_get(dev);
    if (ret < 0) {
        return ret;
    }

    /* do something with the device */
    ...

    /* "put" device (decreases usage count, schedule suspend if no more users) */
    return pm_device_runtime_put_async(dev);
}
```

4.12.5 Power Domain

Introduction

The Zephyr power domain abstraction is designed to support groupings of devices powered by a common source to be notified of power source state changes in a generic fashion. Application code that is using device A does not need to know that device B is on the same power domain and should also be configured into a low power state.

Power domains are optional on Zephyr, to enable this feature the option `CONFIG_PM_DEVICE_POWER_DOMAIN` has to be set.

When a power domain turns itself on or off, it is the responsibility of the power domain to notify all devices using it through their power management callback called with `PM_DEVICE_ACTION_TURN_ON` or `PM_DEVICE_ACTION_TURN_OFF` respectively. This work flow is illustrated in the diagram bellow.

**Internal Power Domains**  Most of the devices in an SoC have independent power control that can be turned on or off to reduce power consumption. But there is a significant amount of static current leakage that can't be controlled only using device power management. To solve this problem, SoCs normally are divided into several regions grouping devices that are generally used together, so that an unused region can be completely powered off to eliminate this leakage. These regions are called “power domains”, can be present in a hierarchy and can be nested.

**External Power Domains**  Devices external to a SoC can be powered from sources other than the main power source of the SoC. These external sources are typically a switch, a regulator, or a dedicated power IC. Multiple devices can be powered from the same source, and this grouping of devices is typically called a “power domain”.

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Power Management

Placing devices on power domains can be done for a variety of reasons, including to enable devices with high power consumption in low power mode to be completely turned off when not in use.

**Implementation guidelines**

In a first place, a device that acts as a power domain needs to declare compatible with `power-domain`.

Taking the **Power domain work flow** as example, the following code defines a domain called `gpio_domain`.

```c
static int mydomain_pm_action(const struct device *dev, enum pm_device_action *action)
{
    switch (action) {
        case PM_DEVICE_ACTION_RESUME:
            /* resume the domain */
            ...
            /* notify children domain is now powered */
            pm_device_children_action_run(dev, PM_DEVICE_ACTION_TURN_ON, NULL);
            break;
        case PM_DEVICE_ACTION_SUSPEND:
            /* notify children domain is going down */
            pm_device_children_action_run(dev, PM_DEVICE_ACTION_TURN_OFF, NULL);
            /* suspend the domain */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_ON:
            /* turn on the domain (e.g. setup control pins to disabled) */
            ...
            break;
        case PM_DEVICE_ACTION_TURN_OFF:
            /* turn off the domain (e.g. reset control pins to default state) */
            ...
            break;
    }
}
```

(continues on next page)
default:
    return -ENOTSUP;
}

return 0;
}

Devices belonging to this device can be declared referring it in the power-domain node's property. The example below declares devices gpio0 and gpio1 belonging to domain gpio_domain.

```
&gpio0 {
    compatible = "zephyr,gpio-emul";
    gpio-controller;
    power-domain = <&gpio_domain>;
};

&gpio1 {
    compatible = "zephyr,gpio-emul";
    gpio-controller;
    power-domain = <&gpio_domain>;
};
```

All devices under a domain will be notified when the domain changes state. These notifications are sent as actions in the device PM action callback and can be used by them to do any additional work required. They can safely be ignored though.

```
static int mydev_pm_action(const struct device *dev,
    enum pm_device_action *action)
{
    switch (action) {
    case PM_DEVICE_ACTION_SUSPEND:
        /* suspend the device */
        ...
        break;
    case PM_DEVICE_ACTION_RESUME:
        /* resume the device */
        ...
        break;
    case PM_DEVICE_ACTION_TURN_ON:
        /* configure the device into low power mode */
        ...
        break;
    case PM_DEVICE_ACTION_TURN_OFF:
        /* prepare the device for power down */
        ...
        break;
    default:
        return -ENOTSUP;
    }

    return 0;
}
```

**Note:** It is responsibility of driver or the application to set the domain as “wakeup” source if a device depending on it is used as “wakeup” source.
4.12.6 Power Management

System PM APIs

group subsys_pm_sys

System Power Management API.

Functions

bool pm_state_force(uint8_t cpu, const struct pm_state_info *info)

Force usage of given power state.

This function overrides decision made by PM policy forcing usage of given power state upon
next entry of the idle thread.

Note: This function can only run in thread context

Parameters

• cpu – CPU index.
• info – Power state which should be used in the ongoing suspend operation.

void pm_notifier_register(struct pm_notifier *notifier)

Register a power management notifier.

Register the given notifier from the power management notification list.

Parameters

• notifier – pm_notifier object to be registered.

int pm_notifier_unregister(struct pm_notifier *notifier)

Unregister a power management notifier.

Remove the given notifier from the power management notification list. After that this object
callbacks will not be called.

Parameters

• notifier – pm_notifier object to be unregistered.

Returns

0 if the notifier was successfully removed, a negative value otherwise.

const struct pm_state_info *pm_state_next_get(uint8_t cpu)

Gets the next power state that will be used.

This function returns the next power state that will be used by the SoC.

Parameters

• cpu – CPU index.

Returns

next pm_state_info that will be used
struct pm_notifier
#include <pm.h> Power management notifier struct

This struct contains callbacks that are called when the target enters and exits power states. As currently implemented the entry callback is invoked when transitioning from PM_STATE_ACTIVE to another state, and the exit callback is invoked when transitioning from a non-active state to PM_STATE_ACTIVE. This behavior may change in the future.

Note: These callbacks can be called from the ISR of the event that caused the kernel exit from idling.

Note: It is not allowed to call pm_notifier_unregister or pm_notifier_register from these callbacks because they are called with the spin locked in those functions.

Public Members

void (*state_entry)(enum pm_state state)
Application defined function for doing any target specific operations for power state entry.

void (*state_exit)(enum pm_state state)
Application defined function for doing any target specific operations for power state exit.

States

group subsys_pm_states
System Power Management States.

Defines

PM_STATE_INFO_DT_INIT(node_id)
Initializer for struct pm_state_info given a DT node identifier with zephyr,power-state compatible.

Parameters
• node_id – A node identifier with compatible zephyr,power-state

PM_STATE_DT_INIT(node_id)
Initializer for enum pm_state given a DT node identifier with zephyr,power-state compatible.

Parameters
• node_id – A node identifier with compatible zephyr,power-state

DT_NUM_CPU_POWER_STATES(node_id)
Obtain number of CPU power states supported by the given CPU node identifier.

Parameters
• node_id – A CPU node identifier.

Returns
Number of supported CPU power states.
PM_STATE_INFO_LIST_FROM_DT_CPU(node_id)
Initialize an array of struct pm_state_info with information from all the states present in the given CPU node identifier.

Example devicetree fragment:

cpus {
    ...
    cpu0: cpu@0 {
        device_type = "cpu";
        ...
        cpu-power-states = <&state0 &state1>;
    };
    ...
}

power-states {
    state0: state0 {
        compatible = "zephyr,power-state";
        power-state-name = "suspend-to-idle";
        min-residency-us = <10000>;
        exit-latency-us = <100>;
    };

    state1: state1 {
        compatible = "zephyr,power-state";
        power-state-name = "suspend-to-ram";
        min-residency-us = <50000>;
        exit-latency-us = <500>;
    };
}

Example usage:

const struct pm_state_info states[] =
    PM_STATE_INFO_LIST_FROM_DT_CPU(DT_NODELABEL(cpu0));

Parameters

• node_id – A CPU node identifier.

PM_STATE_LIST_FROM_DT_CPU(node_id)
Initialize an array of struct pm_state with information from all the states present in the given CPU node identifier.

Example devicetree fragment:

cpus {
    ...
    cpu0: cpu@0 {
        device_type = "cpu";
        ...
        cpu-power-states = <&state0 &state1>;
    };
    ...
}
Example usage:

```c
const enum pm_state states[] = PM_STATE_LIST_FROM_DT_CPU(DT_NODELABEL(cpu0));
```

**Parameters**

- `node_id` – A CPU node identifier.

**Enums**

enum pm_state

Power management state

**Values:**

enumerator PM_STATE_ACTIVE

Runtime active state.

The system is fully powered and active.

---

**Note:** This state is correlated with ACPI G0/S0 state

enumerator PM_STATE_RUNTIME_IDLE

Runtime idle state.

Runtime idle is a system sleep state in which all of the cores enter deepest possible idle state and wait for interrupts, no requirements for the devices, leaving them at the states where they are.

---

**Note:** This state is correlated with ACPI S0ix state
Suspend to idle state.
The system goes through a normal platform suspend where it puts all of the cores in deepest possible idle state and may put peripherals into low-power states. No operating state is lost (i.e., the CPU core does not lose execution context), so the system can go back to where it left off easily enough.

**Note:** This state is correlated with ACPI S1 state

Standby state.
In addition to putting peripherals into low-power states all non-boot CPUs are powered off. It should allow more energy to be saved relative to suspend to idle, but the resume latency will generally be greater than for that state. But it should be the same state with suspend to idle state on uniprocessor system.

**Note:** This state is correlated with ACPI S2 state

Suspend to ram state.
This state offers significant energy savings by powering off as much of the system as possible, where memory should be placed into the self-refresh mode to retain its contents. The state of devices and CPUs is saved and held in memory, and it may require some boot-strapping code in ROM to resume the system from it.

**Note:** This state is correlated with ACPI S3 state

Suspend to disk state.
This state offers significant energy savings by powering off as much of the system as possible, including the memory. The contents of memory are written to disk or other non-volatile storage, and on resume it’s read back into memory with the help of boot-strapping code, restores the system to the same point of execution where it went to suspend to disk.

**Note:** This state is correlated with ACPI S4 state

Soft off state.
This state consumes a minimal amount of power and requires a large latency in order to return to runtime active state. The contents of system (CPU and memory) will not be preserved, so the system will be restarted as if from initial power-up and kernel boot.

**Note:** This state is correlated with ACPI G2/S5 state
enumerator PM_STATE_COUNT
    Number of power management states (internal use)

Functions

uint8_t pm_state_cpu_get_all(uint8_t cpu, const struct pm_state_info **states)
    Obtain information about all supported states by a CPU.

Parameters

• cpu – CPU index.
• states – Where to store the list of supported states.

Returns
    Number of supported states.

struct pm_state_info
    #include <state.h> Information about a power management state

Public Members

uint8_t substate_id
    Some platforms have multiple states that map to one Zephyr power state. This property allows the platform distinguish them. e.g:

    power-states {
        state0: state0 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-idle";
            substate-id = <1>;
            min-residency-us = <10000>;
            exit-latency-us = <100>;
        };
        state1: state1 {
            compatible = "zephyr,power-state";
            power-state-name = "suspend-to-idle";
            substate-id = <2>;
            min-residency-us = <20000>;
            exit-latency-us = <200>;
        };
    }

uint32_t min_residency_us
    Minimum residency duration in microseconds. It is the minimum time for a given idle state to be worthwhile energywise.

    Note: 0 means that this property is not available for this state.

uint32_t exit_latency_us
Worst case latency in microseconds required to exit the idle state.

**Note:** 0 means that this property is not available for this state.

**Policy**

*group subsys_pm_sys_policy*

System Power Management Policy API.

**Defines**

**PM_ALL_SUBSTATES**

Special value for 'all substates'.

**Typedefs**

typedef void (*pm_policy_latency_changed_cb_t)(int32_t latency)

Callback to notify when maximum latency changes.

**Param latency**

New maximum latency. Positive value represents latency in microseconds. SYS_FOREVER_US value lifts the latency constraint. Other values are forbidden.

**Functions**

def pm_policy_state_lock_get(enum pm_state state, uint8_t substate_id)

Increase a power state lock counter.

A power state will not be allowed on the first call of pm_policy_state_lock_get(). Subsequent calls will just increase a reference count, thus meaning this API can be safely used concurrently. A state will be allowed again after pm_policy_state_lock_put() is called as many times as pm_policy_state_lock_get().

Note that the PM_STATE_ACTIVE state is always allowed, so calling this API with PM_STATE_ACTIVE will have no effect.

**See also:**

*pm_policy_state_lock_put()*

**Parameters**

- **state** – Power state.
- **substate_id** – Power substate ID. Use PM_ALL_SUBSTATES to affect all the substates in the given power state.
void pm_policy_state_lock_put(enum pm_state state, uint8_t substate_id)
Decrease a power state lock counter.

See also:

pm_policy_state_lock_get()

Parameters

• state – Power state.
• substate_id – Power substate ID. Use PM_ALL_SUBSTATES to affect all the
substates in the given power state.

bool pm_policy_state_lock_is_active(enum pm_state state, uint8_t substate_id)
Check if a power state lock is active (not allowed).

Parameters

• state – Power state.
• substate_id – Power substate ID. Use PM_ALL_SUBSTATES to affect all the
substates in the given power state.

Return values

• true – if power state lock is active.
• false – if power state lock is not active.

void pm_policy_latency_request_add(struct pm_policy_latency_request *req, uint32_t value)
Add a new latency requirement.

The system will not enter any power state that would make the system to exceed the given
latency value.

Parameters

• req – Latency request.
• value – Maximum allowed latency in microseconds.

void pm_policy_latency_request_update(struct pm_policy_latency_request *req, uint32_t value)
Update a latency requirement.

Parameters

• req – Latency request.
• value – New maximum allowed latency in microseconds.

void pm_policy_latency_request_remove(struct pm_policy_latency_request *req)
Remove a latency requirement.

Parameters

• req – Latency request.

void pm_policy_latency_changed_subscribe(struct pm_policy_latency_subscription *req,
  pm_policy_latency_changed_cb_t cb)
Subscribe to maximum latency changes.

Parameters

• req – Subscription request.
• cb – Callback function (NULL to disable).
void pm_policy_latency_changed_unsubscribe(struct pm_policy_latency_subscription *req)
Unsubscribe to maximum latency changes.

Parameters
• req – Subscription request.

struct pm_policy_latency_subscription
#include <policy.h> Latency change subscription.

Public Members

pm_policy_latency_changed_cb_t cb
Notification callback.

struct pm_policy_latency_request
#include <policy.h> Latency request.

Public Members

uint32_t value
Request value.

Hooks

group subsys_pm_sys_hooks
System Power Management Hooks.

Functions

void pm_state_set(enum pm_state state, uint8_t substate_id)
Put processor into a power state.
This function implements the SoC specific details necessary to put the processor into available power states.

Parameters
• state – Power state.
• substate_id – Power substate id.

void pm_state_exit_post_ops(enum pm_state state, uint8_t substate_id)
Do any SoC or architecture specific post ops after sleep state exits.
This function is a place holder to do any operations that may be needed to be done after sleep state exits. Currently it enables interrupts after resuming from sleep state. In future, the enabling of interrupts may be moved into the kernel.

Parameters
• state – Power state.
• substate_id – Power substate id.
Device PM APIs

```c
PM_DEVICE_DEFINE(dev_id, pm_action_cb)
Define device PM resources for the given device name.
```

See also:

```
PM_DEVICE_DT_DEFINE, PM_DEVICE_DT_INST_DEFINE
```

**Note:** This macro is a no-op if `CONFIG_PM_DEVICE` is not enabled.

**Parameters**

- `dev_id` – Device id.
- `pm_action_cb` – PM control callback.

```
PM_DEVICE_DEFINE(node_id, pm_action_cb)
Define device PM resources for the given node identifier.
```

See also:

```
PM_DEVICE_DT_INST_DEFINE, PM_DEVICE_DEFINE
```

**Note:** This macro is a no-op if `CONFIG_PM_DEVICE` is not enabled.

**Parameters**

- `node_id` – Node identifier.
- `pm_action_cb` – PM control callback.

```
PM_DEVICE_DEFINE_INST_DEFINE(idx, pm_action_cb)
Define device PM resources for the given instance.
```

See also:

```
PM_DEVICE_DT_DEFINE, PM_DEVICE_DEFINE
```

**Note:** This macro is a no-op if `CONFIG_PM_DEVICE` is not enabled.

**Parameters**

- `idx` – Instance index.
- `pm_action_cb` – PM control callback.
PM_DEVICE_GET(dev_id)
Obtain a reference to the device PM resources for the given device.

Parameters
• dev_id – Device id.

Returns
Reference to the device PM resources (NULL if device CONFIG_PM_DEVICE is disabled).

PM_DEVICE_DT_GET(node_id)
Obtain a reference to the device PM resources for the given node.

Parameters
• node_id – Node identifier.

Returns
Reference to the device PM resources (NULL if device CONFIG_PM_DEVICE is disabled).

PM_DEVICE_DT_INST_GET(idx)
Obtain a reference to the device PM resources for the given instance.

Parameters
• idx – Instance index.

Returns
Reference to the device PM resources (NULL if device CONFIG_PM_DEVICE is disabled).

Typedefs

typedef int (*pm_device_action_cb_t)(const struct device *dev, enum pm_device_action action)
Device PM action callback.

Param dev
Device instance.

Param action
Requested action.

Retval 0
If successful.

Retval -ENOTSUP
If the requested action is not supported.

Retval Errno
Other negative errno on failure.

typedef bool (*pm_device_action_failed_cb_t)(const struct device *dev, int err)
Device PM action failed callback.

Param dev
Device that failed the action.

Param err
Return code of action failure.

Return
True to continue iteration, false to halt iteration.
**Enums**

enum pm_device_state

Device power states.

*Values:*

enumerator PM_DEVICE_STATE_ACTIVE

Device is in active or regular state.

enumerator PM_DEVICE_STATE_SUSPENDED

Device is suspended.

**Note:** Device context may be lost.

enumerator PM_DEVICE_STATE_SUSPENDING

Device is being suspended.

enumerator PM_DEVICE_STATE_OFF

Device is turned off (power removed).

**Note:** Device context is lost.

enum pm_device_action

Device PM actions.

*Values:*

enumerator PM_DEVICE_ACTION_SUSPEND

Suspend.

enumerator PM_DEVICE_ACTION_RESUME

Resume.

enumerator PM_DEVICE_ACTION_TURN_OFF

Turn off.

**Note:** Action triggered only by a power domain.

enumerator PM_DEVICE_ACTION_TURN_ON

Turn on.

**Note:** Action triggered only by a power domain.

**Functions**
const char *pm_device_state_str(enum pm_device_state state)
Get name of device PM state.

Parameters
• state – State id which name should be returned

int pm_device_action_run(const struct device *dev, enum pm_device_action action)
Run a pm action on a device.
This function calls the device PM control callback so that the device does the necessary operations to execute the given action.

Parameters
• dev – Device instance.
• action – Device pm action.

Return values
• 0 – If successful.
• -ENOTSUP – If requested state is not supported.
• -EALREADY – If device is already at the requested state.
• -EBUSY – If device is changing its state.
• -ENOSYS – If device does not support PM.
• -EPERM – If device has power state locked.
• Errno – Other negative errno on failure.

void pm_device_children_action_run(const struct device *dev, enum pm_device_action action, pm_device_action_failed_cb_t failure_cb)
Run a pm action on all children of a device.
This function calls all child devices PM control callback so that the device does the necessary operations to execute the given action.

Parameters
• dev – Device instance.
• action – Device pm action.
• failure_cb – Function to call if a child fails the action, can be NULL.

int pm_device_state_get(const struct device *dev, enum pm_device_state *state)
Obtain the power state of a device.

Parameters
• dev – Device instance.
• state – Pointer where device power state will be stored.

Return values
• 0 – If successful.
• -ENOSYS – If device does not implement power management.

static inline void pm_device_init_suspended(const struct device *dev)
Initialize a device state to PM_DEVICE_STATE_SUSPENDED.
By default device state is initialized to PM_DEVICE_STATE_ACTIVE. However in order to save power some drivers may choose to only initialize the device to the suspended state, or actively put the device into the suspended state. This function can therefore be used to notify the PM subsystem that the device is in PM_DEVICE_STATE_SUSPENDED instead of the default.
Parameters

- `dev` – Device instance.

static inline void pm_device_init_off(const struct device *dev)

Initialize a device state to `PM_DEVICE_STATE_OFF`.

By default device state is initialized to `PM_DEVICE_STATE_ACTIVE`. In general, this makes sense because the device initialization function will resume and configure a device, leaving it operational. However, when power domains are enabled, the device may be connected to a switchable power source, in which case it won't be powered at boot. This function can therefore be used to notify the PM subsystem that the device is in `PM_DEVICE_STATE_OFF` instead of the default.

Parameters

- `dev` – Device instance.

void pm_device_busy_set(const struct device *dev)

Mark a device as busy.

Devices marked as busy will not be suspended when the system goes into low-power states. This can be useful if, for example, the device is in the middle of a transaction.

See also:

`pm_device_busy_clear()`

Parameters

- `dev` – Device instance.

void pm_device_busy_clear(const struct device *dev)

Clear a device busy status.

See also:

`pm_device_busy_set()`

Parameters

- `dev` – Device instance.

bool pm_device_is_any_busy(void)

Check if any device is busy.

Return values

- `false` – If no device is busy
- `true` – If one or more devices are busy

bool pm_device_is_busy(const struct device *dev)

Check if a device is busy.

Parameters

- `dev` – Device instance.

Return values

- `false` – If the device is not busy
- `true` – If the device is busy
bool pm_device_wakeup_enable(const struct device *dev, bool enable)
Enable or disable a device as a wake up source.

A device marked as a wake up source will not be suspended when the system goes into low-power modes, thus allowing to use it as a wake up source for the system.

Parameters
- dev – Device instance.
- enable – true to enable or false to disable

Return values
- true – If the wakeup source was successfully enabled.
- false – If the wakeup source was not successfully enabled.

bool pm_device_wakeup_is_enabled(const struct device *dev)
Check if a device is enabled as a wake up source.

Parameters
- dev – Device instance.

Return values
- true – if the wakeup source is enabled.
- false – if the wakeup source is not enabled.

bool pm_device_wakeup_is_capable(const struct device *dev)
Check if a device is wake up capable.

Parameters
- dev – Device instance.

Return values
- true – If the device is wake up capable.
- false – If the device is not wake up capable.

void pm_device_state_lock(const struct device *dev)
Lock current device state.

This function locks the current device power state. Once locked the device power state will not be changed by system power management or device runtime power management until unlocked.

See also:
- pm_device_state_unlock

Note: The given device should not have device runtime enabled.

Parameters
- dev – Device instance.

void pm_device_state_unlock(const struct device *dev)
Unlock the current device state.

Unlocks a previously locked device pm.
See also:

`pm_device_state_lock`

**Parameters**

- `dev` – Device instance.

```c
bool pm_device_state_is_locked(const struct device *dev)
```

Check if the device pm is locked.

**Parameters**

- `dev` – Device instance.

**Return values**

- `true` – If device is locked.
- `false` – If device is not locked.

```c
bool pm_device_on_power_domain(const struct device *dev)
```

Check if the device is on a switchable power domain.

**Parameters**

- `dev` – Device instance.

**Return values**

- `true` – If device is on a switchable power domain.
- `false` – If device is not on a switchable power domain.

```c
int pm_device_power_domain_add(const struct device *dev, const struct device *domain)
```

Add a device to a power domain.

This function adds a device to a given power domain.

**Parameters**

- `dev` – Device to be added to the power domain.
- `domain` – Power domain.

**Return values**

- `0` – If successful.
- `-EALREADY` – If device is already part of the power domain.
- `-ENOSYS` – If the application was built without power domain support.
- `-ENOSPC` – If there is no space available in the power domain to add the device.

```c
int pm_device_power_domain_remove(const struct device *dev, const struct device *domain)
```

Remove a device from a power domain.

This function removes a device from a given power domain.

**Parameters**

- `dev` – Device to be removed from the power domain.
- `domain` – Power domain.

**Return values**

- `0` – If successful.
- `-ENOSYS` – If the application was built without power domain support.
- `-ENOTENT` – If device is not in the given domain.
bool pm_device_is_powered(const struct device *dev)
Check if the device is currently powered.

Parameters
• dev – Device instance.

Return values
• true – If device is currently powered
• false – If device is not currently powered

struct pm_device
#include <device.h> Device PM info.

Public Members

const struct device *dev
Pointer to the device

struct k_mutex lock
Lock to synchronize the get/put operations

uint32_t usage
Device usage count

struct k_work_delayable work
Work object for asynchronous calls

struct k_condvar condvar
Event conditional var to listen to the sync request events

enum pm_device_state state
Device power state

pm_device_action_cb_t action_cb
Device PM action callback

Device Runtime PM APIs

group subsys_pm_device_runtime
Device Runtime Power Management API.

Functions

int pm_device_runtime_enable(const struct device *dev)
Enable device runtime PM.
This function will enable runtime PM on the given device. If the device is in
PMDEVICESTATEACTIVE state, the device will be suspended.
See also:

\texttt{pm_device_init_suspended()}

\textbf{Function properties (list may not be complete)}

\texttt{pre-kernel-ok}

\textbf{Parameters}

- \texttt{dev} – Device instance.

\textbf{Return values}

- \texttt{0} – If the device runtime PM is enabled successfully.
- \texttt{-EPERM} – If device has power state locked.
- \texttt{-ENOTSUP} – If the device does not support PM.
- \texttt{-ENOSYS} – If the functionality is not available.
- \texttt{-errno} – Other negative \texttt{errno}, result of suspending the device.

\begin{verbatim}
int pm_device_runtime_disable(const struct device *dev)
\end{verbatim}

Disable device runtime PM.
If the device is currently suspended it will be resumed.

\textbf{Function properties (list may not be complete)}

\texttt{pre-kernel-ok}

\textbf{Parameters}

- \texttt{dev} – Device instance.

\textbf{Return values}

- \texttt{0} – If the device runtime PM is disabled successfully.
- \texttt{-ENOTSUP} – If the device does not support PM.
- \texttt{-ENOSYS} – If the functionality is not available.
- \texttt{-errno} – Other negative \texttt{errno}, result of resuming the device.

\begin{verbatim}
int pm_device_runtime_get(const struct device *dev)
\end{verbatim}

Resume a device based on usage count.
This function will resume the device if the device is suspended (usage count equal to 0). In case of a resume failure, usage count and device state will be left unchanged. In all other cases, usage count will be incremented.

If the device is still being suspended as a result of calling \texttt{pm_device_runtime_put_async()}, this function will wait for the operation to finish to then resume the device.

\textbf{Function properties (list may not be complete)}

\texttt{pre-kernel-ok}

\textbf{Parameters}

- \texttt{dev} – Device instance.

\textbf{Return values}

- \texttt{0} – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
• -ENOTSUP – If the device does not support PM.
• -errno – Other negative errno, result of the PM action callback.

```c
int pm_device_runtime_put(const struct device *dev)
```

Suspend a device based on usage count.

This function will suspend the device if the device is no longer required (usage count equal to 0). In case of suspend failure, usage count and device state will be left unchanged. In all other cases, usage count will be decremented (down to 0).

**See also:**

`pm_device_runtime_put_async()`

**Function properties (list may not be complete)**

`pre-kernel-ok`

**Parameters**

• `dev` – Device instance.

**Return values**

• 0 – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
• -ENOTSUP – If the device does not support PM.
• -EALREADY – If device is already suspended (can only happen if get/put calls are unbalanced).
• -errno – Other negative errno, result of the action callback.

```c
int pm_device_runtime_put_async(const struct device *dev)
```

Suspend a device based on usage count (asynchronously).

This function will schedule the device suspension if the device is no longer required (usage count equal to 0). In all other cases, usage count will be decremented (down to 0).

**See also:**

`pm_device_runtime_put()`

**Function properties (list may not be complete)**

`pre-kernel-ok, async`

**Note:** Asynchronous operations are not supported when in pre-kernel mode. In this case, the function will be blocking (equivalent to `pm_device_runtime_put()`).

**Parameters**

• `dev` – Device instance.

**Return values**

• 0 – If it succeeds. In case device runtime PM is not enabled or not available this function will be a no-op and will also return 0.
• -ENOTSUP – If the device does not support PM.
bool pm_device_runtime_is_enabled(const struct device *dev)
Check if device runtime is enabled for a given device.

See also:

pm_device_runtime_enable()

Function properties (list may not be complete)
pre-kernel-ok

Parameters
• dev – Device instance.

Return values
• true – If device has device runtime PM enabled.
• false – If the device has device runtime PM disabled.

4.13 OS Abstraction

OS abstraction layers (OSAL) provide wrapper function APIs that encapsulate common system functions offered by any operating system. These APIs make it easier and quicker to develop for, and port code to multiple software and hardware platforms.

These sections describe the software and hardware abstraction layers supported by the Zephyr RTOS.

4.13.1 POSIX Support

The Portable Operating System Interface (POSIX) is a family of standards specified by the IEEE Computer Society for maintaining compatibility between operating systems. Zephyr implements a subset of the embedded profiles PSE51 and PSE52, and BSD Sockets API.

With the POSIX support available in Zephyr, an existing POSIX compliant application can be ported to run on the Zephyr kernel, and therefore leverage Zephyr features and functionality. Additionally, a library designed for use with POSIX threading compatible operating systems can be ported to Zephyr kernel based applications with minimal or no changes.

The POSIX API subset is an increasingly popular OSAL (operating system abstraction layer) for IoT and embedded applications, as can be seen in Zephyr, AWS:FreeRTOS, TI-RTOS, and NuttX.

Benefits of POSIX support in Zephyr include:
• Offering a familiar API to non-embedded programmers, especially from Linux
• Enabling reuse (portability) of existing libraries based on POSIX APIs
• Providing an efficient API subset appropriate for small (MCU) embedded systems

System Overview

Units of Functionality  The system profile is defined in terms of component profiles that specify Units of Functionality that can be combined to realize the application platform. A Unit of Functionality is a defined set of services which can be implemented. If implemented, the standard prescribes that all services in the Unit must be implemented.
A Minimal Realtime System Profile implementation must support the following Units of Functionality as defined in IEEE Std. 1003.1 (also referred to as POSIX.1-2017).

**Table 4.4: Units of Functionality**

<table>
<thead>
<tr>
<th>Requirements</th>
<th>Supported</th>
<th>Remarks</th>
</tr>
</thead>
<tbody>
<tr>
<td>POSIX_C_LANG_JUMP</td>
<td></td>
<td></td>
</tr>
<tr>
<td>POSIX_C_LANG_SUPPORT</td>
<td>yes</td>
<td></td>
</tr>
<tr>
<td>POSIX_DEVICE_IO</td>
<td></td>
<td></td>
</tr>
<tr>
<td>POSIX_FILE_LOCKING</td>
<td></td>
<td></td>
</tr>
<tr>
<td>POSIX_SIGNALS</td>
<td></td>
<td></td>
</tr>
<tr>
<td>POSIX_SINGLE_PROCESS</td>
<td>yes</td>
<td></td>
</tr>
<tr>
<td>POSIX_THREADS_BASE</td>
<td></td>
<td></td>
</tr>
<tr>
<td>XSI_THREAD_MUTEX_EXT</td>
<td>yes</td>
<td></td>
</tr>
<tr>
<td>XSI_THREADS_EXT</td>
<td>yes</td>
<td></td>
</tr>
</tbody>
</table>

**Option Requirements**  An implementation supporting the Minimal Realtime System Profile must support the POSIX.1 Option Requirements which are defined in the standard. Options Requirements are used for further sub-profiling within the units of functionality: they further define the functional behavior of the system service (normally adding extra functionality). Depending on the profile to which the POSIX implementation complies, parameters and/or the precise functionality of certain services may differ.

The following list shows the option requirements that are implemented in Zephyr.
## Units of Functionality

This section describes the Units of Functionality (fixed sets of interfaces) which are implemented (partially or completely) in Zephyr. Please refer to the standard for a full description of each listed interface.

### POSIX_THREADS_BASE

The basic assumption in this profile is that the system consists of a single (implicit) process with multiple threads. Therefore, the standard requires all basic thread services, except those related to multiple processes.

#### Table 4.6: POSIX_THREADS_BASE

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_atfork()</td>
<td></td>
</tr>
<tr>
<td>pthread_attr_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getdetachstate()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_getschedparam()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setdetachstate()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setschedparam()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cancel()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cleanup_pop()</td>
<td></td>
</tr>
<tr>
<td>pthread_cleanup_push()</td>
<td></td>
</tr>
<tr>
<td>pthread_cond_broadcast()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_destroy()</td>
<td></td>
</tr>
<tr>
<td>pthread_cond_destroy()</td>
<td></td>
</tr>
<tr>
<td>pthread_cond_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_signal()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_timedwait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_cond_wait()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_condattr_destroy()</td>
<td></td>
</tr>
</tbody>
</table>

continues on next page
<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_condattr_init()</td>
<td></td>
</tr>
<tr>
<td>pthread_create()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_detach()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_equal()</td>
<td></td>
</tr>
<tr>
<td>pthread_exit()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_getspecific()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_join()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_key_create()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_key_delete()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_kill()</td>
<td></td>
</tr>
<tr>
<td>pthread_mutex_destroy()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_init()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_lock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_trylock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutex_unlock()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_destroy()</td>
<td></td>
</tr>
<tr>
<td>pthread_mutexattr_init()</td>
<td></td>
</tr>
<tr>
<td>pthread_once()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_self()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_setcancelstate()</td>
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</tr>
<tr>
<td>pthread_setcanceltype()</td>
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</tr>
<tr>
<td>pthread_setspecific()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_sigmask()</td>
<td></td>
</tr>
<tr>
<td>pthread_testcancel()</td>
<td></td>
</tr>
</tbody>
</table>

**XSI_THREADS_EXT**  The XSI_THREADS_EXT Unit of Functionality is required because it provides functions to control a thread's stack. This is considered useful for any real-time application.

This table lists service support status in Zephyr:

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_attr_getguardsize()</td>
<td></td>
</tr>
<tr>
<td>pthread_attr_getstack()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_attr_setguardsize()</td>
<td></td>
</tr>
<tr>
<td>pthread_attr_setstack()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_getconcurrency()</td>
<td></td>
</tr>
<tr>
<td>pthread_setconcurrency()</td>
<td></td>
</tr>
</tbody>
</table>

**XSI_THREAD_MUTEX_EXT**  The XSI_THREAD_MUTEX_EXT Unit of Functionality is required because it has options for controlling the behavior of mutexes under erroneous application use.

This table lists service support status in Zephyr:

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_mutexattr_gettype()</td>
<td>yes</td>
</tr>
<tr>
<td>pthread_mutexattr_settype()</td>
<td>yes</td>
</tr>
</tbody>
</table>

**POSIX_C_LANG_SUPPORT**  The POSIX_C_LANG_SUPPORT Unit of Functionality contains the general ISO C Library.

4.13. OS Abstraction
This is implemented as part of the minimal C library available in Zephyr.

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>abs()</td>
<td>yes</td>
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<tr>
<td>asctime()</td>
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</tr>
<tr>
<td>asctime_r()</td>
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<tr>
<td>atof()</td>
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<tr>
<td>atoi()</td>
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<tr>
<td>atol()</td>
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<td>atoll()</td>
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<td>bsearch()</td>
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<td>calfc()</td>
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<td>ctime_r()</td>
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<td>difftime()</td>
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<td>div()</td>
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<tr>
<td>feclearexcept()</td>
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<tr>
<td>fegetenv()</td>
<td></td>
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<tr>
<td>fegetexceptflag()</td>
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<td>fegetround()</td>
<td></td>
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<td>feholdexcept()</td>
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<td>feraiseexcept()</td>
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<td>fesetenv()</td>
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<td>fesetexceptflag()</td>
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<td>fesetround()</td>
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<td>fetestexcept()</td>
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<td>feupdateenv()</td>
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<td>free()</td>
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<td>gmtime_r()</td>
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<td>imaxabs()</td>
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<td>imaxdiv()</td>
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<td>isalnum()</td>
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<td>isblank()</td>
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<td>iscnd()</td>
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<td>isdigit()</td>
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<td>isgraph()</td>
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<td>islower()</td>
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<td>ispunct()</td>
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<td>ldiv()</td>
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<td>lldiv()</td>
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<td>localeconv()</td>
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<td>localtime()</td>
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<td>localtime_r()</td>
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<td>malloc()</td>
<td>yes</td>
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<tr>
<td>memchr()</td>
<td>yes</td>
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<tr>
<td>memcmp()</td>
<td>yes</td>
</tr>
</tbody>
</table>

continues on next page
Table 4.9 – continued from previous page

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
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</thead>
<tbody>
<tr>
<td>memcpy()</td>
<td>yes</td>
</tr>
<tr>
<td>memmove()</td>
<td>yes</td>
</tr>
<tr>
<td>memset()</td>
<td>yes</td>
</tr>
<tr>
<td>mktime()</td>
<td>yes</td>
</tr>
<tr>
<td>qsort()</td>
<td></td>
</tr>
<tr>
<td>rand()</td>
<td>yes</td>
</tr>
<tr>
<td>realloc()</td>
<td>yes</td>
</tr>
<tr>
<td>setlocale()</td>
<td></td>
</tr>
<tr>
<td>snprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>sprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>srand()</td>
<td>yes</td>
</tr>
<tr>
<td>sscanf()</td>
<td></td>
</tr>
<tr>
<td>strcat()</td>
<td>yes</td>
</tr>
<tr>
<td>strchr()</td>
<td>yes</td>
</tr>
<tr>
<td>strcmp()</td>
<td>yes</td>
</tr>
<tr>
<td>strcoll()</td>
<td></td>
</tr>
<tr>
<td>strcpy()</td>
<td>yes</td>
</tr>
<tr>
<td>strcspn()</td>
<td></td>
</tr>
<tr>
<td>strerror()</td>
<td>yes</td>
</tr>
<tr>
<td>strerror_r()</td>
<td>yes</td>
</tr>
<tr>
<td>strftime()</td>
<td></td>
</tr>
<tr>
<td>strlen()</td>
<td>yes</td>
</tr>
<tr>
<td>strncat()</td>
<td>yes</td>
</tr>
<tr>
<td>strncmp()</td>
<td>yes</td>
</tr>
<tr>
<td>strncpy()</td>
<td>yes</td>
</tr>
<tr>
<td>strpbrk()</td>
<td></td>
</tr>
<tr>
<td>strrev()</td>
<td></td>
</tr>
<tr>
<td>strptime()</td>
<td></td>
</tr>
<tr>
<td>strspn()</td>
<td></td>
</tr>
<tr>
<td>strstr()</td>
<td>yes</td>
</tr>
<tr>
<td>strtol()</td>
<td>yes</td>
</tr>
<tr>
<td>strtof()</td>
<td>yes</td>
</tr>
<tr>
<td>strtoll()</td>
<td>yes</td>
</tr>
<tr>
<td>strtoull()</td>
<td>yes</td>
</tr>
<tr>
<td>strtoumax()</td>
<td></td>
</tr>
<tr>
<td>strtok()</td>
<td></td>
</tr>
<tr>
<td>strdup()</td>
<td></td>
</tr>
<tr>
<td>vsnprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>vsprintf()</td>
<td>yes</td>
</tr>
</tbody>
</table>

4.13. OS Abstraction
POSIX_SINGLE_PROCESS  The POSIX_SINGLE_PROCESS Unit of Functionality contains services for single process applications.

Table 4.10: POSIX_SINGLE_PROCESS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>confstr()</td>
<td></td>
</tr>
<tr>
<td>environ</td>
<td></td>
</tr>
<tr>
<td>errno</td>
<td></td>
</tr>
<tr>
<td>getenv()</td>
<td></td>
</tr>
<tr>
<td>setenv()</td>
<td></td>
</tr>
<tr>
<td>sysconf()</td>
<td></td>
</tr>
<tr>
<td>uname()</td>
<td></td>
</tr>
<tr>
<td>unsetenv()</td>
<td></td>
</tr>
</tbody>
</table>

POSIX_SIGNALS  Signal services are a basic mechanism within POSIX-based systems and are required for error and event handling.

Table 4.11: POSIX_SIGNALS

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>abort()</td>
<td>yes</td>
</tr>
<tr>
<td>alarm()</td>
<td></td>
</tr>
<tr>
<td>kill()</td>
<td></td>
</tr>
<tr>
<td>pause()</td>
<td></td>
</tr>
<tr>
<td>raise()</td>
<td></td>
</tr>
<tr>
<td>sigaction()</td>
<td></td>
</tr>
<tr>
<td>igaddset()</td>
<td></td>
</tr>
<tr>
<td>sigdelset()</td>
<td></td>
</tr>
<tr>
<td>sigemptyset()</td>
<td></td>
</tr>
<tr>
<td>sigfillset()</td>
<td></td>
</tr>
<tr>
<td>igismember()</td>
<td></td>
</tr>
<tr>
<td>signal()</td>
<td></td>
</tr>
<tr>
<td>sigpending()</td>
<td></td>
</tr>
<tr>
<td>sigprocmask()</td>
<td></td>
</tr>
<tr>
<td>igsuspend()</td>
<td></td>
</tr>
<tr>
<td>sigwait()</td>
<td></td>
</tr>
</tbody>
</table>

POSIX_DEVICE_IO

Table 4.12: POSIX_DEVICE_IO

<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>flockfile()</td>
<td></td>
</tr>
<tr>
<td>ftrylockfile()</td>
<td></td>
</tr>
<tr>
<td>funlockfile()</td>
<td></td>
</tr>
<tr>
<td>getc_unlocked()</td>
<td></td>
</tr>
<tr>
<td>getc_unlocked()</td>
<td></td>
</tr>
<tr>
<td>putc_unlocked()</td>
<td></td>
</tr>
<tr>
<td>putc_unlocked()</td>
<td></td>
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<tr>
<td>putc_unlocked()</td>
<td></td>
</tr>
<tr>
<td>putc_unlocked()</td>
<td></td>
</tr>
</tbody>
</table>

continues on next page
<table>
<thead>
<tr>
<th>API</th>
<th>Supported</th>
</tr>
</thead>
<tbody>
<tr>
<td>clearerr()</td>
<td></td>
</tr>
<tr>
<td>close()</td>
<td></td>
</tr>
<tr>
<td>fclose()</td>
<td></td>
</tr>
<tr>
<td>fdopen()</td>
<td></td>
</tr>
<tr>
<td>feof()</td>
<td></td>
</tr>
<tr>
<td>ferror()</td>
<td></td>
</tr>
<tr>
<td>fflush()</td>
<td></td>
</tr>
<tr>
<td>fgetc()</td>
<td></td>
</tr>
<tr>
<td>fgets()</td>
<td></td>
</tr>
<tr>
<td>fileno()</td>
<td></td>
</tr>
<tr>
<td>fopen()</td>
<td></td>
</tr>
<tr>
<td>fprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>fputc()</td>
<td>yes</td>
</tr>
<tr>
<td>fputs()</td>
<td>yes</td>
</tr>
<tr>
<td>fread()</td>
<td>yes</td>
</tr>
<tr>
<td>freopen()</td>
<td></td>
</tr>
<tr>
<td>fscanf()</td>
<td></td>
</tr>
<tr>
<td>fwrite()</td>
<td>yes</td>
</tr>
<tr>
<td>getc()</td>
<td></td>
</tr>
<tr>
<td>getchar()</td>
<td></td>
</tr>
<tr>
<td>gets()</td>
<td></td>
</tr>
<tr>
<td>open()</td>
<td>yes</td>
</tr>
<tr>
<td>perror()</td>
<td>yes</td>
</tr>
<tr>
<td>printf()</td>
<td>yes</td>
</tr>
<tr>
<td>putc()</td>
<td>yes</td>
</tr>
<tr>
<td>putchar()</td>
<td>yes</td>
</tr>
<tr>
<td>puts()</td>
<td></td>
</tr>
<tr>
<td>read()</td>
<td>yes</td>
</tr>
<tr>
<td>scanf()</td>
<td></td>
</tr>
<tr>
<td>setbuf()</td>
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<tr>
<td>setvbuf()</td>
<td></td>
</tr>
<tr>
<td>stderr</td>
<td></td>
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<tr>
<td>stdin</td>
<td></td>
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<tr>
<td>stdout</td>
<td></td>
</tr>
<tr>
<td>ungetc()</td>
<td></td>
</tr>
<tr>
<td>vfprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>vfscanf()</td>
<td></td>
</tr>
<tr>
<td>vprintf()</td>
<td>yes</td>
</tr>
<tr>
<td>vscanf()</td>
<td></td>
</tr>
<tr>
<td>write()</td>
<td></td>
</tr>
</tbody>
</table>

### 4.13.2 CMSIS RTOS v1

Cortex-M Software Interface Standard (CMSIS) RTOS is a vendor-independent hardware abstraction layer for the ARM Cortex-M processor series and defines generic tool interfaces. Though it was originally defined for ARM Cortex-M microcontrollers alone, it could be easily extended to other microcontrollers making it generic. For more information on CMSIS RTOS v1, please refer [http://www.keil.com/pack/doc/CMSIS/RTOS/html/index.html](http://www.keil.com/pack/doc/CMSIS/RTOS/html/index.html)
4.13.3 CMSIS RTOS v2

Cortex-M Software Interface Standard (CMSIS) RTOS is a vendor-independent hardware abstraction layer for the ARM Cortex-M processor series and defines generic tool interfaces. Though it was originally defined for ARM Cortex-M microcontrollers alone, it could be easily extended to other microcontrollers making it generic. For more information on CMSIS RTOS v2, please refer to the CMSIS-RTOS2 Documentation.

Features not supported in Zephyr implementation

**Kernel**
- `osKernelGetState`, `osKernelSuspend`, `osKernelResume`, `osKernelInitialize` and `osKernelStart` are not supported.

**Mutex**
- `osMutexPrioInherit` is supported by default and is not configurable, you cannot select/unselect this attribute.
- `osMutexRecursive` is also supported by default. If this attribute is not set, an error is thrown when the same thread tries to acquire it the second time.
- `osMutexRobust` is not supported in Zephyr.

Return values not supported in the Zephyr implementation

- `osKernelUnlock`, `osKernelLock`, `osKernelRestoreLock`
- `osError` (Unspecified error) is not supported.
- `osSemaphoreDelete`
- `osErrorResource` (the semaphore specified by parameter semaphore_id is in an invalid semaphore state) is not supported.
- `osMutexDelete`
- `osErrorResource` (mutex specified by parameter mutex_id is in an invalid mutex state) is not supported.
- `osTimerDelete`
- `osErrorResource` (the timer specified by parameter timer_id is in an invalid timer state) is not supported.
- `osMessageQueueReset`
- `osErrorResource` (the message queue specified by parameter msgq_id is in an invalid message queue state) is not supported.
- `osMessageQueueDelete`
- `osErrorResource` (the message queue specified by parameter msgq_id is in an invalid message queue state) is not supported.
- `osMemoryPoolFree`
- `osErrorResource` (the memory pool specified by parameter mp_id is in an invalid memory pool state) is not supported.
- `osMemoryPoolDelete`
- `osErrorResource` (the memory pool specified by parameter mp_id is in an invalid memory pool state) is not supported.
- `osEventFlagsSet`, `osEventFlagsClear`
- `osFlagsErrorUnknown` (Unspecified error) and `osFlagsErrorResource` (Event flags object specified by parameter ef_id is not ready to be used) are not supported.
- `osEventFlagsDelete`
- `osErrorParameter` (the value of the parameter ef_id is incorrect) is not supported.
osThreadFlagsSet
  osFlagsErrorUnknown (Unspecified error) and osFlagsErrorResource (Thread specified by parameter thread_id is not active to receive flags) are not supported.

osThreadFlagsClear
  osFlagsErrorResource (Running thread is not active to receive flags) is not supported.

osDelayUntil
  osParameter (the time cannot be handled) is not supported.

4.14 Shell

- Overview
  - Connecting to Segger RTT via TCP (on macOS, for example)
- Commands
  - Creating commands
  - Dictionary commands
  - Commands execution
  - Built-in commands
- Tab Feature
- History Feature
- Wildcards Feature
- Meta Keys Feature
- Getopt Feature
- Obscured Input Feature
- Shell Logger Backend Feature
- Usage
- API Reference

4.14.1 Overview

This module allows you to create and handle a shell with a user-defined command set. You can use it in examples where more than simple button or LED user interaction is required. This module is a Unix-like shell with these features:

- Support for multiple instances.
- Advanced cooperation with the Logging.
- Support for static and dynamic commands.
- Support for dictionary commands.
- Smart command completion with the Tab key.
- Built-in commands: clear, shell, colors, echo, history and resize.
- Viewing recently executed commands using keys: ↑ ↓ or meta keys.
• Support for ANSI escape codes: VT100 and \texttt{ESC[n~} for cursor control and color printing.
• Support for editing multiline commands.
• Built-in handler to display help for the commands.
• Support for wildcards: * and ?.
• Support for meta keys.
• Support for getopt and getopt\_long.
• Kconfig configuration to optimize memory usage.

\textbf{Note:} Some of these features have a significant impact on RAM and flash usage, but many can be disabled when not needed. To default to options which favor reduced RAM and flash requirements instead of features, you should enable CONFIG\_SHELL\_MINIMAL and selectively enable just the features you want.

The module can be connected to any transport for command input and output. At this point, the following transport layers are implemented:

• Segger RTT
• SMP
• Telnet
• UART
• USB
• DUMMY - not a physical transport layer.

\textbf{Connecting to Segger RTT via TCP (on macOS, for example)}

On macOS JLinkRTTClient won’t let you enter input. Instead, please use following procedure:

• Open up a first Terminal window and enter:

\begin{verbatim}
JLinkRTTLogger -Device NRF52840\_XXAA -RTTChannel 1 -if SWD -Speed 4000 ~/rtt.log
\end{verbatim}

(change device if required)

• Open up a second Terminal window and enter:

\begin{verbatim}
nc localhost 19021
\end{verbatim}

• Now you should have a network connection to RTT that will let you enter input to the shell.

\textbf{4.14.2 Commands}

Shell commands are organized in a tree structure and grouped into the following types:

• Root command (level 0): Gathered and alphabetically sorted in a dedicated memory section.
• Static subcommand (level > 0): Number and syntax must be known during compile time. Created in the software module.
• Dynamic subcommand (level > 0): Number and syntax does not need to be known during compile time. Created in the software module.
Creating commands

Use the following macros for adding shell commands:

- **SHELL_CMD_REGISTER** - Create root command. All root commands must have different name.
- **SHELL_COND_CMD_REGISTER** - Conditionally (if compile time flag is set) create root command. All root commands must have different name.
- **SHELL_CMD_ARG_REGISTER** - Create root command with arguments. All root commands must have different name.
- **SHELL_COND_CMD_ARG_REGISTER** - Conditionally (if compile time flag is set) create root command with arguments. All root commands must have different name.
- **SHELL_CMD** - Initialize a command.
- **SHELL_COND_CMD** - Initialize a command if compile time flag is set.
- **SHELL_EXPR_CMD** - Initialize a command if compile time expression is non-zero.
- **SHELL_CMD_ARG** - Initialize a command with arguments.
- **SHELL_COND_CMD_ARG** - Initialize a command with arguments if compile time flag is set.
- **SHELL_EXPR_CMD_ARG** - Initialize a command with arguments if compile time expression is non-zero.
- **SHELL_STATIC_SUBCMD_SET_CREATE** - Create a static subcommands array.
- **SHELL_SUBCMD_DICT_SET_CREATE** - Create a dictionary subcommands array.
- **SHELL_DYNAMIC_CMD_CREATE** - Create a dynamic subcommands array.

Commands can be created in any file in the system that includes `include/zephyr/shell/shell.h`. All created commands are available for all shell instances.

**Static commands**  
Example code demonstrating how to create a root command with static subcommands.

```c
/* Creating subcommands (level 1 command) array for command "demo". */
SHELL_STATIC_SUBCMD_SET_CREATE(sub_demo,
    SHELL_CMD(params, NULL, "Print params command.", cmd_demo_params),
    SHELL_CMD(ping, NULL, "Ping command.", cmd_demo_ping),
    SHELL_SUBCMD_SET_END
);
/* Creating root (level 0) command "demo" */
SHELL_CMD_REGISTER(demo, &sub_demo, "Demo commands", NULL);
```

Example implementation can be found under following location: `samples/subsys/shell/shell_module/src/main.c`.  

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Dictionary commands

This is a special kind of static commands. Dictionary commands can be used every time you want to use a pair: (string <-> corresponding data) in a command handler. The string is usually a verbal description of a given data. The idea is to use the string as a command syntax that can be prompted by the shell and corresponding data can be used to process the command.

Let's use an example. Suppose you created a command to set an ADC gain. It is a perfect place where a dictionary can be used. The dictionary would be a set of pairs: (string: gain_value, int: value) where int value could be used with the ADC driver API.

Abstract code for this task would look like this:

```c
static int gain_cmd_handler(const struct shell *shell, size_t argc, char **argv, void *data)
{
    int gain;

    // data is a value corresponding to called command syntax */
    gain = (int)data;
    adc_set_gain(gain);

    shell_print(shell, "ADC gain set to: %s\n"
               "Value send to ADC driver: %d",
               argv[0],
               gain);

    return 0;
}
```

SHELL_SUBCMD_DICT_SET_CREATE(sub_gain, gain_cmd_handler,
      (gain_1, 1), (gain_2, 2), (gain_1_2, 3), (gain_1_4, 4)
    );
SHELL_CMD_REGISTER(gain, &sub_gain, "Set ADC gain", NULL);

This is how it would look like in the shell:

```
uart:--$ gain ga
    gain_1  gain_2  gain_1_2  gain_1_4
uart:--$ gain gain_1
      ADC gain set to: gain_1
      Value send to ADC driver: 1
uart:--$ gain gain_2
      ADC gain set to: gain_2
      Value send to ADC driver: 2
uart:--$ gain gain_1_2
      ADC gain set to: gain_1_2
      Value send to ADC driver: 3
uart:--$ gain gain_1_4
      ADC gain set to: gain_1_4
      Value send to ADC driver: 4
uart:--$
```

Dynamic commands  Example code demonstrating how to create a root command with static and dynamic subcommands. At the beginning dynamic command list is empty. New commands can be added by typing:
dynamic add <new_dynamic_command>

Newly added commands can be prompted or autocompleted with the Tab key.

```c
/* Buffer for 10 dynamic commands */
static char dynamic_cmd_buffer[10][50];

/* commands counter */
static uint8_t dynamic_cmd_cnt;

/* Function returning command dynamically created * in dynamic_cmd_buffer. */
static void dynamic_cmd_get(size_t idx, struct shell_static_entry *entry)
{
    if (idx < dynamic_cmd_cnt) {
        entry->syntax = dynamic_cmd_buffer[idx];
        entry->handler = NULL;
        entry->subcmd = NULL;
        entry->help = "Show dynamic command name."
    } else {
        /* if there are no more dynamic commands available * syntax must be set to NULL. */
        entry->syntax = NULL;
    }
}

SHELL_DYNAMIC_CMD_CREATE(m_sub_dynamic_set, dynamic_cmd_get);
SHELL_STATIC_SUBCMD_SET_CREATE(m_sub_dynamic, 
    SHELL_CMD(add, NULL, "Add new command to dynamic_cmd_buffer and" 
        " sort them alphabetically.", cmd_dynamic_add),
    SHELL_CMD(execute, &m_sub_dynamic_set, 
        "Execute a command.", cmd_dynamic_execute),
    SHELL_CMD(remove, &m_sub_dynamic_set, 
        "Remove a command from dynamic_cmd_buffer.", 
        cmd_dynamic_remove),
    SHELL_CMD(show, NULL, 
        "Show all commands in dynamic_cmd_buffer.", 
        cmd_dynamic_show),
```

(continues on next page)
Example implementation can be found under following location: samples/subsys/shell/shell_module/src/dynamic_cmd.c.

Commands execution

Each command or subcommand may have a handler. The shell executes the handler that is found deepest in the command tree and further subcommands (without a handler) are passed as arguments. Characters within parentheses are treated as one argument. If shell won't find a handler it will display an error message.

Commands can be also executed from a user application using any active backend and a function `shell_execute_cmd()`, as shown in this example:

```c
void main(void)
{
    /* Below code will execute "clear" command on a DUMMY backend */
    shell_execute_cmd(NULL, "clear");

    /* Below code will execute "shell colors off" command on * an UART backend */
    shell_execute_cmd(shell_backend_uart_get_ptr(), "shell colors off");
}
```

Enable the DUMMY backend by setting the Kconfig `CONFIG_SHELL_BACKEND_DUMMY` option.

Command handler  Simple command handler implementation:

```c
static int cmd_handler(const struct shell *shell, size_t argc, char **argv)
{
    ARG_UNUSED(argc);
    ARG_UNUSED(argv);

    shell_fprintf(shell, SHELL_INFO, "Print info message\n");
    shell_print(shell, "Print simple text.");
    shell_warn(shell, "Print warning text.");
    shell_error(shell, "Print error text.");

    return 0;
}
```

Function `shell_fprintf()` or the shell print macros: `shell_print`, `shell_info`, `shell_warn` and `shell_error` can be used from the command handler or from threads, but not from an interrupt context. Instead, interrupt handlers should use `Logging` for printing.
Command help Every user-defined command or subcommand can have its own help description. The help for commands and subcommands can be created with respective macros: `SHELL_CMD_REGISTER`, `SHELL_CMD_ARG_REGISTER`, `SHELL_CMD`, and `SHELL_CMD_ARG`.

Shell prints this help message when you call a command or subcommand with `-h` or `--help` parameter.

Parent commands In the subcommand handler, you can access both the parameters passed to commands or the parent commands, depending on how you index `argv`.

- When indexing `argv` with positive numbers, you can access the parameters.
- When indexing `argv` with negative numbers, you can access the parent commands.
- The subcommand to which the handler belongs has the `argv` index of 0.

```c
static int cmd_handler(const struct shell *shell, size_t argc, char **argv)
{
    ARG_UNUSED(argc);

    /* If it is a subcommand handler parent command syntax can be found using argv[-1]. */
    shell_print(shell, "This command has a parent command: \%s", argv[-1]);

    /* Print this command syntax */
    shell_print(shell, "This command syntax is: \%s", argv[0]);

    /* Print first argument */
    return 0;
}
```

Built-in commands

These commands are activated by `CONFIG_SHELL_CMDS` set to `y`.

- `clear` - Clears the screen.
- `history` - Shows the recently entered commands.
- `resize` - Must be executed when terminal width is different than 80 characters or after each change of terminal width. It ensures proper multiline text display and ←, →, End, Home keys handling. Currently this command works only with UART flow control switched on. It can be also called with a subcommand:
  - `default` - Shell will send terminal width = 80 to the terminal and assume successful delivery. These command needs extra activation: `CONFIG_SHELL_CMDS_RESIZE` set to `y`.
- `select` - It can be used to set new root command. Exit to main command tree is with alt+r. This command needs extra activation: `CONFIG_SHELL_CMDS_SELECT` set to `y`.
- `shell` - Root command with useful shell-related subcommands like:
  - `echo` - Toggles shell echo.
  - `colors` - Toggles colored syntax. This might be helpful in case of Bluetooth shell to limit the amount of transferred bytes.
  - `stats` - Shows shell statistics.
4.14.3 Tab Feature

The Tab button can be used to suggest commands or subcommands. This feature is enabled by CONFIG_SHELL_TAB set to y. It can also be used for partial or complete auto-completion of commands. This feature is activated by CONFIG_SHELL_TAB_AUTOCOMPLETION set to y. When user starts writing a command and presses the Tab button then the shell will do one of 3 possible things:

- Autocomplete the command.
- Prompts available commands and if possible partly completes the command.
- Will not do anything if there are no available or matching commands.

4.14.4 History Feature

This feature enables commands history in the shell. It is activated by: CONFIG_SHELL_HISTORY set to y. History can be accessed using keys: ↑ + or Ctrl + n and Ctrl + p if meta keys are active. Number of commands that can be stored depends on size of CONFIG_SHELL_HISTORY_BUFFER parameter.

4.14.5 Wildcards Feature

The shell module can handle wildcards. Wildcards are interpreted correctly when expanded command and its subcommands do not have a handler. For example, if you want to set logging level to err for the app and app_test modules you can execute the following command:

```
log enable err a*
```

This feature is activated by CONFIG_SHELL_WILDCARD set to y.
### 4.14.6 Meta Keys Feature

The shell module supports the following meta keys:

<table>
<thead>
<tr>
<th>Meta keys</th>
<th>Action</th>
</tr>
</thead>
<tbody>
<tr>
<td>Ctrl + a</td>
<td>Moves the cursor to the beginning of the line.</td>
</tr>
<tr>
<td>Ctrl + b</td>
<td>Moves the cursor backward one character.</td>
</tr>
<tr>
<td>Ctrl + c</td>
<td>Preserves the last command on the screen and starts a new command in a new line.</td>
</tr>
<tr>
<td>Ctrl + d</td>
<td>Deletes the character under the cursor.</td>
</tr>
<tr>
<td>Ctrl + e</td>
<td>Moves the cursor to the end of the line.</td>
</tr>
<tr>
<td>Ctrl + f</td>
<td>Moves the cursor forward one character.</td>
</tr>
<tr>
<td>Ctrl + k</td>
<td>Deletes from the cursor to the end of the line.</td>
</tr>
<tr>
<td>Ctrl + l</td>
<td>Clears the screen and leaves the currently typed command at the top of the screen.</td>
</tr>
<tr>
<td>Ctrl + n</td>
<td>Moves in history to next entry.</td>
</tr>
<tr>
<td>Ctrl + p</td>
<td>Moves in history to previous entry.</td>
</tr>
<tr>
<td>Ctrl + u</td>
<td>Clears the currently typed command.</td>
</tr>
<tr>
<td>Ctrl + w</td>
<td>Removes the word or part of the word to the left of the cursor. Words separated by period instead of space are treated as one word.</td>
</tr>
<tr>
<td>Alt + b</td>
<td>Moves the cursor backward one word.</td>
</tr>
<tr>
<td>Alt + f</td>
<td>Moves the cursor forward one word.</td>
</tr>
</tbody>
</table>

This feature is activated by `CONFIG_SHELL_METAKEYS` set to y.

### 4.14.7 Getopt Feature

Some shell users apart from subcommands might need to use options as well. The arguments string, looking for supported options. Typically, this task is accomplished by the `getopt` family functions.

For this purpose shell supports the getopt and getopt_long libraries available in the FreeBSD project. This feature is activated by: `CONFIG_GETOPT` set to y and `CONFIG_GETOPT_LONG` set to y.

This feature can be used in thread safe as well as non thread safe manner. The former is full compatible with regular getopt usage while the latter a bit differs.

An example non-thread safe usage:

```c
char *cvalue = NULL;
while ((char c = getopt(argc, argv, "abhc:")) != -1) {
    switch (c) {
    case 'c':
        cvalue = optarg;
        break;
    default:
        break;
    }
}
```

An example thread safe usage:

```c
char *cvalue = NULL;
struct getopt_state *state;
while ((char c = getopt(argc, argv, "abhc:")) != -1) {
    state = getopt_state_get();
    switch (c) {
```

(continues on next page)
Thread safe getopt functionality is activated by CONFIG_SHELL_GETOPT set to y.

### 4.14.8 Obscured Input Feature

With the obscured input feature, the shell can be used for implementing a login prompt or other user interaction whereby the characters the user types should not be revealed on screen, such as when entering a password.

Once the obscured input has been accepted, it is normally desired to return the shell to normal operation. Such runtime control is possible with the `shell_obscure_set` function.

An example of login and logout commands using this feature is located in `samples/subsys/shell/shell_module/src/main.c` and the config file `samples/subsys/shell/shell_module/prj_login.conf`.

This feature is activated upon startup by `CONFIG_SHELL_START_OBSCURED` set to y. With this set either way, the option can still be controlled later at runtime. `CONFIG_SHELL_CMDS_SELECT` is useful to prevent entry of any other command besides a login command, by means of the `shell_set_root_cmd` function. Likewise, `CONFIG_SHELL_PROMPT_UART` allows you to set the prompt upon startup, but it can be changed later with the `shell_prompt_change` function.

### 4.14.9 Shell Logger Backend Feature

Shell instance can act as the Logging backend. Shell ensures that log messages are correctly multiplexed with shell output. Log messages from logger thread are enqueued and processed in the shell thread. Logger thread will block for configurable amount of time if queue is full, blocking logger thread context for that time. Oldest log message is removed from the queue after timeout and new message is enqueued.

Use the `shell stats show` command to retrieve number of log messages dropped by the shell instance. Log queue size and timeout are `SHELL_DEFINE` arguments.

This feature is activated by: `CONFIG_SHELL_LOG_BACKEND` set to y.

**Warning:** Enqueuing timeout must be set carefully when multiple backends are used in the system. The shell instance could have a slow transport or could block, for example, by a UART with hardware flow control. If timeout is set too high, the logger thread could be blocked and impact other logger backends.

**Warning:** As the shell is a complex logger backend, it can not output logs if the application crashes before the shell thread is running. In this situation, you can enable one of the simple logging backends instead, such as UART (CONFIG_LOG_BACKEND_UART) or RTT (CONFIG_LOG_BACKEND_RTT), which are available earlier during system initialization.

### 4.14.10 Usage

To create a new shell instance user needs to activate requested backend using menuconfig.
The following code shows a simple use case of this library:

```c
void main(void)
{
}

static int cmd_demo_ping(const struct shell *shell, size_t argc,
    char **argv)
{
    ARG_UNUSED(argc);
    ARG_UNUSED(argv);
    shell_print(shell, "pong");
    return 0;
}

static int cmd_demo_params(const struct shell *shell, size_t argc,
    char **argv)
{
    int cnt;

    shell_print(shell, "argc = %d", argc);
    for (cnt = 0; cnt < argc; cnt++) {
        shell_print(shell, " argv[%d] = %s", cnt, argv[cnt]);
    }
    return 0;
}

/* Creating subcommands (level 1 command) array for command "demo". */
SHELL_STATIC_SUBCMD_SET_CREATE(sub_demo,
    SHELL_CMD(params, NULL, "Print params command.", cmd_demo_params),
    SHELL_CMD(ping, NULL, "Ping command.", cmd_demo_ping),
    SHELL_SUBCMD_SET_END
);
/* Creating root (level 0) command "demo" without a handler */
SHELL_CMD_REGISTER(demo, &sub_demo, "Demo commands", NULL);

/* Creating root (level 0) command "version" */
SHELL_CMD_REGISTER(version, NULL, "Show kernel version", cmd_version);
```

Users may use the Tab key to complete a command/subcommand or to see the available subcommands for the currently entered command level. For example, when the cursor is positioned at the beginning of the command line and the Tab key is pressed, the user will see all root (level 0) commands:

```
clear demo shell history log resize version
```

**Note:** To view the subcommands that are available for a specific command, you must first type a space after this command and then hit Tab.

These commands are registered by various modules, for example:

- clear, shell, history, and resize are built-in commands which have been registered by `subsys/shell/shell.c`
- demo and version have been registered in example code above by `main.c`
- log has been registered by `subsys/logging/log_cmds.c`
Then, if a user types a `demo` command and presses the Tab key, the shell will only print the subcommands registered for this command:

```
params ping
```

## 4.14.11 API Reference

### group shell_api

Shell API.

#### Defines

`SHELL_CMD_ARG_REGISTER(syntax, subcmd, help, handler, mandatory, optional)`

Macro for defining and adding a root command (level 0) with required number of arguments.

**Note:** Each root command shall have unique syntax. If a command will be called with wrong number of arguments shell will print an error message and command handler will not be called.

**Parameters**

- `mandatory` – [in] Number of mandatory arguments including command name.

`SHELL_COND_CMD_ARG_REGISTER(flag, syntax, subcmd, help, handler, mandatory, optional)`

Macro for defining and adding a conditional root command (level 0) with required number of arguments.

Macro can be used to create a command which can be conditionally present. It is and alternative to #ifdefs around command registration and command handler. If command is disabled handler and subcommands are removed from the application.

**See also:**

`SHELL_CMD_ARG_REGISTER` for details.

**Parameters**

- `flag` – [in] Compile time flag. Command is present only if flag exists and equals 1.
- `mandatory` – [in] Number of mandatory arguments including command name.
SHELL_CMD_REGISTER(syntax, subcmd, help, handler)
Macro for defining and adding a root command (level 0) with arguments.

Note: All root commands must have different name.

Parameters

• syntax – [in] Command syntax (for example: history).
• subcmd – [in] Pointer to a subcommands array.
• help – [in] Pointer to a command help string.
• handler – [in] Pointer to a function handler.

SHELL_COND_CMD_REGISTER(flag, syntax, subcmd, help, handler)
Macro for defining and adding a conditional root command (level 0) with arguments.

See also:
SHELL_COND_CMD_ARG_REGISTER.

Parameters

• flag – [in] Compile time flag. Command is present only if flag exists and equals 1.
• syntax – [in] Command syntax (for example: history).
• subcmd – [in] Pointer to a subcommands array.
• help – [in] Pointer to a command help string.
• handler – [in] Pointer to a function handler.

SHELL_STATIC_SUBCMD_SET_CREATE(name, ...)
Macro for creating a subcommand set. It must be used outside of any function body.

Example usage: SHELL_STATIC_SUBCMD_SET_CREATE( foo, SHELL_CMD(abc, ...), SHELL_CMD(def, ...), SHELL_SUBCMD_SET_END )

Parameters

• name – [in] Name of the subcommand set.
• ... – [in] List of commands created with SHELL_CMD_ARG or or SHELL_CMD

SHELL_SUBCMD_SET_CREATE(_name, _parent)
Create set of subcommands.

Commands to this set are added using SHELL_SUBCMD_ADD and SHELL_SUBCMD_COND_ADD. Commands can be added from multiple files.

Parameters

• _name – [in] Name of the set. _name is used to refer the set in the parent command.
• _parent – [in] Set of comma separated parent commands in parenthesis, e.g. (foo_cmd) if subcommands are for the root command “foo_cmd”.

4.14. Shell
SHELL_SUBCMD_COND_ADD(_flag, _parent, _syntax, _subcmd, _help, _handler, _mand, _opt)
Conditionally add command to the set of subcommands.
Add command to the set created with SHELL_SUBCMD_SET_CREATE.

**Note:** The name of the section is formed as concatenation of number of parent commands, names of all parent commands and own syntax. Number of parent commands is added to ensure that section prefix is unique. Without it subcommands of (foo) and (foo, cmd1) would mix.

**Parameters**

- `_flag` – [in] Compile time flag. Command is present only if flag exists and equals 1.
- `_handler` – [in] Pointer to a function handler.
- `_mand` – [in] Number of mandatory arguments including command name.

SHELL_SUBCMD_ADD(_parent, _syntax, _subcmd, _help, _handler, _mand, _opt)
Add command to the set of subcommands.
Add command to the set created with SHELL_SUBCMD_SET_CREATE.

**Parameters**

- `_handler` – [in] Pointer to a function handler.
- `_mand` – [in] Number of mandatory arguments including command name.

SHELL_SUBCMD_SET_END
Define ending subcommands set.

SHELL_DYNAMIC_CMD_CREATE(name, get)
Macro for creating a dynamic entry.

**Parameters**

- `name` – [in] Name of the dynamic entry.
- `get` – [in] Pointer to the function returning dynamic commands array
**SHELL_CMD_ARG**(*syntax*, *subcmd*, *help*, *handler*, *mand*, *opt*)

Initializes a shell command with arguments.

**Note:** If a command will be called with wrong number of arguments shell will print an error message and command handler will not be called.

**Parameters**

- **syntax** – [in] Command syntax (for example: *history*).
- **subcmd** – [in] Pointer to a subcommands array.
- **help** – [in] Pointer to a command help string.
- **handler** – [in] Pointer to a function handler.
- **mand** – [in] Number of mandatory arguments including command name.
- **opt** – [in] Number of optional arguments.

**SHELL_COND_CMD_ARG**(*flag*, *syntax*, *subcmd*, *help*, *handler*, *mand*, *opt*)

Initializes a conditional shell command with arguments.

**See also:**

**SHELL_CMD_ARG**. Based on the flag, creates a valid entry or an empty command which is ignored by the *shell*. It is an alternative to #ifdefs around command registration and command handler. However, empty structure is present in the flash even if command is disabled (subcommands and handler are removed). Macro internally handles case if flag is not defined so flag must be provided without any wrapper, e.g.: **SHELL_COND_CMD_ARG**(CONFIG_FOO, . . . )

**Parameters**

- **flag** – [in] Compile time flag. Command is present only if flag exists and equals 1.
- **syntax** – [in] Command syntax (for example: *history*).
- **subcmd** – [in] Pointer to a subcommands array.
- **help** – [in] Pointer to a command help string.
- **handler** – [in] Pointer to a function handler.
- **mand** – [in] Number of mandatory arguments including command name.
- **opt** – [in] Number of optional arguments.

**SHELL_EXPR_CMD_ARG**(_expr_, _syntax_, _subcmd_, _help_, _handler_, _mand_, _opt_)

Initializes a conditional shell command with arguments if expression gives non-zero result at compile time.

**See also:**

**SHELL_CMD_ARG**. Based on the expression, creates a valid entry or an empty command which is ignored by the *shell*. It should be used instead of **SHELL_COND_CMD_ARG** if condition is not a single configuration flag, e.g.: **SHELL_EXPR_CMD_ARG**(IS_ENABLED(CONFIG_FOO) && IS_ENABLED(CONFIG_FOO_SETTING_1), . . . )

**Parameters**
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.
• _mand – [in] Number of mandatory arguments including command name.
• _opt – [in] Number of optional arguments.

SHELL_CMD(_syntax, _subcmd, _help, _handler)
Initializes a shell command.

Parameters
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.

SHELL_COND_CMD(_flag, _syntax, _subcmd, _help, _handler)
Initializes a conditional shell command.

See also:
SHELL_COND_CMD_ARG.

Parameters
• _flag – [in] Compile time flag. Command is present only if flag exists and equals 1.
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.

SHELL_EXPR_CMD(_expr, _syntax, _subcmd, _help, _handler)
Initializes shell command if expression gives non-zero result at compile time.

See also:
SHELL_EXPR_CMD_ARG.

Parameters
• _expr – [in] Compile time expression. Command is present only if expression is non-zero.
• _syntax – [in] Command syntax (for example: history).
• _subcmd – [in] Pointer to a subcommands array.
• _help – [in] Pointer to a command help string.
• _handler – [in] Pointer to a function handler.
SHELL_CMD_DICT_CREATE(_data, _handler)

SHELL_SUBCMD_DICT_SET_CREATE(_name, _handler, ...)

Initializes shell dictionary commands.

This is a special kind of static commands. Dictionary commands can be used every time you want to use a pair: (string <-> corresponding data) in a command handler. The string is usually a verbal description of a given data. The idea is to use the string as a command syntax that can be prompted by the shell and corresponding data can be used to process the command.

Example usage: static int my_handler(const struct shell *shell,
size_t argc, char **argv, void *data) { int val = (int)data;

See also:

shell_dict_cmd_handler

shell_print(shell, “(%s, %d)”, argv[0], val); return 0; }

SHELL_SUBCMD_DICT_SET_CREATE(sub_dict_cmds, my_handler, (value_0, 0), (value_1, 1), (value_2, 2), (value_3, 3) ); SHELL_CMD_REGISTER(dictionary, &sub_dict_cmds, NULL, NULL);

Parameters

• _name – [in] Name of the dictionary subcommand set
• ... – [in] Dictionary pairs: (command_syntax, value). Value will be passed to the _handler as user data.

SHELL_DEFAULT_BACKEND_CONFIG_FLAGS

SHELL_DEFINE(_name, _prompt, _transport_iface, _log_queue_size, _log_timeout, _shell_flag)

Macro for defining a shell instance.

Parameters

• _name – [in] Instance name.
• _prompt – [in] Shell default prompt string.
• _transport_iface – [in] Pointer to the transport interface.
• _log_queue_size – [in] Logger processing queue size.
• _log_timeout – [in] Logger thread timeout in milliseconds on full log queue. If queue is full logger thread is blocked for given amount of time before log message is dropped.
• _shell_flag – [in] Shell output newline sequence.

SHELL_NORMAL

Terminal default text color for shell_fprintf function.

SHELL_INFO

Green text color for shell_fprintf function.

SHELL_OPTION

Cyan text color for shell_fprintf function.
SHELL_WARNING
Yellow text color for shell_printf function.

SHELL_ERROR
Red text color for shell_printf function.

shell_info(_sh, _ft, ...)
Print info message to the shell.
See shell_printf.

Parameters
• _sh – [in] Pointer to the shell instance.
• ... – [in] List of parameters to print.

shell_print(_sh, _ft, ...)
Print normal message to the shell.
See shell_printf.

Parameters
• _sh – [in] Pointer to the shell instance.
• ... – [in] List of parameters to print.

shell_warn(_sh, _ft, ...)
Print warning message to the shell.
See shell_printf.

Parameters
• _sh – [in] Pointer to the shell instance.
• ... – [in] List of parameters to print.

shell_error(_sh, _ft, ...)
Print error message to the shell.
See shell_printf.

Parameters
• _sh – [in] Pointer to the shell instance.
• ... – [in] List of parameters to print.

SHELL_CMD_HELP_PRINTED

Typedefs
typedef void (*shell_dynamic_get)(size_t idx, struct shell_static_entry *entry)

Shell dynamic command descriptor.

Function shall fill the received shell static entry structure with requested (idx) dynamic subcommand data. If there is more than one dynamic subcommand available, the function shall ensure that the returned commands: entry->syntax are sorted in alphabetical order. If idx exceeds the available dynamic subcommands, the function must write to entry->syntax NULL value. This will indicate to the shell module that there are no more dynamic commands to read.

typedef int (*shell_cmd_handler)(const struct shell *shell, size_t argc, char **argv)

Shell command handler prototype.

**Param shell**
Shell instance.

**Param argc**
Arguments count.

**Param argv**
Arguments.

**Retval 0**
Successful command execution.

**Retval 1**
Help printed and command not executed.

**Retval -EINVAL**
Argument validation failed.

**Retval -ENOEXEC**
Command not executed.

typedef int (*shell_dict_cmd_handler)(const struct shell *shell, size_t argc, char **argv, void *data)

Shell dictionary command handler prototype.

**Param shell**
Shell instance.

**Param argc**
Arguments count.

**Param argv**
Arguments.

**Param data**
Pointer to the user data.

**Retval 0**
Successful command execution.

**Retval 1**
Help printed and command not executed.

**Retval -EINVAL**
Argument validation failed.

**Retval -ENOEXEC**
Command not executed.

typedef void (*shell_transport_handler_t)(enum shell_transport_evt evt, void *context)
typedef void (*shell_uninit_cb_t)(const struct shell *shell, int res)

typedef void (*shell_bypass_cb_t)(const struct shell *shell, uint8_t *data, size_t len)
   Bypass callback.
   
   **Param shell**
   Shell instance.

   **Param data**
   Raw data from transport.

   **Param len**
   Data length.

** Enums **

** enum shell_receive_state **

** Values:**

enumerator SHELL_RECEIVE_DEFAULT

enumerator SHELL_RECEIVE_ESC

enumerator SHELL_RECEIVE_ESC_SEQ

enumerator SHELL_RECEIVE_TILDE_EXP

** enum shell_state **

** Values:**

enumerator SHELL_STATE_UNINITIALIZED

enumerator SHELL_STATE_INITIALIZED

enumerator SHELL_STATE_ACTIVE

enumerator SHELL_STATE_PANIC_MODE_ACTIVE
   Panic activated.

enumerator SHELL_STATE_PANIC_MODE_INACTIVE
   Panic requested, not supported.

** enum shell_transport_evt **

** Shell transport event. **

** Values:**

enumerator SHELL_TRANSPORT_EVT_RX_RDY
enumerator SHELL_TRANSPORT_EVT_TX_RDY

enum shell_signal
Values:

enumerator SHELL_SIGNAL_RXRDY
enumerator SHELL_SIGNAL_LOG_MSG
enumerator SHELL_SIGNAL_KILL
enumerator SHELL_SIGNAL_TXDONE
enumerator SHELL_SIGNALS

enum shell_flag
Flags for setting shell output newline sequence.
Values:

enumerator SHELL_FLAG_CRLF_DEFAULT = (1 << 0)
enumerator SHELL_FLAG_OLF_CRLF = (1 << 1)

Functions

custom struct device *shell_device_lookup(size_t idx, const char *prefix)
Get by index a device that matches.
This can be used, for example, to identify I2C_1 as the second I2C device.
Devices that failed to initialize or do not have a non-empty name are excluded from the
candidates for a match.

Parameters
• idx – the device number starting from zero.
• prefix – optional name prefix used to restrict candidate devices. Indexing is
done relative to devices with names that start with this text. Pass null if no
prefix match is required.

int shell_init(const struct shell *shell, const void *transport_config, struct
shell_backend_config_flags cfg_flags, bool log_backend, uint32_t init_log_level)
Function for initializing a transport layer and internal shell state.

Parameters
• shell – [in] Pointer to shell instance.
• cfg_flags – [in] Initial backend configuration flags. Shell will copy this data.
• log_backend – If true, the console will be used as logger backend.
• init_log_level – [in] Default severity level for the logger.
Returns
Standard error code.

void shell_uninit(const struct shell *shell, shell_uninit_cb_t cb)
Uninitializes the transport layer and the internal shell state.

Parameters
• shell – Pointer to shell instance.
• cb – Callback called when uninitialization is completed.

int shell_start(const struct shell *shell)
Function for starting shell processing.

Parameters
• shell – Pointer to the shell instance.

Returns
Standard error code.

int shell_stop(const struct shell *shell)
Function for stopping shell processing.

Parameters
• shell – Pointer to shell instance.

Returns
Standard error code.

void shell_fprintf(const struct shell *shell, enum shell_vt100_color color, const char *fmt, ...)
printf-like function which sends formatted data stream to the shell.
This function can be used from the command handler or from threads, but not from an interrupt context.

Parameters
• shell – [in] Pointer to the shell instance.
• color – [in] Printed text color.
• ... – [in] List of parameters to print.

void shell_vfprintf(const struct shell *shell, enum shell_vt100_color color, const char *fmt, va_list args)
vprintf-like function which sends formatted data stream to the shell.
This function can be used from the command handler or from threads, but not from an interrupt context. It is similar to shell_fprintf() but takes a va_list instead of variable arguments.

Parameters
• shell – [in] Pointer to the shell instance.
• color – [in] Printed text color.
• args – [in] List of parameters to print.

void shell_hexdump_line(const struct shell *shell, unsigned int offset, const uint8_t *data, size_t len)
Print a line of data in hexadecimal format.
Each line shows the offset, bytes and then ASCII representation.
For example:
00008010: 20 25 00 20 2f 48 00 08 80 05 00 20 af 46 00 | %. /H.. . . . .F. |

Parameters
- \texttt{shell} – [in] Pointer to the shell instance.
- \texttt{offset} – [in] Offset to show for this line.
- \texttt{data} – [in] Pointer to data.
- \texttt{len} – [in] Length of data.

\begin{verbatim}
void shell_hexdump(const struct shell *shell, const uint8_t *data, size_t len)
Print data in hexadecimal format.
\end{verbatim}

Parameters
- \texttt{shell} – [in] Pointer to the shell instance.
- \texttt{data} – [in] Pointer to data.
- \texttt{len} – [in] Length of data.

\begin{verbatim}
void shell_process(const struct shell *shell)
Process function, which should be executed when data is ready in the transport interface. To
be used if shell thread is disabled.
\end{verbatim}

Parameters
- \texttt{shell} – [in] Pointer to the shell instance.

\begin{verbatim}
int shell_prompt_change(const struct shell *shell, const char *prompt)
Change displayed shell prompt.
\end{verbatim}

Parameters
- \texttt{shell} – [in] Pointer to the shell instance.

Returns
0 Success.

Returns
-EINVAL Pointer to new prompt is not correct.

\begin{verbatim}
void shell_help(const struct shell *shell)
Prints the current command help.
Function will print a help string with: the currently entered command and subcommands (if
they exist).
\end{verbatim}

Parameters
- \texttt{shell} – [in] Pointer to the shell instance.

\begin{verbatim}
int shell_execute_cmd(const struct shell *shell, const char *cmd)
Execute command.
Pass command line to shell to execute.
Note: This by no means makes any of the commands a stable interface, so this function should
only be used for debugging/diagnostic.
This function must not be called from shell command context!
\end{verbatim}

Parameters
- \texttt{shell} – [in] Pointer to the shell instance. It can be NULL when the
  CONFIG_SHELL_BACKEND_DUMMY option is enabled.
• cmd – [in] Command to be executed.

Returns
Result of the execution

int shell_set_root_cmd(const char *cmd)
Set root command for all shell instances.
It allows setting from the code the root command. It is an equivalent of calling select command with one of the root commands as the argument (e.g “select log”) except it sets command for all shell instances.

Parameters
• cmd – String with one of the root commands or null pointer to reset.

Return values
• 0 – if root command is set.
• -EINVAL – if invalid root command is provided.

void shell_set_bypass(const struct shell *shell, shell_bypass_cb_t bypass)
Set bypass callback.
Bypass callback is called whenever data is received. Shell is bypassed and data is passed directly to the callback. Use null to disable bypass functionality.

Parameters
• shell – [in] Pointer to the shell instance.
• bypass – [in] Bypass callback or null to disable.

bool shell_ready(const struct shell *sh)
Get shell readiness to execute commands.

Parameters
• sh – [in] Pointer to the shell instance.

Return values
• true – Shell backend is ready to execute commands.
• false – Shell backend is not initialized or not started.

int shell_insert_mode_set(const struct shell *shell, bool val)
Allow application to control text insert mode. Value is modified atomically and the previous value is returned.

Parameters
• shell – [in] Pointer to the shell instance.
• val – [in] Insert mode.

Return values
• 0 – or 1: previous value
• -EINVAL – if shell is NULL.

int shell_use_colors_set(const struct shell *shell, bool val)
Allow application to control whether terminal output uses colored syntax. Value is modified atomically and the previous value is returned.

Parameters
• shell – [in] Pointer to the shell instance.
• val – [in] Color mode.
Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

int shell_echo_set(const struct shell *shell, bool val)

Allow application to control whether user input is echoed back. Value is modified atomically and the previous value is returned.

Parameters

- shell – [in] Pointer to the shell instance.

Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

int shell_obscure_set(const struct shell *shell, bool obscure)

Allow application to control whether user input is obscured with asterisks. Useful for implementing passwords. Value is modified atomically and the previous value is returned.

Parameters

- shell – [in] Pointer to the shell instance.

Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

int shell_mode_delete_set(const struct shell *shell, bool val)

Allow application to control whether the delete key backspaces or deletes. Value is modified atomically and the previous value is returned.

Parameters

- shell – [in] Pointer to the shell instance.

Return values

- 0 – or 1: previous value
- -EINVAL – if shell is NULL.

Variables

const struct log_backend_api log_backend_shell_api

union shell_cmd_entry

#include <shell.h> Shell command descriptor.

Public Members
shell_dynamic_get  dynamic_get
< Pointer to function returning dynamic commands. Pointer to array of static commands.

const struct shell_static_entry *entry

struct shell_static_args
#include <shell.h>

Public Members

uint8_t mandatory
   Number of mandatory arguments.

uint8_t optional
   Number of optional arguments.

struct shell_static_entry
#include <shell.h>

Public Members

const char *syntax
   Command syntax strings.

const char *help
   Command help string.

const union shell_cmd_entry *subcmd
   Pointer to subcommand.

shell_cmd_handler handler
   Command handler.

struct shell_static_args args
   Command arguments.

struct shell_transport_api
#include <shell.h> Unified shell transport interface.

Public Members

int (*init)(const struct shell_transport *transport, const void *config,
shell_transport_handler_t evt_handler, void *context)
   Function for initializing the shell transport interface.
   
   Param transport
      [in] Pointer to the transfer instance.
Param config
  [in] Pointer to instance configuration.

Param evt_handler

Param context
  [in] Pointer to the context passed to event handler.

Return
  Standard error code.

int (*uninit)(const struct shell_transport *transport)
Function for uninitializing the shell transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Return
    Standard error code.

int (*enable)(const struct shell_transport *transport, bool blocking_tx)
Function for enabling transport in given TX mode.
  Function can be used to reconfigure TX to work in blocking mode.
  Param transport
    Pointer to the transfer instance.
  Param blocking_tx
    If true, the transport TX is enabled in blocking mode.
  Return
    NRF_SUCCESS on successful enabling, error otherwise (also if not supported).

int (*write)(const struct shell_transport *transport, const void *data, size_t length, size_t *cnt)
Function for writing data to the transport interface.
  Param transport
    [in] Pointer to the transfer instance.
  Param data
    [in] Pointer to the source buffer.
  Param length
    [in] Source buffer length.
  Param cnt
    [out] Pointer to the sent bytes counter.
  Return
    Standard error code.

int (*read)(const struct shell_transport *transport, void *data, size_t length, size_t *cnt)
Function for reading data from the transport interface.
  Param p_transport
    [in] Pointer to the transfer instance.
  Param p_data
    [in] Pointer to the destination buffer.
  Param length
    [in] Destination buffer length.
  Param cnt
    [out] Pointer to the received bytes counter.
  Return
    Standard error code.

void (*update)(const struct shell_transport *transport)
Function called in shell thread loop.
Can be used for backend operations that require longer execution time

**Param transport**

[in] Pointer to the transfer instance.

```c
struct shell_transport
#include <shell.h>
```

```c
struct shell_stats
#include <shell.h> Shell statistics structure.

Public Members

atomic_t log_lost_cnt
Lost log counter.

struct shell_backend_config_flags
#include <shell.h>

Public Members

uint32_t insert_mode
Controls insert mode for text introduction

uint32_t echo
Controls shell echo

uint32_t obscure
If echo on, print asterisk instead

uint32_t mode_delete
Operation mode of backspace key

uint32_t use_colors
Controls colored syntax

uint32_t use_vt100
Controls VT100 commands usage in shell

struct shell_backend_ctx_flags
#include <shell.h>

Public Members

uint32_t processing
Shell is executing process function
uint32_t history_exit
    Request to exit history mode

uint32_t last_nl
    Last received new line character

uint32_t cmd_ctx
    Shell is executing command

uint32_t print_noinit
    Print request from not initialized shell

uint32_t sync_mode
    Shell in synchronous mode

union shell_backend_cfg
    #include <shell.h>

Public Members

atomic_t value

struct shell_backend_config_flags flags

union shell_backend_ctx
    #include <shell.h>

Public Members

uint32_t value

struct shell_backend_ctx_flags flags

struct shell_ctx
    #include <shell.h> Shell instance context.

Public Members

const char *prompt
    Shell current prompt.

enum shell_state state
    Internal module state.
enum **shell_receive_state** receive_state

Escape sequence indicator. Currently executed command.

const struct **shell_static_entry** *selected_cmd

VT100 color and cursor position, terminal width.

struct shell_vt100_ctx vt100_ctx

Callback called from shell thread context when unitialization is completed just before aborting shell thread.

**shell_uninit_cb_t** uninit_cb

When bypass is set, all incoming data is passed to the callback.

uint16_t cmd_buff_len

Command length.

uint16_t cmd_buff_pos

Command buffer cursor position.

uint16_t cmd_tmp_buff_len

Command length in tmp buffer. Command input buffer.

char cmd_buff[0]

Command temporary buffer.

char temp_buff[0]

Printf buffer size.

struct *k_poll_signal* signals[SHELL_SIGNALS]

Events that should be used only internally by shell thread. Event for SHELL_SIGNAL_TXDONE is initialized but unused.

struct shell

#include <shell.h> Shell instance internals.

**Public Members**

const char *default_prompt

shell default prompt.

const struct **shell_transport** *iface

Transport interface.

struct **shell_ctx** *ctx

Internal context.
4.15 Settings

The settings subsystem gives modules a way to store persistent per-device configuration and runtime state. A variety of storage implementations are provided behind a common API using FCB, NVS, or a file system. These different implementations give the application developer flexibility to select an appropriate storage medium, and even change it later as needs change. This subsystem is used by various Zephyr components and can be used simultaneously by user applications.

Settings items are stored as key-value pair strings. By convention, the keys can be organized by the package and subtree defining the key, for example the key `id/serial` would define the `serial` configuration element for the package `id`.

Convenience routines are provided for converting a key value to and from a string type.

For an example of the settings subsystem refer to the sample.

**Note:** As of Zephyr release 2.1 the recommended backend for non-filesystem storage is **NVS**.

4.15.1 Handlers

Settings handlers for subtree implement a set of handler functions. These are registered using a call to `settings_register()`.

- **h_get**
  This gets called when asking for a settings element value by its name using `settings_runtime_get()` from the runtime backend.

- **h_set**
  This gets called when the value is loaded from persisted storage with `settings_load()`, or when using `settings_runtime_set()` from the runtime backend.

- **h_commit**
  This gets called after the settings have been loaded in full. Sometimes you don’t want an individual setting value to take effect right away, for example if there are multiple settings which are interdependent.

- **h_export**
  This gets called to write all current settings. This happens when `settings_save()` tries to save the settings or transfer to any user-implemented back-end.

4.15.2 Backends

Backends are meant to load and save data to/from setting handlers, and implement a set of handler functions. These are registered using a call to `settings_src_register()` for backends that can load data, and/or `settings_dst_register()` for backends that can save data. The current implementation allows for multiple source backends but only a single destination backend.

- **csi_load**
  This gets called when loading values from persistent storage using `settings_load()`.

- **csi_save**
  This gets called when saving a single setting to persistent storage using `settings_save_one()`.

- **csi_save_start**
  This gets called when starting a save of all current settings using `settings_save()`.

- **csi_save_end**
  This gets called after having saved of all current settings using `settings_save()`.
4.15.3 Zephyr Storage Backends

Zephyr has three storage backends: a Flash Circular Buffer (CONFIG_SETTINGS_FCB), a file in the filesystem (CONFIG_SETTINGS_FILE), or non-volatile storage (CONFIG_SETTINGS_NVS).

You can declare multiple sources for settings; settings from all of these are restored when settings_load() is called.

There can be only one target for writing settings; this is where data is stored when you call settings_save(), or settings_save_one().

FCB read target is registered using settings_fcb_src(), and write target using settings_fcb_dst(). As a side-effect, settings_fcb_src() initializes the FCB area, so it must be called before calling settings_fcb_dst(). File read target is registered using settings_file_src(), and write target by using settings_file_dst(). Non-volatile storage read target is registered using settings_nvs_src(), and write target by using settings_nvs_dst().

4.15.4 Storage Location

The FCB and non-volatile storage (NVS) backends both look for a fixed partition with label “storage” by default. A different partition can be selected by setting the zephyr,settings-partition property of the chosen node in the devicetree.

The file path used by the file backend to store settings is selected via the option CONFIG_SETTINGS_FILE_PATH.

4.15.5 Loading data from persisted storage

A call to settings_load() uses an h_set implementation to load settings data from storage to volatile memory. After all data is loaded, the h_commit handler is issued, signalling the application that the settings were successfully retrieved.

Technically FCB and file backends may store some history of the entities. This means that the newest data entity is stored after any older existing data entities. Starting with Zephyr 2.1, the back-end must filter out all old entities and call the callback with only the newest entity.

4.15.6 Storing data to persistent storage

A call to settings_save_one() uses a backend implementation to store settings data to the storage medium. A call to settings_save() uses an h_export implementation to store different data in one operation using settings_save_one(). A key need to be covered by a h_export only if it is supposed to be stored by settings_save() call.

For both FCB and file back-end only storage requests with data which changes most actual key’s value are stored, therefore there is no need to check whether a value changed by the application. Such a storage mechanism implies that storage can contain multiple value assignments for a key, while only the last is the current value for the key.

Garbage collection

When storage becomes full (FCB) or consumes too much space (file), the backend removes non-recent key-value pairs records and unnecessary key-delete records.
4.15.7 Secure domain settings

Currently settings doesn’t provide scheme of being secure, and non-secure configuration storage simultaneously for the same instance. It is recommended that secure domain uses its own settings instance and it might provide data for non-secure domain using dedicated interface if needed (case dependent).

4.15.8 Example: Device Configuration

This is a simple example, where the settings handler only implements h_set and h_export. h_set is called when the value is restored from storage (or when set initially), and h_export is used to write the value to storage thanks to storage_func(). The user can also implement some other export functionality, for example, writing to the shell console).

```c
#define DEFAULT_FOO_VAL_VALUE 1

static int8 foo_val = DEFAULT_FOO_VAL_VALUE;

static int foo_settings_set(const char *name, size_t len,
                            settings_read_cb read_cb, void *cb_arg)
{
    const char *next;
    int rc;

    if (settings_name_steq(name, "bar", &next) && !next) {
        if (len != sizeof(foo_val)) {
            return -EINVAL;
        }
        rc = read_cb(cb_arg, &foo_val, sizeof(foo_val));
        if (rc >= 0) {
            /* key-value pair was properly read.
             * rc contains value length.
             */
            return 0;
        }
        /* read-out error */
    }
    /* read-out error */
    return rc;
}

static int foo_settings_export(int (*storage_func)(const char *name,
                                                    const void *value,
                                                    size_t val_len))
{
    return storage_func("foo/bar", &foo_val, sizeof(foo_val));
}

struct settings_handler my_conf = {
    .name = "foo",
    .h_set = foo_settings_set,
    .h_export = foo_settings_export
};
```
4.15.9 Example: Persist Runtime State

This is a simple example showing how to persist runtime state. In this example, only h_set is defined, which is used when restoring value from persisted storage.

In this example, the main function increments foo_val, and then persists the latest number. When the system restarts, the application calls settings_load() while initializing, and foo_val will continue counting up from where it was before restart.

```c
#include <zephyr/kernel.h>
#include <zephyr/sys/reboot.h>
#include <zephyr/settings/settings.h>
#include <zephyr/sys/printk.h>
#include <inttypes.h>

#define DEFAULT_FOO_VAL_VALUE 0

static uint8_t foo_val = DEFAULT_FOO_VAL_VALUE;

static int foo_settings_set(const char *name, size_t len,
    settings_read_cb read_cb, void *cb_arg)
{
    const char *next;
    int rc;

    if (settings_name_steq(name, "bar", &next) && !next) {
        if (len != sizeof(foo_val)) {
            return -EINVAL;
        }

        rc = read_cb(cb_arg, &foo_val, sizeof(foo_val));
        if (rc >= 0) {
            return 0;
        }
    }

    return rc;
}

struct settings_handler my_conf = {
    .name = "foo",
    .h_set = foo_settings_set
};

void main(void)
{
    settings_subsys_init();
    settings_register(&my_conf);
    settings_load();

    foo_val++;
    settings_save_one("foo/bar", &foo_val, sizeof(foo_val));

    printk("foo: %d\n", foo_val);
}
```

(continues on next page)
4.15.10 Example: Custom Backend Implementation

This is a simple example showing how to register a simple custom backend handler (CONFIG_SETTINGS_CUSTOM).

```c
static int settings_custom_load(struct settings_store *cs)
{
  //...
}

static int settings_custom_save(struct settings_store *cs, const char *name,
                                const char *value, size_t val_len)
{
  //...
}

/* custom backend interface */
static struct settings_store_itf settings_custom_itf = {
  .csi_load = settings_custom_load,
  .csi_save = settings_custom_save,
};

/* custom backend node */
static struct settings_store settings_custom_store = {
  .cs_itf = &settings_custom_itf
}

int settings_backend_init(void)
{
  /* register custom backend */
  settings_dst_register(&settings_custom_store);
  settings_src_register(&settings_custom_store);
  return 0;
}
```

4.15.11 API Reference

The Settings subsystem APIs are provided by settings.h:

**API for general settings usage**

`group settings`

**Defines**

```
SETTINGS_MAX_DIR_DEPTH
```
SETTINGS_MAX_NAME_LEN

SETTINGS_MAX_VAL_LEN

SETTINGS_NAME_SEPARATOR

SETTINGS_NAME_END

SETTINGS_EXTRA_LEN

SETTINGS_STATIC_HANDLER_DEFINE(_hname, _tree, _get, _set, _commit, _export)

Define a static handler for settings items

This creates a variable *hname prepended by settings_handler.*

Parameters

- _hname – handler name
- _tree – subtree name
- _get – get routine (can be NULL)
- _set – set routine (can be NULL)
- _commit – commit routine (can be NULL)
- _export – export routine (can be NULL)

Typedefs

typedef ssize_t (*settings_read_cb)(void *cb_arg, void *data, size_t len)

Function used to read the data from the settings storage in h_set handler implementations.

- **Param cb_arg**
  - [in] arguments for the read function. Appropriate cb_arg is transferred to h_set handler implementation by the backend.

- **Param data**
  - [out] the destination buffer

- **Param len**
  - [in] length of read

Return

- positive: Number of bytes read, 0: key-value pair is deleted. On error returns -ERRNO code.

typedef int (*settings_load_direct_cb)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg, void *param)

Callback function used for direct loading. Used by settings_load_subtree_direct function.

- **Param key**
  - [in] the name with skipped part that was used as name in handler registration

- **Param len**
  - [in] the size of the data found in the backend.
**Param read_cb**

[in] function provided to read the data from the backend.

**Param cb_arg**

[inout] arguments for the read function provided by the backend.

**Param param**

[inout] parameter given to the `settings_load_subtree_direct` function.

**Return**

When nonzero value is returned, further subtree searching is stopped.

### Functions

```c
int settings_subsys_init(void)
```

Initialization of settings and backend

Can be called at application startup. In case the backend is a FS Remember to call it after the FS was mounted. For FCB backend it can be called without such a restriction.

**Returns**

0 on success, non-zero on failure.

```c
int settings_register(struct settings_handler *cf)
```

Register a handler for settings items stored in RAM.

**Parameters**

- `cf` – Structure containing registration info.

**Returns**

0 on success, non-zero on failure.

```c
int settings_load(void)
```

Load serialized items from registered persistence sources. Handlers for serialized item subtrees registered earlier will be called for encountered values.

**Returns**

0 on success, non-zero on failure.

```c
int settings_load_subtree(const char *subtree)
```

Load limited set of serialized items from registered persistence sources. Handlers for serialized item subtrees registered earlier will be called for encountered values that belong to the subtree.

**Parameters**

- `subtree` – [in] name of the subtree to be loaded.

**Returns**

0 on success, non-zero on failure.

```c
int settings_load_subtree_direct(const char *subtree, settings_load_direct_cb cb, void *param)
```

Load limited set of serialized items using given callback.

This function bypasses the normal data workflow in settings module. All the settings values that are found are passed to the given callback.

**Note:** This function does not call commit function. It works as a blocking function, so it is up to the user to call any kind of commit function when this operation ends.

**Parameters**
Zephyr Project Documentation, Release 3.2.99

- **subtree** – [in] subtree name of the subtree to be loaded.
- **cb** – [in] pointer to the callback function.
- **param** – [inout] parameter to be passed when callback function is called.

**Returns**
0 on success, non-zero on failure.

```c
int settings_save(void)
```
Save currently running serialized items. All serialized items which are different from currently persisted values will be saved.

**Returns**
0 on success, non-zero on failure.

```c
int settings_save_one(const char *name, const void *value, size_t val_len)
```
Write a single serialized value to persisted storage (if it has changed value).

**Parameters**
- **name** – Name/key of the settings item.
- **value** – Pointer to the value of the settings item. This value will be transferred to the `settings_handler::h_export` handler implementation.
- **val_len** – Length of the value.

**Returns**
0 on success, non-zero on failure.

```c
int settings_delete(const char *name)
```
Delete a single serialized in persisted storage.

Deleting an existing key-value pair in the settings mean to set its value to NULL.

**Parameters**
- **name** – Name/key of the settings item.

**Returns**
0 on success, non-zero on failure.

```c
int settings_commit(void)
```
Call commit for all settings handler. This should apply all settings which has been set, but not applied yet.

**Returns**
0 on success, non-zero on failure.

```c
int settings_commit_subtree(const char *subtree)
```
Call commit for settings handler that belong to subtree. This should apply all settings which has been set, but not applied yet.

**Parameters**
- **subtree** – [in] name of the subtree to be committed.

**Returns**
0 on success, non-zero on failure.

```c
struct settings_handler
```
#include <settings.h> Config handlers for subtree implement a set of handler functions. These are registered using a call to `settings_register`.  

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Public Members

const char *name
  Name of subtree.

int (*h_get)(const char *key, char *val, int val_len_max)
  Get values handler of settings items identified by keyword names.
  Parameters:
  • key[in] the name with skipped part that was used as name in handler registration
  • val[out] buffer to receive value.
  • val_len_max[in] size of that buffer.
  Return: length of data read on success, negative on failure.

int (*h_set)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg)
  Set value handler of settings items identified by keyword names.
  Parameters:
  • key[in] the name with skipped part that was used as name in handler registration
  • len[in] the size of the data found in the backend.
  • read_cb[in] function provided to read the data from the backend.
  • cb_arg[in] arguments for the read function provided by the backend.
  Return: 0 on success, non-zero on failure.

int (*h_commit)(void)
  This handler gets called after settings has been loaded in full. User might use it to apply
  setting to the application.
  Return: 0 on success, non-zero on failure.

int (*h_export)(int (*export_func)(const char *name, const void *val, size_t val_len))
  This gets called to dump all current settings items.
  This happens when settings_save tries to save the settings. Parameters:
  • export_func: the pointer to the internal function which appends a single key-value
    pair to persisted settings. Don’t store duplicated value. The name is subtree/key
    string, val is the string with value.
  Return: 0 on success, non-zero on failure.

Remark
The User might limit a implementations of handler to serving only one keyword at one
  call - what will impose limit to get/set values using full subtree/key name.

sys_snod_t node
  Linked list node info for module internal usage.

struct settings_handler_static
  #include <settings.h> Config handlers without the node element, used for static handlers.
  These are registered using a call to SETTINGS_STATIC_HANDLER_DEFINE().

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Public Members

const char *name
Name of subtree.

int (*h_get)(const char *key, char *val, int val_len_max)
Get values handler of settings items identified by keyword names.
Parameters:
• key[in] the name with skipped part that was used as name in handler registration
• val[out] buffer to receive value.
• val_len_max[in] size of that buffer.
Return: length of data read on success, negative on failure.

int (*h_set)(const char *key, size_t len, settings_read_cb read_cb, void *cb_arg)
Set value handler of settings items identified by keyword names.
Parameters:
• key[in] the name with skipped part that was used as name in handler registration
• len[in] the size of the data found in the backend.
• read_cb[in] function provided to read the data from the backend.
• cb_arg[in] arguments for the read function provided by the backend.
Return: 0 on success, non-zero on failure.

int (*h_commit)(void)
This handler gets called after settings has been loaded in full. User might use it to apply setting to the application.

int (*h_export)(int (*export_func)(const char *name, const void *val, size_t val_len))
This gets called to dump all current settings items.
This happens when settings_save tries to save the settings. Parameters:
• export_func: the pointer to the internal function which appends a single key-value pair to persisted settings. Don't store duplicated value. The name is subtree/key string, val is the string with value.

Remark
The User might limit a implementations of handler to serving only one keyword at one call - what will impose limit to get/set values using full subtree/key name.

API for key-name processing

group settings_name_proc
API for const name processing.

Functions
int settings_name_steq(const char *name, const char *key, const char **next)
Compared the start of name with a key

Some examples: settings_name_steq("bt/btmesh/iv", "b", &next) returns 1, next="t/btmesh/iv" settings_name_steq("bt/btmesh/iv", "bt", &next) returns 1, next="bmesh/iv" settings_name_steq("bt/btmesh/iv", "bt/", &next) returns 0, next=NULL settings_name_steq("bt/btmesh/iv", "bta", &next) returns 0, next=NULL

REMARK: This routine could be simplified if the settings_handler names would include a separator at the end.

Parameters
• name – [in] in string format
• key – [in] comparison string
• next – [out] pointer to remaining of name, when the remaining part starts with a separator the separator is removed from next

Returns
0: no match 1: match, next can be used to check if match is full

int settings_name_next(const char *name, const char **next)
determine the number of characters before the first separator

Parameters
• name – [in] in string format
• next – [out] pointer to remaining of name (excluding separator)

Returns
index of the first separator, in case no separator was found this is the size of name

API for runtime settings manipulation

group settings_rt
API for runtime settings.

Functions

int settings_runtime_set(const char *name, const void *data, size_t len)
Set a value with a specific key to a module handler.

Parameters
• name – Key in string format.
• data – Binary value.
• len – Value length in bytes.

Returns
0 on success, non-zero on failure.

int settings_runtime_get(const char *name, void *data, size_t len)
Get a value corresponding to a key from a module handler.

Parameters
• name – Key in string format.
• data – Returned binary value.
• len – requested value length in bytes.

Returns
length of data read on success, negative on failure.

int settings_runtime_commit(const char *name)
Apply settings in a module handler.

Parameters
• name – Key in string format.

Returns
0 on success, non-zero on failure.

API of backend interface

group settings_backend
settings

Functions

void settings_src_register(struct settings_store *cs)
Register a backend handler acting as source.

Parameters
• cs – Backend handler node containing handler information.

void settings_dst_register(struct settings_store *cs)
Register a backend handler acting as destination.

Parameters
• cs – Backend handler node containing handler information.

struct settings_handler_* settings_parse_and_lookup(const char *name, const char **next)
Parses a key to an array of elements and locate corresponding module handler.

Parameters
• name – [in] in string format
• next – [out] remaining of name after matched handler

Returns
settings_handler_static on success, NULL on failure.

int settings_call_set_handler(const char *name, size_t len, settings_read_cb read_cb, void
read_cb_arg, const struct settings_load_arg *load_arg)
Calls settings handler.

Parameters
• name – [in] The name of the data found in the backend.
• len – [in] The size of the data found in the backend.
• read_cb – [in] Function provided to read the data from the backend.
• read_cb_arg – [inout] Arguments for the read function provided by the back-end.
**Returns**

0 or negative error code

```c
struct settings_store

#include <settings.h> Backend handler node for storage handling.
```

**Public Members**

```c
sys_snnode_t cs_next
  Linked list node info for internal usage.

const struct settings_store_itf *cs_itf
  Backend handler structure.
```

```c
struct settings_load_arg

#include <settings.h> Arguments for data loading. Holds all parameters that changes the way data should be loaded from backend.
```

**Public Members**

```c
const char *subtree
  Name of the subtree to be loaded.
  If NULL, all values would be loaded.

settings_load_direct_cb cb
  Pointer to the callback function.
  If NULL then matching registered function would be used.

void *param
  Parameter for callback function.
  Parameter to be passed to the callback function.
```

```c
struct settings_store_itf

#include <settings.h> Backend handler functions. Sources are registered using a call to settings_src_register. Destinations are registered using a call to settings_dst_register.
```

**Public Members**

```c
int (*csi_load)(struct settings_store *cs, const struct settings_load_arg *arg)
  Loads values from storage limited to subtree defined by subtree.

Parameters:
  • cs - Corresponding backend handler node,
  • arg - Structure that holds additional data for data loading.
```

**Note:** Backend is expected not to provide duplicates of the entities. It means that if the backend does not contain any functionality to really delete old keys, it has to filter out old entities and call load callback only on the final entity.
int (*csi_save_start)(struct settings_store *cs)
    Handler called before an export operation.
    Parameters:
    • cs - Corresponding backend handler node

int (*csi_save)(struct settings_store *cs, const char *name, const char *value, size_t val_len)
    Save a single key-value pair to storage.
    Parameters:
    • cs - Corresponding backend handler node
    • name - Key in string format
    • value - Binary value
    • val_len - Length of value in bytes.

int (*csi_save_end)(struct settings_store *cs)
    Handler called after an export operation.
    Parameters:
    • cs - Corresponding backend handler node

4.16 State Machine Framework

4.16.1 Overview

The State Machine Framework (SMF) is an application agnostic framework that provides an easy way for developers to integrate state machines into their application. The framework can be added to any project by enabling the CONFIG_SMF option.

4.16.2 State Creation

A state is represented by three functions, where one function implements the Entry actions, another function implements the Run actions, and the last function implements the Exit actions. The prototype for these functions is as follows: void funct(void *obj), where the obj parameter is a user defined structure that has the state machine context, struct smf_ctx, as its first member. For example:

```c
struct user_object {
    struct smf_ctx ctx;
    /* All User Defined Data Follows */
};
```

The struct smf_ctx member must be first because the state machine framework’s functions casts the user defined object to the struct smf_ctx type with the following macro: SMF_CTX(o)

For example instead of doing this (struct smf_ctx *)&user_obj, you could use SMF_CTX(&user_obj).

By default, a state can have no ancestor states, resulting in a flat state machine. But to enable the creation of a hierarchical state machine, the CONFIG_SMFANCESTOR_SUPPORT option must be enabled.

The following macro can be used for easy state creation:

```
    • SMF_CREATE_STATE Create a state
```

**NOTE:** The SMF_CREATE_STATE macro takes an additional parameter when CONFIG_SMFANCESTOR_SUPPORT is enabled.
4.16.3  State Machine Creation

A state machine is created by defining a table of states that's indexed by an enum. For example, the following creates three flat states:

```c
enum demo_state { S0, S1, S2 };

const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, s0_exit),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, s1_exit),
    [S2] = SMF_CREATE_STATE(s2_entry, s2_run, s2_exit)
};
```

And this example creates three hierarchical states:

```c
enum demo_state { S0, S1, S2 };

const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, s0_exit, parent_s0),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, s1_exit, parent_s12),
    [S2] = SMF_CREATE_STATE(s2_entry, s2_run, s2_exit, parent_s12)
};
```

To set the initial state, the `smf_set_initial` function should be called. It has the following prototype:

```c
void smf_set_initial(smf_ctx *ctx, smf_state *state)
```

To transition from one state to another, the `smf_set_state` function is used and it has the following prototype:

```c
void smf_set_state(smf_ctx *ctx, smf_state *state)
```

**NOTE:** While the state machine is running, `smf_set_state` should only be called from the Entry and Run functions. Calling `smf_set_state` from the Exit functions doesn't make sense and will generate a warning.

4.16.4  State Machine Execution

To run the state machine, the `smf_run_state` function should be called in some application dependent way. An application should cease calling `smf_run_state` if it returns a non-zero value. The function has the following prototype:

```c
int32_t smf_run_state(smf_ctx *ctx)
```

4.16.5  State Machine Termination

To terminate the state machine, the `smf_terminate` function should be called. It can be called from the entry, run, or exit action. The function takes a non-zero user defined value that's returned by the `smf_run_state` function. The function has the following prototype:

```c
void smf_terminate(smf_ctx *ctx, int32_t val)
```

4.16.6  Flat State Machine Example

This example turns the following state diagram into code using the SMF, where the initial state is S0.

Code:

```c
#include <zephyr/smf.h>

/* Forward declaration of state table */
static const struct smf_state demo_states[];
```

(continues on next page)
/* List of demo states */
enum demo_state { S0, S1, S2 };

/* User defined object */
struct s_object {
    /* This must be first */
    struct smf_ctx ctx;

    /* Other state specific data add here */
} s_obj;

/* State S0 */
static void s0_entry(void *o) {
    /* Do something */
}
static void s0_run(void *o) {
    smf_set_state(SMF_CTX(&s_obj), &demo_states[S1]);
}
static void s0_exit(void *o) {
    /* Do something */
}

/* State S1 */
static void s1_run(void *o) {
    /* Do something */
}

/* State S2 */
static void s2_entry(void *o) {
    /* Do something */
}
static void s2_run(void *o) {
    /* Do something */
}

(continued from previous page)
### 4.16.7 Hierarchical State Machine Example

This example turns the following state diagram into code using the SMF, where S0 and S1 share a parent state and S0 is the initial state.

**Code:**

```c
#include <zephyr/smf.h>
```

(continues on next page)
Fig. 4.10: Hierarchical state machine diagram

/* Forward declaration of state table */
static const struct smf_state demo_states[];

/* List of demo states */
enum demo_state { PARENT, S0, S1, S2 };

/* User defined object */
struct s_object {
    /* This must be first */
    struct smf_ctx ctx;

    /* Other state specific data add here */
} s_obj;

/* Parent State */
static void parent_entry(void *o)
{
    /* Do something */
}
static void parent_exit(void *o)
{
    /* Do something */
}

/* State S0 */
static void s0_run(void *o)
{

(continues on next page)
When designing hierarchical state machines, the following should be considered:

- Ancestor entry actions are executed before the sibling entry actions. For example, the parent_entry function is called before the s0_entry function.

- Transitioning from one sibling to another with a shared ancestry does not re-execute the ancestor's entry action or execute the exit action. For example, the parent_entry function is not called when transitioning from S0 to S1, nor is the parent_exit function called.

- Ancestor exit actions are executed after the sibling exit actions. For example, the s1_exit function is called before the parent_exit function is called.

- The parent_run function only executes if the child_run function returns without transitioning to another state, i.e. calling smf_set_state.
4.16.8 Event Driven State Machine Example

Events are not explicitly part of the State Machine Framework but an event driven state machine can be implemented using Zephyr Events.

Figure 4.11: Event driven state machine diagram

Code:

```c
#include <zephyr/kernel.h>
#include <zephyr/drivers/gpio.h>
#include <zephyr/smf.h>

#define SW0_NODE DT_ALIAS(sw0)

/* List of events */
#define EVENT_BTN_PRESS BIT(0)

static const struct gpio_dt_spec button =
    GPIO_DT_SPEC_GET_OR(SW0_NODE, gpios, {0});

static struct gpio_callback button_cb_data;

/* Forward declaration of state table */
static const struct smf_state demo_states[];

/* List of demo states */
enum demo_state { S0, S1 };

/* User defined object */
struct s_object {
    /* This must be first */
    struct smf_ctx ctx;

    /* Events */
    struct k_event smf_event;
};
```

(continues on next page)
int32_t events;
 *
 */ Other state specific data add here */
} s_obj;

/* State S0 */
static void s0_entry(void *o)
{
    printk("STATE0\n");
}

static void s0_run(void *o)
{
    struct s_object *s = (struct s_object *)o;
    /* Change states on Button Press Event */
    if (s->events & EVENT_BTN_PRESS) {
        smf_set_state(SMF_CTX(&s_obj), &demo_states[S1]);
    }
}

/* State S1 */
static void s1_entry(void *o)
{
    printk("STATE1\n");
}

static void s1_run(void *o)
{
    struct s_object *s = (struct s_object *)o;
    /* Change states on Button Press Event */
    if (s->events & EVENT_BTN_PRESS) {
        smf_set_state(SMF_CTX(&s_obj), &demo_states[S0]);
    }
}

/* Populate state table */
static const struct smf_state demo_states[] = {
    [S0] = SMF_CREATE_STATE(s0_entry, s0_run, NULL),
    [S1] = SMF_CREATE_STATE(s1_entry, s1_run, NULL),
};

void button_pressed(const struct device *dev,
    struct gpio_callback *cb, uint32_t pins)
{
    /* Generate Button Press Event */
    k_event_post(&s_obj.smf_event, EVENT_BTN_PRESS);
}

void main(void)
{
    int ret;
    if (!device_is_ready(button.port)) {
        printk("Error: button device %s is not ready\n",}
button.port->name);
    return;
}

ret = gpio_pin_configure_dt(&button, GPIO_INPUT);
if (ret != 0) {
    printk("Error %d: failed to configure %s pin %d\n",
           ret, button.port->name, button.pin);
    return;
}

ret = gpio_pin_interrupt_configure_dt(&button,
                                       GPIO_INT_EDGE_TO_ACTIVE);
if (ret != 0) {
    printk("Error %d: failed to configure interrupt on %s pin %d\n",
            ret, button.port->name, button.pin);
    return;
}

gpio_init_callback(&button_cb_data, button_pressed, BIT(button.pin));
gpio_add_callback(button.port, &button_cb_data);

/* Initialize the event */
k_event_init(&s_obj.smf_event);

/* Set initial state */
smf_set_initial(SMF_CTX(&s_obj), &demo_states[S0]);

/* Run the state machine */
while(1) {
    /* Block until an event is detected */
    s_obj.events = k_event_wait(&s_obj.smf_event,
                                 EVENT_BTN_PRESS, true, K_FOREVER);

    /* State machine terminates if a non-zero value is returned */
    ret = smf_run_state(SMF_CTX(&s_obj));
    if (ret) {
        /* handle return code and terminate state machine */
        break;
    }
}

4.17 Storage

4.17.1 Non-Volatile Storage (NVS)

Elements, represented as id-data pairs, are stored in flash using a FIFO-managed circular buffer. The flash area is divided into sectors. Elements are appended to a sector until storage space in the sector is exhausted. Then a new sector in the flash area is prepared for use (erased). Before erasing the sector it is checked that identifier - data pairs exist in the sectors in use, if not the id-data pair is copied.

The id is a 16-bit unsigned number. NVS ensures that for each used id there is at least one id-data pair stored in flash at all time.
NVS allows storage of binary blobs, strings, integers, longs, and any combination of these. Each element is stored in flash as metadata (8 byte) and data. The metadata is written in a table starting from the end of an nvs sector, the data is written one after the other from the start of the sector. The metadata consists of: id, data offset in sector, data length, part (unused) and a crc.

A write of data to nvs always starts with writing the data, followed by a write of the metadata. Data that is written in flash without metadata is ignored during initialization.

During initialization NVS will verify the data stored in flash, if it encounters an error it will ignore any data with missing/incorrect metadata.

NVS checks the id-data pair before writing data to flash. If the id-data pair is unchanged no write to flash is performed.

To protect the flash area against frequent erases it is important that there is sufficient free space. NVS has a protection mechanism to avoid getting in an endless loop of flash page erases when there is limited free space. When such a loop is detected NVS returns that there is no more space available.

For NVS the file system is declared as:

```c
static struct nvs_fs fs = {
    .flash_device = NVS_FLASH_DEVICE,
    .sector_size = NVS_SECTOR_SIZE,
    .sector_count = NVS_SECTOR_COUNT,
    .offset = NVS_STORAGE_OFFSET,
};
```

where

- `NVS_FLASH_DEVICE` is a reference to the flash device that will be used. The device needs to be operational.
- `NVS_SECTOR_SIZE` is the sector size, it has to be a multiple of the flash erase page size and a power of 2.
- `NVS_SECTOR_COUNT` is the number of sectors, it is at least 2, one sector is always kept empty to allow copying of existing data.
- `NVS_STORAGE_OFFSET` is the offset of the storage area in flash.

**Flash wear**

When writing data to flash a study of the flash wear is important. Flash has a limited life which is determined by the number of times flash can be erased. Flash is erased one page at a time and the pagesize is determined by the hardware. As an example a nRF51822 device has a pagesize of 1024 bytes and each page can be erased about 20,000 times.

**Calculating expected device lifetime** Suppose we use a 4 bytes state variable that is changed every minute and needs to be restored after reboot. NVS has been defined with a sector_size equal to the pagesize (1024 bytes) and 2 sectors have been defined.

Each write of the state variable requires 12 bytes of flash storage: 8 bytes for the metadata and 4 bytes for the data. When storing the data the first sector will be full after 1024/12 = 85.33 minutes. After another 85.33 minutes, the second sector is full. When this happens, because we're using only two sectors, the first sector will be used for storage and will be erased after 171 minutes of system time. With the expected device life of 20,000 writes, with two sectors writing every 171 minutes, the device should last about 171 * 20,000 minutes, or about 6.5 years.

More generally then, with

- $NS$ as the number of storage requests per minute,
- $DS$ as the data size in bytes,
• SECTOR_SIZE in bytes, and
  • PAGE_ERASES as the number of times the page can be erased,
the expected device life (in minutes) can be calculated as:

\[
\text{SECTOR\_COUNT} \times \text{SECTOR\_SIZE} \times \text{PAGE\_ERASES} \div (\text{NS} \times (\text{DS+8})) \text{ minutes}
\]

From this formula it is also clear what to do in case the expected life is too short: increase SECTOR\_COUNT or SECTOR\_SIZE.

Flash write block size migration

It is possible that during a DFU process, the flash driver used by the NVS changes the supported minimal write block size. The NVS in-flash image will stay compatible unless the physical ATE size changes. Especially, migration between 1,2,4,8-bytes write block sizes is allowed.

Sample

A sample of how NVS can be used is supplied in samples/subsys/nvs.

Troubleshooting

MPU fault while using NVS, or -ETIMEDOUT error returned
NVS can use the internal flash of the SoC. While the MPU is enabled, the flash driver requires MPU RWX access to flash memory, configured using CONFIG_MPU_ALLOW_FLASH_WRITE. If this option is disabled, the NVS application will get an MPU fault if it references the internal SoC flash and it’s the only thread running. In a multi-threaded application, another thread might intercept the fault and the NVS API will return an -ETIMEDOUT error.

API Reference

The NVS subsystem APIs are provided by nvs.h:

group nvs_data_structures
  Non-volatile Storage Data Structures.

struct nvs_fs
  #include <nvs.h> Non-volatile Storage File system structure.

  Param offset
  File system offset in flash

  Param ate_wra
  Allocation table entry write address. Addresses are stored as uint32_t: high 2 bytes correspond to the sector, low 2 bytes are the offset in the sector

  Param data_wra
  Data write address

  Param sector_size
  File system is split into sectors, each sector must be multiple of pagesize

  Param sector_count
  Number of sectors in the file systems

  Param ready
  Flag indicating if the filesystem is initialized
Param nvs_lock
Mutex

Param flash_device
Flash Device runtime structure

Param flash_parameters
Flash memory parameters structure

group nvs_high_level_api
Non-volatile Storage APIs.

Functions

int nvs_mount(struct nvs_fs *fs)
nvs_mount
Mount a NVS file system onto the flash device specified in fs.

Parameters
• fs – Pointer to file system

Return values
• 0 – Success
• -ERRNO – errno code if error

int nvs_clear(struct nvs_fs *fs)
nvs_clear
Clears the NVS file system from flash.

Parameters
• fs – Pointer to file system

Return values
• 0 – Success
• -ERRNO – errno code if error

ssize_t nvs_write(struct nvs_fs *fs, uint16_t id, const void *data, size_t len)
nvs_write
Write an entry to the file system.

Parameters
• fs – Pointer to file system
• id – Id of the entry to be written
• data – Pointer to the data to be written
• len – Number of bytes to be written

Returns
Number of bytes written. On success, it will be equal to the number of bytes requested to be written. When a rewrite of the same data already stored is attempted, nothing is written to flash, thus 0 is returned. On error, returns negative value of errno.h defined error codes.
int nvs_delete(struct nvs_fs *fs, uint16_t id)
    nvs_delete
Delete an entry from the file system

Parameters
• fs – Pointer to file system
• id – Id of the entry to be deleted

Return values
• 0 – Success
• -ENOMEM – errno code if error

ssize_t nvs_read(struct nvs_fs *fs, uint16_t id, void *data, size_t len)
    nvs_read
Read an entry from the file system.

Parameters
• fs – Pointer to file system
• id – Id of the entry to be read
• data – Pointer to data buffer
• len – Number of bytes to be read

Returns
Number of bytes read. On success, it will be equal to the number of bytes requested to be read. When the return value is larger than the number of bytes requested to read this indicates not all bytes were read, and more data is available. On error, returns negative value of errno.h defined error codes.

ssize_t nvs_read_hist(struct nvs_fs *fs, uint16_t id, void *data, size_t len, uint16_t cnt)
    nvs_read_hist
Read a history entry from the file system.

Parameters
• fs – Pointer to file system
• id – Id of the entry to be read
• data – Pointer to data buffer
• len – Number of bytes to be read
• cnt – History counter: 0: latest entry, 1: one before latest ...

Returns
Number of bytes read. On success, it will be equal to the number of bytes requested to be read. When the return value is larger than the number of bytes requested to read this indicates not all bytes were read, and more data is available. On error, returns negative value of errno.h defined error codes.

ssize_t nvs_calc_free_space(struct nvs_fs *fs)
    nvs_calc_free_space
Calculate the available free space in the file system.

Parameters
• fs – Pointer to file system
Returns
Number of bytes free. On success, it will be equal to the number of bytes that can still be written to the file system. Calculating the free space is a time consuming operation, especially on spi flash. On error, returns negative value of errno.h defined error codes.

4.17.2 Disk Access

Overview
The disk access API provides access to storage devices.

SD Card support
Zephyr has support for some SD card controllers and support for interfacing SD cards via SPI. These drivers use disk driver interface and a file system can access the SD cards via disk access API. Both standard and high-capacity SD cards are supported.

Note: The system does not support inserting or removing cards while the system is running. The cards must be present at boot and must not be removed. This may be fixed in future releases.

FAT filesystems are not power safe so the filesystem may become corrupted if power is lost or if the card is removed.

SD Memory Card subsystem Zephyr supports SD memory cards via the disk driver API, or via the SDMMC subsystem. This subsystem can be used transparently via the disk driver API, but also supports direct block level access to cards. The SDMMC subsystem interacts with the sd host controller api to communicate with attached SD cards.

SD Card support via SPI Example devicetree fragment below shows how to add SD card node to spi1 interface. Example uses pin PA27 for chip select, and runs the SPI bus at 24 MHz once the SD card has been initialized:

```c
&spi1 {
    status = "okay";
    cs-gpios = <&porta 27 GPIO_ACTIVE_LOW>;

    sdhc0: sdhc00 {
        compatible = "zephyr,sdhc-spi-slot";
        reg = <0>;
        status = "okay";
        mmc {
            compatible = "zephyr,sdmmc-disk";
            status = "okay";
        };
        spi-max-frequency = <24000000>;
    };
}
```

The SD card will be automatically detected and initialized by the filesystem driver when the board boots.

To read and write files and directories, see the File Systems in include/zephyr/fs/fs.h such as fs_open(), fs_read(), and fs_write().
Emulated block device on flash partition support

Zephyr flashdisk driver makes it possible to use flash memory partition as a block device. The flashdisk instances are defined in devicetree:

```c
/ {
    msc_disk0 {
        compatible = "zephyr,flash-disk";
        partition = <&storage_partition>;
        disk-name = "NAND";
        cache-size = <4096>;
    }
};
```

The cache size specified in `zephyr,flash-disk` node should be equal to backing partition minimum erasable block size.

Disk Access API Configuration Options

Related configuration options:

- CONFIG_DISK_ACCESS

API Reference

**group** disk_access_interface

Disk Access APIs.

**Functions**

`int disk_access_init(const char *pdrv)`

perform any initialization

This call is made by the consumer before doing any IO calls so that the disk or the backing device can do any initialization.

**Parameters**

- `pdrv` – [in] Disk name

**Returns**

0 on success, negative errno code on fail

`int disk_access_status(const char *pdrv)`

Get the status of disk.

This call is used to get the status of the disk

**Parameters**

- `pdrv` – [in] Disk name

**Returns**

DISK_STATUS_OK or other DISK_STATUS_*s

`int disk_access_read(const char *pdrv, uint8_t *data_buf, uint32_t start_sector, uint32_t num sector)`

read data from disk

Function to read data from disk to a memory buffer.
Parameters

• pdrv – [in] Disk name
• data_buf – [in] Pointer to the memory buffer to put data.
• start_sector – [in] Start disk sector to read from
• num_sector – [in] Number of disk sectors to read

Returns
0 on success, negative errno code on fail

int disk_access_write(const char *pdrv, const uint8_t *data_buf, uint32_t start_sector, uint32_t num_sector)

write data to disk
Function write data from memory buffer to disk.

Parameters

• pdrv – [in] Disk name
• data_buf – [in] Pointer to the memory buffer
• start_sector – [in] Start disk sector to write to
• num_sector – [in] Number of disk sectors to write

Returns
0 on success, negative errno code on fail

int disk_access_ioctl(const char *pdrv, uint8_t cmd, void *buff)

Get/Configure disk parameters.
Function to get disk parameters and make any special device requests.

Parameters

• pdrv – [in] Disk name
• cmd – [in] DISK_IOCTL_* code describing the request
• buff – [in] Command data buffer

Returns
0 on success, negative errno code on fail

Disk Driver Configuration Options

Related driver configuration options:
• CONFIG_DISK_DRIVERS

Disk Driver Interface

group disk_driver_interface
Disk Driver Interface.

Defines
DISK_IOCTL_GET_SECTOR_COUNT
   Possible Cmd Codes for disk_ioctl()
   Get the number of sectors in the disk

DISK_IOCTL_GET_SECTOR_SIZE
   Get the size of a disk SECTOR in bytes

DISK_IOCTL_RESERVED
   reserved. It used to be DISK_IOCTL_GET_DISK_SIZE

DISK_IOCTL_GET_ERASE_BLOCK_SZ
   How many sectors constitute a FLASH Erase block

DISK_IOCTL_CTRL_SYNC
   Commit any cached read/writes to disk

DISK_STATUS_OK
   Possible return bitmasks for disk_status()
   Disk status okay

DISK_STATUS_UNINIT
   Disk status uninitialized

DISK_STATUS_NOMEDIA
   Disk status no media

DISK_STATUS_WR_PROTECT
   Disk status write protected

Functions

int disk_access_register(struct disk_info *disk)
   Register disk.

   Parameters
   • disk – [in] Pointer to the disk info structure

   Returns
   0 on success, negative errno code on fail

int disk_access_unregister(struct disk_info *disk)
   Unregister disk.

   Parameters
   • disk – [in] Pointer to the disk info structure

   Returns
   0 on success, negative errno code on fail

struct disk_info
   #include <disk.h>  Disk info.
Public Members

`sys_dnode_t node`
Internally used list node

`char *name`
Disk name

`const struct disk_operations *ops`
Disk operations

`const struct device *dev`
Device associated to this disk

```c
#include <disk.h>
```
Disk operations.

### 4.17.3 Flash map

The `<storage/flash_map.h>` API allows accessing information about device flash partitions via `flash_area` structures.

Each `flash_area` describes a flash partition. The API provides access to a “flash map”, which contains predefined flash areas accessible via globally unique ID numbers. The map is created from “fixed-partition” compatible entries in DTS file. Users may also create `flash_area` objects at runtime for application-specific purposes.

This documentation uses “flash area” when referencing single “fixed-partition” entities.

The `flash_area` contains a pointer to a `device`, which can be used to access the flash device an area is placed on directly with the `flash API`. Each flash area is characterized by a device it is placed on, offset from the beginning of the device and size on the device. An additional identifier parameter is used by the `flash_area_open()` function to find flash area in flash map.

The `flash_map.h` API provides functions for operating on a `flash_area`. The main examples are `flash_area_read()` and `flash_area_write()`. These functions are basically wrappers around the flash API with additional offset and size checks, to limit flash operations to a predefined area.

Most `<storage/flash_map.h>` API functions require a `flash_area` object pointer characterizing the flash area they will be working on. There are two possible methods to obtain such a pointer:

- obtain it using `flash_area_open();`
- defining a `flash_area` type object, which requires providing a valid `device` object pointer with offset and size of the area within the flash device.

`flash_area_open()` uses numeric identifiers to search flash map for `flash_area` objects and returns, if found, a pointer to an object representing area with given ID. The ID number for a flash area can be obtained from a fixed-partition DTS node label using `FIXED_PARTITION_ID();` these labels are obtained from the devicetree as described below.

**Relationship with Devicetree**

The `flash_map.h` API uses data generated from the `Devicetree API`, in particular its `Fixed flash partitions`. Zephyr additionally has some partitioning conventions used for `Device Firmware Upgrade` via the MCU-boot bootloader, as well as defining partitions usable by `file systems` or other nonvolatile `storage`. 
Here is an example devicetree fragment which uses fixed flash partitions for both MCUboot and a storage partition. Some details were left out for clarity.

/ {
    soc {
        flashctrl: flash-controller@deadbeef {
            flash0: flash@0 {
                compatible = "soc-nv-flash";
                reg = <0x0 0x100000>;

                partitions {
                    compatible = "fixed-partitions";
                    #address-cells = <0x1>;
                    #size-cells = <0x1>;

                    boot_partition: partition@0 {
                        reg = <0x0 0x10000>;
                        read-only;
                    }

                    storage_partition: partition@1e000 {
                        reg = <0x1e000 0x2000>;
                    }

                    slot0_partition: partition@20000 {
                        reg = <0x20000 0x60000>;
                    }

                    slot1_partition: partition@80000 {
                        reg = <0x80000 0x60000>;
                    }

                    scratch_partition: partition@e0000 {
                        reg = <0xe0000 0x20000>;
                    }
                }
            }
        }
    }
};

Partition offset shall be expressed in relation to the flash memory beginning address, to which the partition belongs to.

The `boot_partition`, `slot0_partition`, `slot1_partition`, and `scratch_partition` node labels are defined for MCUboot, though not all MCUboot configurations require all of them to be defined. See the MCUboot documentation for more details.

The `storage_partition` node is defined for use by a file system or other nonvolatile storage API.

Numeric flash area ID is obtained by passing DTS node label to `FIXED_PARTITION_ID()`; for example to obtain ID number for `slot0_partition`, user would invoke `FIXED_PARTITION_ID(slot0_partition)`.

All `FIXED_PARTITION_` macros take DTS node labels as partition identifiers.

Users do not have to obtain a `flash_area` object pointer using `flash_map_open()` to get information on flash area size, offset or device, if such area is defined in DTS file. Knowing the DTS node label of an area, users may use `FIXED_PARTITION_OFFSET()``, `FIXED_PARTITION_SIZE()` or `FIXED_PARTITION_DEVICE()` respectively to obtain such information directly from DTS node definition. For example to obtain offset of `storage_partition` it is enough to invoke `FIXED_PARTITION_OFFSET(storage_partition)`.

Below example shows how to obtain a `flash_area` object pointer using `flash_area_open()` and DTS node label:
struct flash_area *my_area;
int err = flash_area_open(FIXED_PARTITION_ID(slot0_partition), &my_area);

if (err != 0) {
    handle_the_error(err);
} else {
    flash_area_read(my_area, ...);
}

API Reference

group flash_area_api
    Abstraction over flash partitions/areas and their drivers.

Defines

SOC_FLASH_0_ID
    Provided for compatibility with MCUboot
SPI_FLASH_0_ID
    Provided for compatibility with MCUboot
FLASH_AREA_LABEL_EXISTS(label)
FLASH_AREA_LABEL_STR(lbl)
FLASH_AREA_ID(label)
FLASH_AREA_OFFSET(label)
FLASH_AREA_SIZE(label)
FIXED_PARTITION_EXISTS(label)
    Returns non-0 value if fixed-partition of given DTS node label exists.

Parameters
    • label – DTS node label

Returns
    non-0 if fixed-partition node exists and is enabled; 0 if node does not exist, is not enabled or is not fixed-partition.

FIXED_PARTITION_ID(label)
    Get flash area ID from fixed-partition DTS node label

Parameters
    • label – DTS node label of a partition

Returns
    flash area ID

FIXED_PARTITION_OFFSET(label)
    Get fixed-partition offset from DTS node label

Parameters
    • label – DTS node label of a partition
**Returns**

fixed-partition offset, as defined for the partition in DTS.

**FIXED_PARTITION_SIZE**<br>
Get fixed-partition size for DTS node label

**Parameters**

- label – DTS node label

**Returns**

fixed-partition offset, as defined for the partition in DTS.

**FLASH_AREA_DEVICE**<br>
Get device pointer for device the area/partition resides on

**Parameters**

- label – DTS node label of a partition

**Returns**

const struct device type pointer

**FIXED_PARTITION_DEVICE**<br>
Get device pointer for device the area/partition resides on

**Parameters**

- label – DTS node label of a partition

**Returns**

Pointer to a device.

**Typedefs**

typedef void (*flash_area_cb_t)(const struct flash_area *fa, void *user_data)<br>
Flash map iteration callback

**Param fa**
flash area

**Param user_data**
User supplied data

**Functions**

int flash_area_open(uint8_t id, const struct flash_area **fa)<br>
Retrieve partitions flash area from the flash_map.<br>
Function Retrieves flash_area from flash_map for given partition.

**Parameters**

- fa – [out] Pointer which has to reference flash_area. If ID is unknown, it will be NULL on output.

**Returns**

0 on success, -EACCES if the flash_map is not available, -ENOENT if ID is unknown, -ENODEV if there is no driver attached to the area.
void flash_area_close(const struct flash_area *fa)

Close flash_area.

Reserved for future usage and external projects compatibility reason. Currently is NOP.

Parameters

• fa – [in] Flash area to be closed.

int flash_area_read(const struct flash_area *fa, off_t off, void *dst, size_t len)

Read flash area data.

Read data from flash area. Area readout boundaries are asserted before read request. API has the same limitation regard read-block alignment and size as wrapped flash driver.

Parameters

• fa – [in] Flash area
• off – [in] Offset relative from beginning of flash area to read
• dst – [out] Buffer to store read data
• len – [in] Number of bytes to read

Returns

0 on success, negative errno code on fail.

int flash_area_write(const struct flash_area *fa, off_t off, const void *src, size_t len)

Write data to flash area.

Write data to flash area. Area write boundaries are asserted before write request. API has the same limitation regard write-block alignment and size as wrapped flash driver.

Parameters

• fa – [in] Flash area
• off – [in] Offset relative from beginning of flash area to read
• src – [out] Buffer with data to be written
• len – [in] Number of bytes to write

Returns

0 on success, negative errno code on fail.

int flash_area_erase(const struct flash_area *fa, off_t off, size_t len)

Erase flash area.

Erase given flash area range. Area boundaries are asserted before erase request. API has the same limitation regard erase-block alignment and size as wrapped flash driver.

Parameters

• fa – [in] Flash area
• off – [in] Offset relative from beginning of flash area.
• len – [in] Number of bytes to be erase

Returns

0 on success, negative errno code on fail.

uint32_t flash_area_align(const struct flash_area *fa)

Get write block size of the flash area.

Currently write block size might be treated as read block size, although most of drivers supports unaligned readout.

Parameters
• **fa** – [in] Flash area

**Returns**
Alignment restriction for flash writes in [B].

```c
int flash_area_get_sectors(int fa_id, uint32_t *count, struct flash_sector *sectors)
```

Retrieve info about sectors within the area.

**Parameters**
- **fa_id** – [in] Given flash area ID
- **sectors** – [out] buffer for sectors data
- **count** – [inout] On input Capacity of sectors, on output number of sectors Retrieved.

**Returns**
0 on success, negative errno code on fail. Especially returns -ENOMEM if There are too many flash pages on the flash_area to fit in the array.

```c
void flash_area_foreach(flash_area_cb_t user_cb, void *user_data)
```

Iterate over flash map

**Parameters**
- **user_cb** – User callback
- **user_data** – User supplied data

```c
int flash_area_has_driver(const struct flash_area *fa)
```

Check whether given flash area has supporting flash driver in the system.

**Parameters**
- **fa** – [in] Flash area.

**Returns**
1 On success. -ENODEV if no driver match.

```c
const struct device *flash_area_get_device(const struct flash_area *fa)
```

Get driver for given flash area.

**Parameters**
- **fa** – Flash area.

**Returns**
device driver.

```c
uint8_t flash_area_erased_val(const struct flash_area *fa)
```

Get the value expected to be read when accessing any erased flash byte. This API is compatible with the MCUBoot's porting layer.

**Parameters**
- **fa** – Flash area.

**Returns**
Byte value of erase memory.

```c
struct flash_area
```

*include <flash_map.h>* Flash partition.

This structure represents a fixed-size partition on a flash device. Each partition contains one or more flash sectors.
Public Members

uint8_t fa_id
    ID number

uint8_t fa_device_id
    Provided for compatibility with MCUboot

off_t fa_off
    Start offset from the beginning of the flash device

size_t fa_size
    Total size

const struct device *fa_dev
    Backing flash device

struct flash_sector
    #include <flash_map.h> Structure for transfer flash sector boundaries.
    This template is used for presentation of flash memory structure. It consumes much less RAM than flash_area

Public Members

off_t fs_off
    Sector offset from the beginning of the flash device

size_t fs_size
    Sector size in bytes

4.17.4 Flash Image

The flash image API as part of the Device Firmware Upgrade (DFU) subsystem provides an abstraction on top of Flash Stream to simplify writing firmware image chunks to flash.

API Reference

group flash_img_api
    Abstraction layer to write firmware images to flash.

Functions

int flash_img_init_id(struct flash_img_context *ctx, uint8_t area_id)
    Initialize context needed for writing the image to the flash.

Parameters
    • ctx – context to be initialized
• area_id – flash area id of partition where the image should be written

Returns
0 on success, negative errno code on fail

int flash_img_init(struct flash_img_context *ctx)
Initialize context needed for writing the image to the flash.

Parameters
• ctx – context to be initialized

Returns
0 on success, negative errno code on fail

size_t flash_img_bytes_written(struct flash_img_context *ctx)
Read number of bytes of the image written to the flash.

Parameters
• ctx – context

Returns
Number of bytes written to the image flash.

int flash_img_buffered_write(struct flash_img_context *ctx, const uint8_t *data, size_t len, bool flush)
Process input buffers to be written to the image slot 1. flash memory in single blocks. Will store remainder between calls.

A final call to this function with flush set to true will write out the remaining block buffer to flash. Since flash is written to in blocks, the contents of flash from the last byte written up to the next multiple of CONFIG_IMG_BLOCK_BUF_SIZE is padded with 0xff.

Parameters
• ctx – context
• data – data to write
• len – Number of bytes to write
• flush – when true this forces any buffered data to be written to flash

Returns
0 on success, negative errno code on fail

int flash_img_check(struct flash_img_context *ctx, const struct flash_img_check *fic, uint8_t area_id)
Verify flash memory length bytes integrity from a flash area. The start point is indicated by an offset value.

The function is enabled via CONFIG_IMG_ENABLE_IMAGE_CHECK Kconfig options.

Parameters
• ctx – [in] context.
• fic – [in] flash img check data.
• area_id – [in] flash area id of partition where the image should be verified.

Returns
0 on success, negative errno code on fail

#include <flash_img.h>
struct flash_img_check

#include <flash_img.h> Structure for verify flash region integrity.

Match vector length is fixed and depends on size from hash algorithm used to verify flash integrity. The current available algorithm is SHA-256.

Public Members

size_t clen

Match vector data

4.17.5 Flash Circular Buffer (FCB)

Flash circular buffer provides an abstraction through which you can treat flash like a FIFO. You append entries to the end, and read data from the beginning.

**Note:** As of Zephyr release 2.1 the NVS storage API is recommended over FCB for use as a back-end for the settings API.

Description

Entries in the flash contain the length of the entry, the data within the entry, and checksum over the entry contents.

Storage of entries in flash is done in a FIFO fashion. When you request space for the next entry, space is located at the end of the used area. When you start reading, the first entry served is the oldest entry in flash.

Entries can be appended to the end of the area until storage space is exhausted. You have control over what happens next; either erase oldest block of data, thereby freeing up some space, or stop writing new data until existing data has been collected. FCB treats underlying storage as an array of flash sectors; when it erases old data, it does this a sector at a time.

Entries in the flash are checksummed. That is how FCB detects whether writing entry to flash completed ok. It will skip over entries which don't have a valid checksum.

Usage

To add an entry to circular buffer:

- Call `fcb_append()` to get the location where data can be written. If this fails due to lack of space, you can call `fcb_rotate()` to erase the oldest sector which will make the space. And then call `fcb_append()` again.
- Use `flash_area_write()` to write entry contents.
- Call `fcb_append_finish()` when done. This completes the writing of the entry by calculating the checksum.

To read contents of the circular buffer:

- Call `fcb_walk()` with a pointer to your callback function.
- Within callback function copy in data from the entry using `flash_area_read()`. You can tell when all data from within a sector has been read by monitoring the returned entry’s area pointer. Then you can call `fcb_rotate()`, if you're done with that data.
Alternatively:

- Call `fcb_getnext()` with 0 in entry offset to get the pointer to the oldest entry.
- Use `flash_area_read()` to read entry contents.
- Call `fcb_getnext()` with pointer to current entry to get the next one. And so on.

**API Reference**

The FCB subsystem APIs are provided by `fcb.h`:

**Data structures**

`group fcb_data_structures`

**Defines**

- `FCB_MAX_LEN`  
  Max length of element

- `FCB_ENTRY_FA_DATA_OFF(entry)`  
  Helper macro for calculating the data offset related to the fcb `flash_area` start offset.

  **Parameters**

  - entry – fcb entry structure

- `struct fcb_entry`  
  
  #include `<fcb.h>` FCB entry info structure. This data structure describes the element location in the flash.

  You would use it to figure out what parameters to pass to `flash_area_read()` to read element contents. Or to `flash_area_write()` when adding a new element. Entry location is pointer to area (within fcb->`f_sectors`), and offset within that area.

- `struct flash_sector *fe_sector`  
  Pointer to info about sector where data are placed

- `uint32_t fe_elem_off`  
  Offset from the start of the sector to beginning of element.

- `uint32_t fe_data_off`  
  Offset from the start of the sector to the start of element.

- `uint16_t fe_data_len`  
  Size of data area in fcb entry

- `struct fcb_entry_ctx`  
  
  #include `<fcb.h>` Structure for transferring complete information about FCB entry location within flash memory.
Public Members

struct fcb_entry loc
   FCB entry info

const struct flash_area *fap
   Flash area where the entry is placed

struct fcb
   #include <fcb.h> FCB instance structure.
   The following data structure describes the FCB itself. First part should be filled in by the user before calling fcb_init. The second part is used by FCB for its internal bookkeeping.

Public Members

uint32_t f_magic
   Magic value, should not be 0xFFFFFFFF. It is xored with inversion of f_erase_value and placed in the beginning of FCB flash sector. FCB uses this when determining whether sector contains valid data or not. Giving it value of 0xFFFFFFFF means leaving bytes of the file in “erased” state.

uint8_t f_version
   Current version number of the data

uint8_t f_sector_cnt
   Number of elements in sector array

uint8_t f_scratch_cnt
   Number of sectors to keep empty. This can be used if you need to have scratch space for garbage collecting when FCB fills up.

struct flash_sector *f_sectors
   Array of sectors, must be contiguous

struct k_mutex f_mtx
   Locking for accessing the FCB data, internal state

struct flash_sector *f_oldest
   Pointer to flash sector containing the oldest data, internal state

struct fcb_entry f_active
   internal state

uint16_t f_active_id
   Flash location where the newest data is, internal state

uint8_t f_align
   writes to flash have to aligned to this, internal state
const struct flash_area *fap

Flash area used by the fcb instance, internal state. This can be transfer to FCB user

uint8_t f_erase_value

The value flash takes when it is erased. This is read from flash parameters and initialized upon call to fcb_init.

API functions

group fcb_api

Flash Circular Buffer APIs.

Typedefs

typedef int (*fcb_walk_cb)(struct fcb_entry_ctx *loc_ctx, void *arg)

FCB Walk callback function type.

Type of function which is expected to be called while walking over fcb entries thanks to a fcb_walk call.

Entry data can be read using flash_area_read(), using loc_ctx fields as arguments. If cb wants to stop the walk, it should return non-zero value.

Param loc_ctx [in]
entry location information (full context)

Param arg [inout] callback context, transferred from fcb_walk.

Return
0 continue walking, non-zero stop walking.

Functions

int fcb_init(int f_area_id, struct fcb *fcb)

Initialize FCB instance.

Parameters

• f_area_id – [in] ID of flash area where fcb storage resides.
• fcb – [inout] FCB instance structure.

Returns
0 on success, non-zero on failure.

int fcb_append(struct fcb *fcb, uint16_t len, struct fcb_entry *loc)

Appends an entry to circular buffer.

When writing the contents for the entry, use loc->fe_sector and loc->fe_data_off with flash_area_write() to fcb flash_area. When you're finished, call fcb_append_finish() with loc as argument.

Parameters

• fcb – [in] FCB instance structure.
• len – [in] Length of data which are expected to be written as the entry payload.
• loc – [out] entry location information
Returns
0 on success, non-zero on failure.

int fcb_append_finish(struct fcb *fcb, struct fcb_entry *append_loc)
Finishes entry append operation.

Parameters
• fcb – [in] FCB instance structure.
• append_loc – [in] entry location information

Returns
0 on success, non-zero on failure.

int fcb_walk(struct fcb *fcb, struct flash_sector *sector, fcb_walk_cb cb, void *cb_arg)
Walk over all entries in the FCB sector

Parameters
• sector – [in] fcb sector to be walked. If null, traverse entire storage.
• fcb – [in] FCB instance structure.
• cb – [in] pointer to the function which gets called for every entry. If cb wants to stop the walk, it should return non-zero value.
• cb_arg – [inout] callback context, transferred to the callback implementation.

Returns
0 on success, negative on failure (or transferred form callback return-value), positive transferred form callback return-value

int fcb_getnext(struct fcb *fcb, struct fcb_entry *loc)
Get next fcb entry location.

Function to obtain fcb entry location in relation to entry pointed by loc. If loc->fe_sector is set and loc->fe_elem_off is not 0 function fetches next fcb entry location. If loc->fe_sector is NULL function fetches the oldest entry location within FCB storage. loc->fe_sector is set and loc->fe_elem_off is 0 function fetches the first entry location in the fcb sector.

Parameters
• fcb – [in] FCB instance structure.
• loc – [inout] entry location information

Returns
0 on success, non-zero on failure.

int fcb_rotate(struct fcb *fcb)
Rotate fcb sectors

Function erases the data from oldest sector. Upon that the next sector becomes the oldest. Active sector is also switched if needed.

Parameters
• fcb – [in] FCB instance structure.

int fcb_append_to_scratch(struct fcb *fcb)
Start using the scratch block.

Take one of the scratch blocks into use. So a scratch sector becomes active sector to which entries can be appended.

Parameters
• `fcb` – [in] FCB instance structure.

Returns
0 on success, non-zero on failure.

```c
int fcb_free_sector_cnt(struct fcb *fcb)
```
Get free sector count.

Parameters
• `fcb` – [in] FCB instance structure.

Returns
Number of free sectors.

```c
int fcb_is_empty(struct fcb *fcb)
```
Check whether FCB has any data.

Parameters
• `fcb` – [in] FCB instance structure.

Returns
Positive value if fcb is empty, otherwise 0.

```c
int fcb_offset_last_n(struct fcb *fcb, uint8_t entries, struct fcb_entry *last_n_entry)
```
Finds the fcb entry that gives back up to n entries at the end.

Parameters
• `fcb` – [in] FCB instance structure.
• `entries` – [in] number of fcb entries the user wants to get
• `last_n_entry` – [out] last_n_entry the `fcb_entry` to be returned

Returns
0 on there are any fcbs available; -ENOENT otherwise

```c
int fcb_clear(struct fcb *fcb)
```
Clear fcb instance storage.

Parameters
• `fcb` – [in] FCB instance structure.

Returns
0 on success; non-zero on failure

4.17.6 Stream Flash

The Stream Flash module takes contiguous fragments of a stream of data (e.g. from radio packets), aggregates them into a user-provided buffer, then when the buffer fills (or stream ends) writes it to a raw flash partition. It supports providing the read-back buffer to the client to use in validating the persisted stream content.

One typical use of a stream write operation is when receiving a new firmware image to be used in a DFU operation.

There are several reasons why one might want to use buffered writes instead of writing the data directly as it is made available. Some devices have hardware limitations which does not allow flash writes to be performed in parallel with other operations, such as radio RX and TX. Also, fewer write operations result in faster response times seen from the application.
Persistent stream write progress

Some stream write operations, such as DFU operations, may run for a long time. When performing such long running operations it can be useful to be able to save the stream write progress to persistent storage so that the operation can resume at the same point after an unexpected interruption.

The Stream Flash module offers an API for loading, saving and clearing stream write progress to persistent storage using the Settings module. The API can be enabled using CONFIG_STREAM_FLASH_PROGRESS.

API Reference

**group stream_flash**

Abstraction over stream writes to flash.

**Typedefs**

typedef int (*stream_flash_callback_t)(uint8_t *buf, size_t len, size_t offset)

Signature for callback invoked after flash write completes.

Functions of this type are invoked with a buffer containing data read back from the flash after a flash write has completed. This enables verifying that the data has been correctly stored (for instance by using a SHA function). The write buffer ‘buf’ provided in stream_flash_init is used as a read buffer for this purpose.

**Param buf**

Pointer to the data read.

**Param len**

The length of the data read.

**Param offset**

The offset the data was read from.

**Functions**

```c
int stream_flash_init(struct stream_flash_ctx *ctx, const struct device *fdev, uint8_t *buf, size_t buf_len, size_t offset, size_t size, stream_flash_callback_t cb)
```

Initialize context needed for stream writes to flash.

**Parameters**

- **ctx** – context to be initialized
- **fdev** – Flash device to operate on
- **buf** – Write buffer
- **buf_len** – Length of write buffer. Can not be larger than the page size. Must be multiple of the flash device write-block-size.
- **offset** – Offset within flash device to start writing to
- **size** – Number of bytes available for performing buffered write. If this is ‘0’, the size will be set to the total size of the flash device minus the offset.
- **cb** – Callback to be invoked on completed flash write operations.

**Returns**

non-negative on success, negative errno code on fail
size_t stream_flash_bytes_written(struct stream_flash_ctx *ctx)
    Read number of bytes written to the flash.

Note: api-tags: pre-kernel-ok isr-ok

Parameters
• ctx – context

Returns
Number of payload bytes written to flash.

int stream_flash_buffered_write(struct stream_flash_ctx *ctx, const uint8_t *data, size_t len, bool flush)
    Process input buffers to be written to flash device in single blocks. Will store remainder
    between calls.
    A final call to this function with flush set to true will write out the remaining block buffer to
    flash.

Parameters
• ctx – context
• data – data to write
• len – Number of bytes to write
• flush – when true this forces any buffered data to be written to flash A flush
    write should be the last write operation in a sequence of write operations for
    given context (although this is not mandatory if the total data size is a multiple
    of the buffer size).

Returns
non-negative on success, negative errno code on fail

int stream_flash_erase_page(struct stream_flash_ctx *ctx, off_t off)
    Erase the flash page to which a given offset belongs.
    This function erases a flash page to which an offset belongs if this page is not the page previ-
    ously erased by the provided ctx (ctx->last_erased_page_start_offset).

Parameters
• ctx – context
• off – offset from the base address of the flash device

Returns
non-negative on success, negative errno code on fail

int stream_flash_progress_load(struct stream_flash_ctx *ctx, const char *settings_key)
    Load persistent stream write progress stored with key settings_key.
    This function should be called directly after stream_flash_init to load previous stream write
    progress before writing any data. If the loaded progress has fewer bytes written than ctx then
    it will be ignored.

Parameters
• ctx – context
• settings_key – key to use with the settings module for loading the stream
    write progress
Returns
non-negative on success, negative errno code on fail

int stream_flash_progress_save(struct stream_flash_ctx *ctx, const char *settings_key)
Save persistent stream write progress using key settings_key.

Parameters
- ctx – context
- settings_key – key to use with the settings module for storing the stream write progress

Returns
non-negative on success, negative errno code on fail

int stream_flash_progress_clear(struct stream_flash_ctx *ctx, const char *settings_key)
Clear persistent stream write progress stored with key settings_key.

Parameters
- ctx – context
- settings_key – key previously used for storing the stream write progress

Returns
non-negative on success, negative errno code on fail

struct stream_flash_ctx
#include <stream_flash.h> Structure for stream flash context.

Users should treat these structures as opaque values and only interact with them through the below API.

4.18 Task Watchdog

4.18.1 Overview

Many microcontrollers feature a hardware watchdog timer peripheral. Its purpose is to trigger an action (usually a system reset) in case of severe software malfunctions. Once initialized, the watchdog timer has to be restarted (“fed”) in regular intervals to prevent it from timing out. If the software got stuck and does not manage to feed the watchdog anymore, the corrective action is triggered to bring the system back to normal operation.

In real-time operating systems with multiple tasks running in parallel, a single watchdog instance may not be sufficient anymore, as it can be used for only one task. This software watchdog based on kernel timers provides a method to supervise multiple threads or tasks (called watchdog channels).

An existing hardware watchdog can be used as an optional fallback if the task watchdog itself or the scheduler has a malfunction.

The task watchdog uses a kernel timer as its backend. If configured properly, the timer ISR is never actually called during normal operation, as the timer is continuously updated in the feed calls.

It's currently not possible to have multiple instances of task watchdogs. Instead, the task watchdog API can be accessed globally to add or delete new channels without passing around a context or device pointer in the firmware.

The maximum number of channels is predefined via Kconfig and should be adjusted to match exactly the number of channels required by the application.
4.18.2 Configuration Options

Related configuration options can be found under `subsys/task_wdt/Kconfig`.

- `CONFIG_TASK_WDT`
- `CONFIG_TASK_WDT_CHANNELS`
- `CONFIG_TASK_WDT_HW_FALLBACK`
- `CONFIG_TASK_WDT_MIN_TIMEOUT`
- `CONFIG_TASK_WDT_HW_FALLBACK_DELAY`

4.18.3 API Reference

`group task_wdt_api`

Task Watchdog APIs.

**Typedefs**

typedef void (*task_wdt_callback_t)(int channel_id, void *user_data)

Task watchdog callback.

**Functions**

```c
int task_wdt_init(const struct device *hw_wdt)
```

Initialize task watchdog.

This function sets up necessary kernel timers and the hardware watchdog (if desired as fallback). It has to be called before `task_wdt_add()` and `task_wdt_feed()`.

**Parameters**

- `hw_wdt` – Pointer to the hardware watchdog device used as fallback. Pass NULL if no hardware watchdog fallback is desired.

**Return values**

- `0` – If successful.
- `-ENOTSUP` – If assigning a hardware watchdog is not supported.
- `-Errno` – Negative errno if the fallback hw_wdt is used and the install timeout API fails. See `wdt_install_timeout()` API for possible return values.

```c
int task_wdt_add(uint32_t reload_period, task_wdt_callback_t callback, void *user_data)
```

Install new timeout.

Adds a new timeout to the list of task watchdog channels.

**Parameters**

- `reload_period` – Period in milliseconds used to reset the timeout
- `callback` – Function to be called when watchdog timer expired. Pass NULL to use system reset handler.
- `user_data` – User data to associate with the watchdog channel.

**Return values**
• channel_id – If successful, a non-negative value indicating the index of the channel to which the timeout was assigned. This ID is supposed to be used as the parameter in calls to task_wdt_feed().

• -EINVAL – If the reload_period is invalid.

• -ENOMEM – If no more timeouts can be installed.

```c
int task_wdt_delete(int channel_id)
```
Delete task watchdog channel.

Deletes the specified channel from the list of task watchdog channels. The channel is now available again for other tasks via task_wdt_add() function.

**Parameters**

- channel_id – Index of the channel as returned by task_wdt_add().

**Return values**

- 0 – If successful.

- EINVAL – If there is no installed timeout for supplied channel.

```c
int task_wdt_feed(int channel_id)
```
Feed specified watchdog channel.

This function loops through all installed task watchdogs and updates the internal kernel timer used as for the software watchdog with the next due timeout.

**Parameters**

- channel_id – Index of the fed channel as returned by task_wdt_add().

**Return values**

- 0 – If successful.

- EINVAL – If there is no installed timeout for supplied channel.

### 4.19 Trusted Firmware-M

#### 4.19.1 Trusted Firmware-M Overview

**Trusted Firmware-M (TF-M)** is a reference implementation of the Platform Security Architecture (PSA) IoT Security Framework. It defines and implements an architecture and a set of software components that aim to address some of the main security concerns in IoT products.

Zephyr RTOS has been PSA Certified since Zephyr 2.0.0 with TF-M 1.0, and is currently integrated with TF-M 1.4.1.

**What Does TF-M Offer?**

Through a set of secure services and by design, TF-M provides:

- Isolation of secure and non-secure resources
- Embedded-appropriate crypto
- Management of device secrets (keys, etc.)
- Firmware verification (and encryption)
- Protected off-chip data storage and retrieval
- Proof of device identity (device attestation)
Audit logging

Build System Integration

When using TF-M with a supported platform, TF-M will be automatically built and link in the background as part of the standard Zephyr build process. This build process makes a number of assumptions about how TF-M is being used, and has certain implications about what the Zephyr application image can and cannot do:

- The secure processing environment (secure boot and TF-M) starts first
- Resource allocation for Zephyr relies on choices made in the secure image.

Architecture Overview

A TF-M application will, generally, have the following three parts, from most to least trusted, left-to-right, with code execution happening in the same order (secure boot > secure image > ns image).

While the secure bootloader is optional, it is enabled by default, and secure boot is an important part of providing a secure solution:

<table>
<thead>
<tr>
<th>Secure Processing Environment (SPE)</th>
<th>NSPE</th>
</tr>
</thead>
<tbody>
<tr>
<td>bl2.bin</td>
<td>zephyr.bin</td>
</tr>
<tr>
<td>Secure Boot</td>
<td>Trusted Firmware-M APIs</td>
</tr>
<tr>
<td>(Secure Image)</td>
<td>Zephyr</td>
</tr>
<tr>
<td></td>
<td>(NS Image)</td>
</tr>
</tbody>
</table>

Communication between the (Zephyr) Non-Secure Processing Environment (NSPE) and the (TF-M) Secure Processing Environment image happens based on a set of PSA APIs, and normally makes use of an IPC mechanism that is included as part of the TF-M build, and implemented in Zephyr (see modules/trusted-firmware-m/interface).

Root of Trust (RoT) Architecture

TF-M is based upon a Root of Trust (RoT) architecture. This allows for hierarchies of trust from most, to less, to least trusted, providing a sound foundation upon which to build or access trusted services and resources.

The benefit of this approach is that less trusted components are prevented from accessing or compromising more critical parts of the system, and error conditions in less trusted environments won’t corrupt more trusted, isolated resources.

The following RoT hierarchy is defined for TF-M, from most to least trusted:

- PSA Root of Trust (PRoT), which consists of:
  - PSA Immutable Root of Trust: secure boot
  - PSA Updateable Root of Trust: most trusted secure services
- Application Root of Trust (ARoT): isolated secure services

The PSA Immutable Root of Trust is the most trusted piece of code in the system, to which subsequent Roots of Trust are anchored. In TF-M, this is the secure boot image, which verifies that the secure and non-secure images are valid, have not been tampered with, and come from a reliable source. The secure bootloader also verifies new images during the firmware update process, thanks to the public signing key(s) built into it. As the name implies, this image is immutable.
The **PSA Updateable Root of Trust** implements the most trusted secure services and components in TF-M, such as the Secure Partition Manager (SPM), and shared secure services like PSA Crypto, Internal Trusted Storage (ITS), etc. Services in the PSA Updateable Root of Trust have access to other resources in the same Root of Trust.

The **Application Root of Trust** is a reduced-privilege area in the secure processing environment which, depending on the isolation level chosen when building TF-M, has limited access to the PRoT, or even other ARoT services at the highest isolation levels. Some standard services exist in the ARoT, such as Protected Storage (PS), and generally custom secure services that you implement should be placed in the ARoT, unless a compelling reason is present to place them in the PRoT.

These divisions are distinct from the **untrusted code**, which runs in the non-secure environment, and has the least privilege in the system. This is the Zephyr application image in this case.

### Isolation Levels

At present, there are three distinct isolation levels defined in TF-M, with increasingly rigid boundaries between regions. The isolation level used will depend on your security requirements, and the system resources available to you.

- **Isolation Level 1** is the lowest isolation level, and the only major boundary is between the secure and non-secure processing environment, usually by means of Arm TrustZone on Armv8-M processors. There is no distinction here between the PSA Updateable Root of Trust (PRoT) and the Application Root of Trust (ARoT). They execute at the same privilege level. This isolation level will lead to the smallest combined application images.

- **Isolation Level 2** builds upon level one by introducing a distinction between the PSA Updateable Root of Trust and the Application Root of Trust, where ARoT services have limited access to PRoT services, and can only communicate with them through public APIs exposed by the PRoT services. ARoT services, however, are not strictly isolated from one another.

- **Isolation Level 3** is the highest isolation level, and builds upon level 2 by isolating ARoT services from each other, so that each ARoT is essentially silo’ed from other services. This provides the highest level of isolation, but also comes at the cost of additional overhead and code duplication between services.

The current isolation level can be checked via `CONFIG_TFM_ISOLATION_LEVEL`.

### Secure Boot

The default secure bootloader in TF-M is based on MCUBoot, and is referred to as BL2 in TF-M (for the second-stage bootloader, potentially after a HW-based bootloader on the secure MCU, etc.).

All images in TF-M are hashed and signed, with the hash and signature verified by MCUBoot during the firmware update process.

Some key features of MCUBoot as used in TF-M are:

- Public signing key(s) are baked into the bootloader
- S and NS images can be signed using different keys
- Firmware images can optionally be encrypted
- Client software is responsible for writing a new image to the secondary slot
- By default, uses static flash layout of two identically-sized memory regions
- Optional security counter for rollback protection

When dealing with (optionally) encrypted images:

- Only the payload is encrypted (header, TLVs are plain text)
- Hashing and signing are applied over the un-encrypted data
- Uses AES-CTR-128 or AES-CTR-256 for encryption
- Encryption key randomized every encryption cycle (via `imgtool`)
• The \texttt{AES-CTR} key is included in the image and can be encrypted using:
  
  – \texttt{RSA-OAEP}
  – \texttt{AES-KW} (128 or 256 bits depending on the \texttt{AES-CTR} key length)
  – \texttt{ECIES-P256}
  – \texttt{ECIES-X25519}

Key config properties to control secure boot in Zephyr are:

• \texttt{CONFIG_TFM_BL2} toggles the bootloader (default = \texttt{y}).
• \texttt{CONFIG_TFM_KEY_FILE_S} overrides the secure signing key.
• \texttt{CONFIG_TFM_KEY_FILE_NS} overrides the non-secure signing key.

\textbf{Secure Processing Environment}  Once the secure bootloader has finished executing, a TF-M based secure image will begin execution in the \textit{secure processing environment}. This is where our device will be initially configured, and any secure services will be initialised.

Note that the starting state of our device is controlled by the secure firmware, meaning that when the non-secure Zephyr application starts, peripherals may not be in the HW-default reset state. In case of doubts, be sure to consult the board support packages in TF-M, available in the \texttt{platform/ext/target/} folder of the TF-M module (which is in \texttt{modules/tee/tf-m/trusted-firmware-m/} within a default Zephyr west workspace.)

\textbf{Secure Services}  As of TF-M 1.4.1, the following secure services are generally available (although vendor support may vary):

• Audit Logging (Audit)
• Crypto (Crypto)
• Firmware Update (FWU)
• Initial Attestation (IAS)
• Platform (Platform)
• Secure Storage, which has two parts:
  – Internal Trusted Storage (ITS)
  – Protected Storage (PS)

A template also exists for creating your own custom services.

For full details on these services, and their exposed APIs, please consult the \texttt{TF-M Documentation}.

\textbf{Key Management and Derivation}  Key and secret management is a critical part of any secure device. You need to ensure that key material is available to regions that require it, but not to anything else, and that it is stored securely in a way that makes it difficult to tamper with or maliciously access.

The \texttt{Internal Trusted Storage} service in TF-M is used by the \texttt{PSA Crypto} service (which itself makes use of mbedtls) to store keys, and ensure that private keys are only ever accessible to the secure processing environment. Crypto operations that make use of key material, such as when signing payloads or when decrypting sensitive data, all take place via key handles. At no point should the key material ever be exposed to the NS environment.

One exception is that private keys can be provisioned into the secure processing environment as a one-way operation, such as during a factory provisioning process, but even this should be avoided where possible, and a request should be made to the SPE (via the PSA Crypto service) to generate a new private key itself, and the public key for that can be requested during provisioning and logged in the factory. This ensures the private key material is never exposed, or even known during the provisioning phase.
TF-M also makes extensive use of the **Hardware Unique Key (HUK)**, which every TF-M device must provide. This device-unique key is used by the **Protected Storage** service, for example, to encrypt information stored in external memory. For example, this ensures that the contents of flash memory can’t be decrypted if they are removed and placed on a new device, since each device has its own unique HUK used while encrypting the memory contents the first time.

HUKs provide an additional advantage for developers, in that they can be used to derive new keys, and the **derived keys** don’t need to be stored since they can be regenerated from the HUK at startup, using an additional salt/seed value (depending on the key derivation algorithm used). This removes the storage issue and a frequent attack vector. The HUK itself is usually highly protected in secure devices, and inaccessible directly by users.

**TFM_CRYPTO_ALG_HUK_DERIVATION** identifies the default key derivation algorithm used if a software implementation is used. The current default algorithm is **HKDF (RFC 5869)** with a SHA-256 hash. Other hardware implementations may be available on some platforms.

### Non-Secure Processing Environment

Zephyr is used for the NSPE, using a board that is supported by TF-M where the `CONFIG_BUILD_WITH_TFM` flag has been enabled.

Generally, you simply need to select the `*_ns` variant of a valid target (for example `mps2_an521_ns`), which will configure your Zephyr application to run in the NSPE, correctly build and link it with the TF-M secure images, sign the secure and non-secure images, and merge the three binaries into a single `tfm_merged.hex` file. The `west flash` command will flash `tfm_merged.hex` by default in this configuration.

At present, Zephyr can not be configured to be used as the secure processing environment.

### 4.19.2 TF-M Requirements

The following are some of the boards that can be used with TF-M:

<table>
<thead>
<tr>
<th>Board</th>
<th>NSPE board name</th>
</tr>
</thead>
<tbody>
<tr>
<td>mps2_an521_board</td>
<td>mps2_an521_ns (qemu supported)</td>
</tr>
<tr>
<td>mps3_an547_board</td>
<td>mps3_an547_ns (qemu supported)</td>
</tr>
<tr>
<td>bl5340_dvk</td>
<td>bl5340_dvk_cpuapp_ns</td>
</tr>
<tr>
<td>lpcxpresso55s69</td>
<td>lpcxpresso55s69_ns</td>
</tr>
<tr>
<td>nrf9160dk_nrf9160</td>
<td>nrf9160dk_nrf9160_ns</td>
</tr>
<tr>
<td>nrf5340dk_nrf5340</td>
<td>nrf5340dk_nrf5340_cpuapp_ns</td>
</tr>
<tr>
<td>b_u585i_iot02a_board</td>
<td>b_u585i_iot02a_ns</td>
</tr>
<tr>
<td>nucleo_l552ze_q_board</td>
<td>nucleo_l552ze_q_ns</td>
</tr>
<tr>
<td>stm32l562e_dk_board</td>
<td>stm32l562e_dk_ns</td>
</tr>
<tr>
<td>v2m_musca_b1_board</td>
<td>v2m_musca_b1_ns</td>
</tr>
<tr>
<td>v2m_musca_s1_board</td>
<td>v2m_musca_s1_ns</td>
</tr>
</tbody>
</table>

You can run `west boards -n _ns$` to search for non-secure variants of different board targets. To make sure TF-M is supported for a board in its output, check that `CONFIG_TRUSTED_EXECUTION_NONSECURE` is set to `y` in that board's default configuration.

### Software Requirements

The following Python modules are required when building TF-M binaries:

- cryptography
- pyasn1
- pyyaml
• cbor>=1.0.0
• imgtool>=1.9.0
• jinja2
• click

You can install them via:

```bash
$ pip3 install --user cryptography pyasn1 pycrypto cbor>=1.0.0 imgtool>=1.9.0
   jinja2 click
```

They are used by TF-M's signing utility to prepare firmware images for validation by the bootloader.

Part of the process of generating binaries for QEMU and merging signed secure and non-secure binaries on certain platforms also requires the use of the `srec_cat` utility.

This can be installed on Linux via:

```bash
$ sudo apt-get install srec
```

And on OS X via:

```bash
$ brew install srec
```

For Windows-based systems, please make sure you have a copy of the utility available on your system path. See, for example: SRecord for Windows

### 4.19.3 TF-M Build System

When building a valid `_ns` board target, TF-M will be built in the background, and linked with the Zephyr non-secure application. No knowledge of TF-M's build system is required in most cases, and the following will build a TF-M and Zephyr image pair, and run it in qemu with no additional steps required:

```bash
$ west build -p auto -t mps2_an521_ns samples/tfm_integration/psa_crypto/ -
   \t run
```

The outputs and certain key steps in this build process are described here, however, since you will need to understand and interact with the outputs, and deal with signing the secure and non-secure images before deploying them.

### Images Created by the TF-M Build

The TF-M build system creates the following executable files:

- `tfm_s` - TF-M secure firmware
- `tfm_ns` - TF-M non-secure app (only used by regression tests).
- `bl2` - TF-M MCUboot, if enabled

For each of these, it creates `.bin`, `.hex`, `.elf`, and `.axf` files.

The TF-M build system also creates signed variants of `tfm_s` and `tfm_ns`, and a file which combines them:

- `tfm_s_signed`
- `tfm_ns_signed`
- `tfm_s_ns_signed`
For each of these, only .bin files are created.

The TF-M non-secure app is discarded in favor of Zephyr non-secure app except when running the TF-M regression test suite.

The Zephyr build system usually signs both tfm_s and the Zephyr non-secure app itself. See below for details.

The 'tfm' target contains properties for all these paths. For example, the following will resolve to <path>/tfm_s.hex:

```
$<TARGET_PROPERTY:tfm,TFM_S_HEX_FILE>
```

See the top level CMakeLists.txt file in the tfm module for an overview of all the properties.

**Signing Images**

When CONFIG_TFM_BL2 is set to y, TF-M uses a secure bootloader (BL2) and firmware images must be signed with a private key. The firmware image is validated by the bootloader during updates using the corresponding public key, which is stored inside the secure bootloader firmware image.

By default, <tfm-dir>/b12/ext/mcuboot/root-rsa-3072.pem is used to sign secure images, and <tfm-dir>/b12/ext/mcuboot/root-rsa-3072_1.pem is used to sign non-secure images. These default .pem keys can (and should) be overridden using the CONFIG_TFM_KEY_FILE_S and CONFIG_TFM_KEY_FILE_NS config flags.

To satisfy PSA Certified Level 1 requirements, **You MUST replace the default .pem file with a new key pair!**

To generate a new public/private key pair, run the following commands:

```
$ imgtool keygen -k root-rsa-3072_s.pem -t rsa-3072
$ imgtool keygen -k root-rsa-3072_ns.pem -t rsa-3072
```

You can then place the new .pem files in an alternate location, such as your Zephyr application folder, and reference them in the prj.conf file via the CONFIG_TFM_KEY_FILE_S and CONFIG_TFM_KEY_FILE_NS config flags.

**Warning:** Be sure to keep your private key file in a safe, reliable location! If you lose this key file, you will be unable to sign any future firmware images, and it will no longer be possible to update your devices in the field!

After the built-in signing script has run, it creates a tfm_merged.hex file that contains all three binaries: bl2, tfm_s, and the zephyr app. This hex file can then be flashed to your development board or run in QEMU.

**Custom CMake arguments** When building a Zephyr application with TF-M it might be necessary to control the CMake arguments passed to the TF-M build.

Zephyr TF-M build offers several Kconfig options for controlling the build, but doesn't cover every CMake argument supported by the TF-M build system.

The TFM_CMAKE_OPTIONS property on the zephyr_property_target can be used to pass custom CMake arguments to the TF-M build system.

To pass the CMake argument -DFOO=bar to the TF-M build system, place the following CMake snippet in your CMakeLists.txt file.
```cpp
set_property(TARGET zephyr_property_target
    APPEND PROPERTY TFM_CMAKE_OPTIONS
    -DFOO=bar)
```

**Note:** The `TFM_CMAKE_OPTIONS` is a list so it is possible to append multiple options. Also CMake generator expressions are supported, such as `$<1:-DFOO=bar>`

---

**Footprint and Memory Usage**

The build system offers targets to view and analyse RAM and ROM usage in generated images. The tools run on the final images and give information about size of symbols and code being used in both RAM and ROM. For more information on these tools look here: Footprint and Memory Usage

Use the `tfm_ram_report` to get the RAM report for TF-M secure firmware (tfm_s).

**Using west:**

```
west build -b mps2_an521_ns samples/hello_world
west build -t tfm_ram_report
```

**Using CMake and ninja:**

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world

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

Use the `tfm_rom_report` to get the ROM report for TF-M secure firmware (tfm_s).

**Using west:**

```
west build -b mps2_an521_ns samples/hello_world
west build -t tfm_rom_report
```

**Using CMake and ninja:**

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world

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

Use the `bl2_ram_report` to get the RAM report for TF-M MCUboot, if enabled.

**Using west:**

```
west build -b mps2_an521_ns samples/hello_world
west build -t bl2_ram_report
```

**Using CMake and ninja:**

```
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world

# Now run ninja on the generated build system:
ninja -Cbuild bl2_ram_report
```
Use the `bl2_rom_report` to get the ROM report for TF-M MCUboot, if enabled.

Using west:

```bash
west build -b mps2_an521_ns samples/hello_world
west build -t bl2_rom_report
```

Using CMake and ninja:

```bash
# Use cmake to configure a Ninja-based buildsystem:
cmake -Bbuild -GNinja -DBOARD=mps2_an521_ns samples/hello_world

# Now run ninja on the generated build system:
ninja -Cbuild bl2_rom_report
```

### 4.19.4 Trusted Firmware-M Integration

The Trusted Firmware-M (TF-M) section contains information about the integration between TF-M and Zephyr RTOS. Use this information to help understand how to integrate TF-M with Zephyr for Cortex-M platforms and make use of its secure run-time services in Zephyr applications.

#### Board Definitions

TF-M will be built for the secure processing environment along with Zephyr if the `CONFIG_BUILD_WITH_TFM` flag is set to `y`.

Generally, this value should never be set at the application level, however, and all config flags required for TF-M should be set in a board variant with the `_ns` suffix.

This board variant must define an appropriate flash, SRAM and peripheral configuration that takes into account the initialisation process in the secure processing environment. `CONFIG_TFM_BOARD` must also be set via `modules/trusted-firmware-m/Kconfig.tfm` to the board name that TF-M expects for this target, so that it knows which target to build for the secure processing environment.

**Example**: `mps2_an521_ns` The `mps2_an521` target is a dual-core Arm Cortex-M33 evaluation board that, when using the default board variant, would generate a secure Zephyr binary.

The optional `mps2_an521_ns` target, however, sets these additional kconfig flags that indicate that Zephyr should be built as a non-secure image, linked with TF-M as an external project, and optionally the secure bootloader:

- `CONFIG_TRUSTED_EXECUTION_NONSECURE y`
- `CONFIG_ARM_TRUSTZONE_M y`

Comparing the `mps2_an521.dts` and `mps2_an521_ns.dts` files, we can see that the `_ns` version defines offsets in flash and SRAM memory, which leave the required space for TF-M and the secure bootloader:

```plaintext
reserved-memory {
    #address-cells = <1>;
    #size-cells = <1>;
    ranges;

    /* The memory regions defined below must match what the TF-M
    * project has defined for that board - a single image boot is
    * assumed. Please see the memory layout in:
    * https://git.trustedfirmware.org/TF-M/trusted-firmware-m.git/tree/
    * platform/ext/target/mps2/an521/partition/flash_layout.h
    */
}
```

(continues on next page)
This reserves 1 MB of code memory and 1 MB of RAM for secure boot and TF-M, such that our non-secure Zephyr application code will start at 0x10000, with RAM at 0x28100000. 512 KB code memory is available for the NS zephyr image, along with 1 MB of RAM. This matches the flash memory layout we see in flash_layout.h in TF-M:

- 0x0000_0000 BL2 – MCUBoot (0.5 MB)
- 0x0008_0000 Secure image primary slot (0.5 MB)
- 0x0010_0000 Non-secure image primary slot (0.5 MB)
- 0x0018_0000 Secure image secondary slot (0.5 MB)
- 0x0020_0000 Non-secure image secondary slot (0.5 MB)
- 0x0020_0000 Scratch area (0.5 MB)
- 0x0030_0000 Protected Storage Area (20 KB)
- 0x0030_5000 Internal Trusted Storage Area (16 KB)
- 0x0030_9000 NV counters area (4 KB)
- 0x0030_A000 Unused (984 KB)

mps2/an521 will be passed in to Tf-M as the board target, specified via CONFIG_TFM_BOARD.

### 4.19.5 Test Suites

TF-M includes two sets of test suites:

- tf-m-tests - Standard TF-M specific regression tests
- psa-arch-tests - Test suites for specific PSA APIs (secure storage, etc.)

These test suites can be run from Zephyr via an appropriate sample application in the samples/tfm_integration folder.

#### TF-M Regression Tests

The regression test suite can be run via the tfm_regression_test sample. This sample tests various services and communication mechanisms across the NS/S boundary via the PSA APIs. They provide a useful sanity check for proper integration between the NS RTOS (Zephyr in this case) and the secure application (TF-M).

#### PSA Arch Tests

The PSA Arch Test suite, available via tfm_psa_test, contains a number of test suites that can be used to validate that PSA API specifications are being followed by the secure application, TF-M being an implementation of the Platform Security Architecture (PSA).

Only one of these suites can be run at a time, with the available test suites described via CONFIG_TFM_PSA_TEST_* KConfig flags:
Purpose

The output of these test suites is required to obtain PSA Certification for your specific board, RTOS (Zephyr here), and PSA implementation (TF-M in this case).

They also provide a useful test case to validate any PRs that make meaningful changes to TF-M, such as enabling a new TF-M board target, or making changes to the core TF-M module(s). They should generally be run as a coherence check before publishing a new PR for new board support, etc.

4.20 USB device support

4.20.1 USB device controller driver

The USB Device Controller Driver Layer implements the low level control routines to deal directly with the hardware. All device controller drivers should implement the APIs described in include/zephyr/drivers/usb/usb_dc.h. This allows the integration of new USB device controllers to be done without changing the upper layers. With this API it is not possible to support more than one controller instance at runtime.

API reference

`group _usb_device_controller_api`

USB Device Controller API.

**Typedefs**

typedef void (*`usb_dc_ep_callback`)(uint8_t ep, enum `usb_dc_ep_cb_status_code` cb_status)

Callback function signature for the USB Endpoint status

typedef void (*`usb_dc_status_callback`)(enum `usb_dc_status_code` cb_status, const uint8_t *param)

Callback function signature for the device

**Enums**

enum `usb_dc_status_code`

USB Driver Status Codes.

Status codes reported by the registered device status callback.

*Values:*

- `USB_DC_ERROR` USB error reported by the controller
- `USB_DC_RESET` USB reset
enumerator USB_DC_CONNECTED
    USB connection established, hardware enumeration is completed

enumerator USB_DC_CONFIGURED
    USB configuration done

enumerator USB_DC_DISCONNECTED
    USB connection lost

enumerator USB_DC_SUSPEND
    USB connection suspended by the HOST

enumerator USB_DC_RESUME
    USB connection resumed by the HOST

enumerator USB_DC_INTERFACE
    USB interface selected

enumerator USB_DC_SET_HALT
    Set Feature ENDPOINT_HALT received

enumerator USB_DC_CLEAR_HALT
    Clear Feature ENDPOINT_HALT received

enumerator USB_DC_SOF
    Start of Frame received

enumerator USB_DC_UNKNOWN
    Initial USB connection status

enum usb_dc_ep_cb_status_code
    USB Endpoint Callback Status Codes.
    Status Codes reported by the registered endpoint callback.
    Values:

enumerator USB_DC_EP_SETUP
    SETUP received

enumerator USB_DC_EP_DATA_OUT
    Out transaction on this EP, data is available for read

enumerator USB_DC_EP_DATA_IN
    In transaction done on this EP

enum usb_dc_ep_transfer_type
    USB Endpoint Transfer Type.
    Values:
enumerator USB_DC_EP_CONTROL = 0
    Control type endpoint

eenumerator USB_DC_EP_ISOCHRONOUS
    Isochronous type endpoint

eenumerator USB_DC_EP_BULK
    Bulk type endpoint

eenumerator USB_DC_EP_INTERRUPT
    Interrupt type endpoint

enum usb_dc_ep_synchronization_type
    USB Endpoint Synchronization Type.

    Note: Valid only for Isochronous Endpoints

    Values:

eenumerator USB_DC_EP_NO_SYNCHRONIZATION = (0U << 2U)
    No Synchronization

eenumerator USB_DC_EPASYNCHRONOUS = (1U << 2U)
    Asynchronous

eenumerator USB_DC_EP_ADAPTIVE = (2U << 2U)
    Adaptive

eenumerator USB_DC_EP_SYNCHRONOUS = (3U << 2U)
    Synchronous

Functions

int usb_dc_attach(void)
    Attach USB for device connection.
    Function to attach USB for device connection. Upon success, the USB PLL is enabled, and the
    USB device is now capable of transmitting and receiving on the USB bus and of generating
    interrupts.

    Returns
    0 on success, negative errno code on fail.

int usb_dc_detach(void)
    Detach the USB device.
    Function to detach the USB device. Upon success, the USB hardware PLL is powered down
    and USB communication is disabled.

    Returns
    0 on success, negative errno code on fail.
int usb_dc_reset(void)
    Reset the USB device.

This function returns the USB device and firmware back to its initial state. N.B. the USB PLL
is handled by the usb_detach function

Returns
    0 on success, negative errno code on fail.

int usb_dc_set_address(const uint8_t addr)
    Set USB device address.

Parameters
    • addr – [in] Device address

Returns
    0 on success, negative errno code on fail.

void usb_dc_set_status_callback(const usb_dc_status_callback cb)
    Set USB device controller status callback.

Function to set USB device controller status callback. The registered callback is used to re-
port changes in the status of the device controller. The status code are described by the
usb_dc_status_code enumeration.

Parameters
    • cb – [in] Callback function

int usb_dc_ep_check_cap(const struct usb_dc_ep_cfg_data *const cfg)
    check endpoint capabilities

Function to check capabilities of an endpoint. usb_dc_ep_cfg_data structure provides the end-
point configuration parameters: endpoint address, endpoint maximum packet size and end-
point type. The driver should check endpoint capabilities and return 0 if the endpoint config-
uration is possible.

Parameters
    • cfg – [in] Endpoint config

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_configure(const struct usb_dc_ep_cfg_data *const cfg)
    Configure endpoint.

Function to configure an endpoint. usb_dc_ep_cfg_data structure provides the endpoint con-
figuration parameters: endpoint address, endpoint maximum packet size and endpoint type.

Parameters
    • cfg – [in] Endpoint config

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_set_stall(const uint8_t ep)
    Set stall condition for the selected endpoint.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device con-
figuration table

Returns
    0 on success, negative errno code on fail.
int usb_dc_ep_clear_stall(const uint8_t ep)
    Clear stall condition for the selected endpoint.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_is_stalled(const uint8_t ep, uint8_t *const stalled)
    Check if the selected endpoint is stalled.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device configuration table
    • stalled – [out] Endpoint stall status

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_halt(const uint8_t ep)
    Halt the selected endpoint.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_enable(const uint8_t ep)
    Enable the selected endpoint. Upon success interrupts are enabled for the corresponding endpoint and the endpoint is ready for transmitting/receiving data.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_disable(const uint8_t ep)
    Disable the selected endpoint. Upon success interrupts are disabled for the corresponding endpoint and the endpoint is no longer able for transmitting/receiving data.

Parameters
    • ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
    0 on success, negative errno code on fail.

int usb_dc_ep_flush(const uint8_t ep)
    Flush the selected endpoint.

This function flushes the FIFOs for the selected endpoint.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_write(const uint8_t *ep, const uint8_t *data, const uint32_t data_len, uint32_t *ret_bytes)

Write data to the specified endpoint.

This function is called to write data to the specified endpoint. The supplied usb_ep_callback function will be called when data is transmitted out.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• data – [in] Pointer to data to write
• data_len – [in] Length of the data requested to write. This may be zero for a zero length status packet.
• ret_bytes – [out] Bytes scheduled for transmission. This value may be NULL if the application expects all bytes to be written

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_read(const uint8_t *ep, uint8_t *data, const uint32_t max_data_len, uint32_t *read_bytes)

Read data from the specified endpoint.

This function is called by the endpoint handler function, after an OUT interrupt has been received for that EP. The application must only call this function through the supplied usb_ep_callback function. This function clears the ENDPOINT NAK, if all data in the endpoint FIFO has been read, so as to accept more data from host.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• data – [in] Pointer to data buffer to write to
• max_data_len – [in] Max length of data to read
• read_bytes – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read should be returned.

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_set_callback(const uint8_t *ep, const usb_dc_ep_callback cb)

Set callback function for the specified endpoint.

Function to set callback function for notification of data received and available to application or transmit done on the selected endpoint, NULL if callback not required by application code. The callback status code is described by usb_dc_ep_cb_status_code.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• cb – [in] Callback function

Returns
0 on success, negative errno code on fail.
int usb_dc_ep_read_wait(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *read_bytes)
Read data from the specified endpoint.
This is similar to usb_dc_ep_read, the difference being that, it doesn't clear the endpoint NAKs so that the consumer is not bogged down by further upcalls till he is done with the processing of the data. The caller should reactivate ep by invoking usb_dc_ep_read_continue() do so.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• data – [in] Pointer to data buffer to write to
• max_data_len – [in] Max length of data to read
• read_bytes – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read should be returned.

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_read_continue(uint8_t ep)
Continue reading data from the endpoint.
Clear the endpoint NAK and enable the endpoint to accept more data from the host. Usually called after usb_dc_ep_read_wait() when the consumer is fine to accept more data. Thus these calls together act as a flow control mechanism.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

int usb_dc_ep_mps(uint8_t ep)
Get endpoint max packet size.

Parameters
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
Endpoint max packet size (mps)

int usb_dc_wakeup_request(void)
Start the host wake up procedure.
Function to wake up the host if it’s currently in sleep mode.

Returns
0 on success, negative errno code on fail.

struct usb_dc_ep_cfg_data
#include <usb_dc.h> USB Endpoint Configuration.
Structure containing the USB endpoint configuration.

Public Members
4.20.2 USB device stack

The USB device stack is a hardware independent interface between USB device controller driver and USB device class drivers or customer applications. It is a port of the LPCUSB device stack and has been modified and expanded over time. It provides the following functionalities:

- Uses the APIs provided by the device controller drivers to interact with the USB device controller.
- Responds to standard device requests and returns standard descriptors, essentially handling 'Chapter 9' processing, specifically the standard device requests in table 9-3 from the universal serial bus specification revision 2.0.
- Provides a programming interface to be used by USB device classes or customer applications. The APIs is described in include/zephyr/usb/usb_device.h

The device stack has few limitations with which it is not possible to support more than one controller instance at runtime, and only one USB device configuration is supported.

Supported USB classes:

- USB Audio (experimental)
- USB CDC ACM
- USB CDC ECM
- USB CDC EEM
- RNDIS
- USB MSC
- USB DFU
- Bluetooth HCI over USB
- USB HID class

List of samples for different purposes. CDC ACM and HID samples have configuration overlays for composite configuration.

Implementing a non-standard USB class

The configuration of USB Device is done in the stack layer.

The following structures and callbacks need to be defined:

- Part of USB Descriptor table
- USB Endpoint configuration table
- USB Device configuration structure
- Endpoint callbacks
* Optionally class, vendor and custom handlers

For example, for the USB loopback application:

```c
struct usb_loopback_config {
    struct usb_if_descriptor if0;
    struct usb_ep_descriptor if0_out_ep;
    struct usb_ep_descriptor if0_in_ep;
} __packed;

USBD_CLASS_DESCR_DEFINE(primary, 0) struct usb_loopback_config loopback_cfg = {
    /* Interface descriptor 0 */
    .if0 = {
        .bLength = sizeof(struct usb_if_descriptor),
        .bDescriptorType = USB_DESC_INTERFACE,
        .bInterfaceNumber = 0,
        .bAlternateSetting = 0,
        .bNumEndpoints = 2,
        .bInterfaceClass = USB_BCC_VENDOR,
        .bInterfaceSubClass = 0,
        .bInterfaceProtocol = 0,
        .iInterface = 0,
    },

    /* Data Endpoint OUT */
    .if0_out_ep = {
        .bLength = sizeof(struct usb_ep_descriptor),
        .bDescriptorType = USB_DESC_ENDPOINT,
        .bEndpointAddress = LOOPBACK_OUT_EP_ADDR,
        .bmAttributes = USB_DC_EP_BULK,
        .wMaxPacketSize = sys_cpu_to_le16(CONFIG_LOOPBACK_BULK_EP_MPS),
        .bInterval = 0x00,
    },

    /* Data Endpoint IN */
    .if0_in_ep = {
        .bLength = sizeof(struct usb_ep_descriptor),
        .bDescriptorType = USB_DESC_ENDPOINT,
        .bEndpointAddress = LOOPBACK_IN_EP_ADDR,
        .bmAttributes = USB_DC_EP_BULK,
        .wMaxPacketSize = sys_cpu_to_le16(CONFIG_LOOPBACK_BULK_EP_MPS),
        .bInterval = 0x00,
    },
};
```

Endpoint configuration:

```c
static struct usb_ep_cfg_data ep_cfg[] = {
    { .ep_cb = loopback_out_cb, .ep_addr = LOOPBACK_OUT_EP_ADDR, },
    { .ep_cb = loopback_in_cb, .ep_addr = LOOPBACK_IN_EP_ADDR, }
};
```

USB Device configuration structure:
USBD_DEFINE_CFG_DATA(loopback_config) = {
    .usb_device_description = NULL,
    .interface_config = loopback_interface_config,
    .interface_descriptor = &loopback_cfg.if0,
    .cb_usb_status = loopback_status_cb,
    .interface = {
        .class_handler = NULL,
        .custom_handler = NULL,
        .vendor_handler = loopback_vendor_handler,
    },
    .num_endpoints = ARRAY_SIZE(ep_cfg),
    .endpoint = ep_cfg,
};

The vendor device requests are forwarded by the USB stack core driver to the class driver through the registered vendor handler.

For the loopback class driver, loopback_vendor_handler() processes the vendor requests:

```c
static int loopback_vendor_handler(struct usb_setup_packet *setup,
    int32_t *len, uint8_t **data)
{
    LOG_DBG("Class request: bRequest 0x%x bmRequestType 0x%x len %d",
        setup->bRequest, setup->bmRequestType, *len);

    if (setup->RequestType.recipient != USB_REQTYPE_RECIPIENT_DEVICE) {
        return -ENOTSUP;
    }

    if (usb_reqtype_is_to_device(setup) &&
        setup->bRequest == 0x5b) {
        LOG_DBG("Host-to-Device, data %p", *data);
        /*
         * Copy request data in loopback_buf buffer and reuse it later in control device-to-host transfer.
         * /
         * memcpy(loopback_buf, *data,
         * MIN(sizeof(loopback_buf), setup->wLength));
         * return 0;
     }

    if ((usb_reqtype_is_to_host(setup)) &&
        (setup->bRequest == 0x5c)) {
        LOG_DBG("Device-to-Host, wLength %d, data %p",
            setup->wLength, *data);
        *data = loopback_buf;
        *len = MIN(sizeof(loopback_buf), setup->wLength);
        return 0;
    }

    return -ENOTSUP;
}
```

The class driver waits for the USB_DC_CONFIGURED device status code before transmitting any data.
USB Vendor and Product identifiers

The USB Vendor ID for the Zephyr project is 0x2FE3. This USB Vendor ID must not be used when a vendor integrates Zephyr USB device support into its own product.

Each USB sample has its own unique Product ID. The USB maintainer, if one is assigned, or otherwise the Zephyr Technical Steering Committee, may allocate other USB Product IDs based on well-motivated and documented requests.

The following Product IDs are currently used:

<table>
<thead>
<tr>
<th>Sample</th>
<th>PID</th>
</tr>
</thead>
<tbody>
<tr>
<td>usb_cdc-acm</td>
<td>0x0001</td>
</tr>
<tr>
<td>usb_cdc-acm_composite</td>
<td>0x0002</td>
</tr>
<tr>
<td>usb_hid-cdc</td>
<td>0x0003</td>
</tr>
<tr>
<td>cdc-acm-console</td>
<td>0x0004</td>
</tr>
<tr>
<td>usb_dfu</td>
<td>0x0005</td>
</tr>
<tr>
<td>usb_hid</td>
<td>0x0006</td>
</tr>
<tr>
<td>usb_hid-mouse</td>
<td>0x0007</td>
</tr>
<tr>
<td>usb_mass</td>
<td>0x0008</td>
</tr>
<tr>
<td>testusb-app</td>
<td>0x0009</td>
</tr>
<tr>
<td>webusb-sample</td>
<td>0x000A</td>
</tr>
<tr>
<td>bluetooth-hci-usb-sample</td>
<td>0x000B</td>
</tr>
<tr>
<td>bluetooth-hci-usb-h4-sample</td>
<td>0x000C</td>
</tr>
<tr>
<td>wpanusb-sample</td>
<td>0x000D</td>
</tr>
</tbody>
</table>

The USB device descriptor field bcdDevice (Device Release Number) represents the Zephyr kernel major and minor versions as a binary coded decimal value.

API reference

There are two ways to transmit data, using the ‘low’ level read/write API or the ‘high’ level transfer API.

Low level API

To transmit data to the host, the class driver should call usb_write(). Upon completion the registered endpoint callback will be called. Before sending another packet the class driver should wait for the completion of the previous write. When data is received, the registered endpoint callback is called. usb_read() should be used for retrieving the received data. For CDC ACM sample driver this happens via the OUT bulk endpoint handler (cdc_acm_bulk_out) mentioned in the endpoint array (cdc_acm_ep_data).

High level API

The usb_transfer method can be used to transfer data to/from the host. The transfer API will automatically split the data transmission into one or more USB transaction(s), depending endpoint max packet size. The class driver does not have to implement endpoint callback and should set this callback to the generic usb_transfer_ep_callback.

group _usb_device_core_api

USB Device Core Layer API.

Defines

USB_TRANS_READ

USB_TRANS_WRITE
typedef void (*usb_ep_callback)(uint8_t ep, enum usb_dc_ep_cb_status_code cb_status)
    Callback function signature for the USB Endpoint status.

typedef int (*usb_request_handler)(struct usb_setup_packet *setup, int32_t *transfer_len, uint8_t **payload_data)
    Callback function signature for class specific requests.

    Function which handles Class specific requests corresponding to an interface number specified in the device descriptor table. For host to device direction the 'len' and 'payload_data' contain the length of the received data and the pointer to the received data respectively. For device to host class requests, 'len' and 'payload_data' should be set by the callback function with the length and the address of the data to be transmitted buffer respectively.

typedef void (*usb_interface_config)(struct usb_desc_header *head, uint8_t bInterfaceNumber)
    Function for interface runtime configuration.

typedef void (*usb_transfer_callback)(uint8_t ep, int tsize, void *priv)
    Callback function signature for transfer completion.

Functions

int usb_set_config(const uint8_t *usb_descriptor)
Configure USB controller.

    Function to configure USB controller. Configuration parameters must be valid or an error is returned

    Parameters
    • usb_descriptor – [in] USB descriptor table

    Returns
    0 on success, negative errno code on fail

int usb_deconfig(void)
Deconfigure USB controller.

    This function returns the USB device to it's initial state

    Returns
    0 on success, negative errno code on fail

int usb_enable(usb_dc_status_callback status_cb)
Enable the USB subsystem and associated hardware.

    This function initializes the USB core subsystem and enables the corresponding hardware so that it can begin transmitting and receiving on the USB bus, as well as generating interrupts. Class-specific initialization and registration must be performed by the user before invoking this, so that any data or events on the bus are processed correctly by the associated class handling code.

    Parameters
• status_cb – [in] Callback registered by user to notify about USB device controller state.

**Returns**
0 on success, negative errno code on fail.

```c
int usb_disable(void)
```

Disable the USB device.

Function to disable the USB device. Upon success, the specified USB interface is clock gated in hardware, it is no longer capable of generating interrupts.

**Returns**
0 on success, negative errno code on fail

```c
int usb_write(uint8_t ep, const uint8_t *data, uint32_t data_len, uint32_t *bytes_ret)
```

Write data to the specified endpoint.

Function to write data to the specified endpoint. The supplied usb_ep_callback will be called when transmission is done.

**Parameters**
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• data – [in] Pointer to data to write
• data_len – [in] Length of data requested to write. This may be zero for a zero length status packet.
• bytes_ret – [out] Bytes written to the EP FIFO. This value may be NULL if the application expects all bytes to be written

**Returns**
0 on success, negative errno code on fail

```c
int usb_read(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *ret_bytes)
```

Read data from the specified endpoint.

This function is called by the Endpoint handler function, after an OUT interrupt has been received for that EP. The application must only call this function through the supplied usb_ep_callback function.

**Parameters**
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
• data – [in] Pointer to data buffer to write to
• max_data_len – [in] Max length of data to read
• ret_bytes – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read is returned.

**Returns**
0 on success, negative errno code on fail

```c
int usb_ep_set_stall(uint8_t ep)
```

Set STALL condition on the specified endpoint.

This function is called by USB device class handler code to set stall condition on endpoint.

**Parameters**
• ep – [in] Endpoint address corresponding to the one listed in the device configuration table
Returns
0 on success, negative errno code on fail

int usb_ep_clear_stall(uint8_t ep)
Clears STALL condition on the specified endpoint.
This function is called by USB device class handler code to clear stall condition on endpoint.

Parameters
* ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail

int usb_ep_read_wait(uint8_t ep, uint8_t *data, uint32_t max_data_len, uint32_t *read_bytes)
Read data from the specified endpoint.
This is similar to usb_ep_read, the difference being that, it doesn’t clear the endpoint NAKs so that the consumer is not bogged down by further upcalls till he is done with the processing of the data. The caller should reactivate ep by invoking usb_ep_read_continue() do so.

Parameters
* ep – [in] Endpoint address corresponding to the one listed in the device configuration table
* data – [in] pointer to data buffer to write to
* max_data_len – [in] max length of data to read
* read_bytes – [out] Number of bytes read. If data is NULL and max_data_len is 0 the number of bytes available for read should be returned.

Returns
0 on success, negative errno code on fail.

int usb_ep_read_continue(uint8_t ep)
Continue reading data from the endpoint.
Clear the endpoint NAK and enable the endpoint to accept more data from the host. Usually called after usb_ep_read_wait() when the consumer is fine to accept more data. Thus these calls together acts as flow control mechanism.

Parameters
* ep – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
0 on success, negative errno code on fail.

void usb_transfer_ep_callback(uint8_t ep, enum usb_dc_ep_cb_status_code)
Transfer management endpoint callback.
If a USB class driver wants to use high-level transfer functions, driver needs to register this callback as usb endpoint callback.

int usb_transfer(uint8_t ep, uint8_t *data, size_t dlen, unsigned int flags, usb_transfer_callback cb, void *priv)
Start a transfer.
Start a usb transfer to/from the data buffer. This function is asynchronous and can be executed in IRQ context. The provided callback will be called on transfer completion (or error) in thread context.

Parameters
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
• **data** – [in] Pointer to data buffer to write-to/read-from
• **dlen** – [in] Size of data buffer
• **flags** – [in] Transfer flags (USB_TRANS_READ, USB_TRANS_WRITE…)
• **cb** – [in] Function called on transfer completion/failure
• **priv** – [in] Data passed back to the transfer completion callback

Returns
0 on success, negative errno code on fail.

```c
int usb_transfer_sync(uint8_t ep, uint8_t *data, size_t dlen, unsigned int flags)
```

Start a transfer and block-wait for completion.

Synchronous version of `usb_transfer`, wait for transfer completion before returning.

Parameters
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table
• **data** – [in] Pointer to data buffer to write-to/read-from
• **dlen** – [in] Size of data buffer
• **flags** – [in] Transfer flags

Returns
number of bytes transferred on success, negative errno code on fail.

```c
void usb_cancel_transfer(uint8_t ep)
```

Cancel any ongoing transfer on the specified endpoint.

Parameters
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

```c
void usb_cancel_transfers(void)
```

Cancel all ongoing transfers.

```c
bool usb_transfer_is_busy(uint8_t ep)
```

Check that transfer is ongoing for the endpoint.

Parameters
• **ep** – [in] Endpoint address corresponding to the one listed in the device configuration table

Returns
ture if transfer is ongoing, false otherwise.

```c
int usb_wakeup_request(void)
```

Start the USB remote wakeup procedure.

Function to request a remote wakeup. This feature must be enabled in configuration, otherwise it will always return -ENOTSUP error.

Returns
0 on success, negative errno code on fail, i.e. when the bus is already active.

```c
bool usb_get_remote_wakeup_status(void)
```

Get status of the USB remote wakeup feature.
Returns
true if remote wakeup has been enabled by the host, false otherwise.

struct usb_ep_cfg_data
#include <usb_device.h> USB Endpoint Configuration.
This structure contains configuration for the endpoint.

Public Members

*usb_ep_callback ep_cb
Callback function for notification of data received and available to application or transmit done, NULL if callback not required by application code

uint8_t ep_addr
The number associated with the EP in the device configuration structure
IN EP = 0x80 | <endpoint number>
OUT EP = 0x00 | <endpoint number>

struct usb_interface_cfg_data
#include <usb_device.h> USB Interface Configuration.
This structure contains USB interface configuration.

Public Members

*usb_request_handler class_handler
Handler for USB Class specific Control (EP 0) communications

*usb_request_handler vendor_handler
Handler for USB Vendor specific commands

*usb_request_handler custom_handler
The custom request handler gets a first chance at handling the request before it is handed over to the 'chapter 9' request handler. return 0 on success, -EINVAL if the request has not been handled by the custom handler and instead needs to be handled by the core USB stack. Any other error code to denote failure within the custom handler.

struct usb_cfg_data
#include <usb_device.h> USB device configuration.
The Application instantiates this with given parameters added using the “usb_set_config” function. Once this function is called changes to this structure will result in undefined behavior. This structure may only be updated after calls to usb_deconfig.

Public Members

const uint8_t *usb_device_description
USB device description, see http://www.beyondlogic.org/usbnutshell/usb5.shtml#DeviceDescriptors
void *interface_descriptor

  Pointer to interface descriptor


usb_interface_config interface_config

  Function for interface runtime configuration

void (*cb_usb_status)(struct usb_cfg_data *cfg, enum usb_dc_status_code cb_status, const uint8_t *param)

  Callback to be notified on USB connection status change

struct usb_interface_cfg_data interface

  USB interface (Class) handler and storage space

uint8_t num_endpoints

  Number of individual endpoints in the device configuration

struct usb_ep_cfg_data *endpoint

  Pointer to an array of endpoint structs of length equal to the number of EP associated with the device description, not including control endpoints

### 4.20.3 Testing USB device support

**Testing over USPIP in native_posix**

A virtual USB controller implemented through USBIP might be used to test the USB Device stack. Follow the general build procedure to build the USB sample for the native_posix configuration.

Run built sample with:

```bash
west build -t run
```

In a terminal window, run the following command to list USB devices:

```bash
$ usbip list -r localhost
Exportable USB devices
========================
- 127.0.0.1
  1-1: unknown vendor : unknown product (2fe3:0100)
    : /sys/devices/pci0000:00/0000:00:01.2/usb1/1-1
    : (Defined at Interface level) (00/00/00)
    : 0 - Vendor Specific Class / unknown subclass / unknown protocol (ff/00/
-00)
```

In a terminal window, run the following command to attach the USB device:

```bash
$ sudo usbip attach -r localhost -b 1-1
```

The USB device should be connected to your Linux host, and verified with the following commands:

```bash
$ sudo usbip port
Imported USB devices
=====================
Port 00: <Port in Use> at Full Speed(12Mbps)
  unknown vendor : unknown product (2fe3:0100)
```

(continues on next page)
4.20.4 USB Human Interface Devices (HID) support

Since the USB HID specification is not only used by the USB subsystem, the USB HID API is split into two header files include/zephyr/usb/class/hid.h and include/zephyr/usb/class/usb_hid.h. The second includes a specific part for HID support in the USB device stack.

HID Item helpers

HID item helper macros can be used to compose a HID Report Descriptor. The names correspond to those used in the USB HID Specification.

Example of a HID Report Descriptor:

```c
static const uint8_t hid_report_desc[] = {
    HID_USAGE_PAGE(HID_USAGE_GEN_DESKTOP),
    HID_USAGE(HID_USAGE_GEN_DESKTOP_UNDEFINED),
    HID_COLLECTION(HID_COLLECTION_APPLICATION),
    HID_LOGICAL_MIN8(0),
    /* logical maximum 255 */
    HID_LOGICAL_MAX16(0xFF, 0x00),
    HID_REPORT_ID(1),
    HID_REPORT_SIZE(8),
    HID_REPORT_COUNT(1),
    HID_USAGE(HID_USAGE_GEN_DESKTOP_UNDEFINED),
    /* HID_INPUT (Data, Variable, Absolute) */
    HID_INPUT(0x02),
    HID_END_COLLECTION,
};
```

HID items reference

```c
group usb_hid_items

Defines

HID_ITEM(bTag, bType, bSize)
Define HID short item.

Parameters

- bTag – Item tag
- bType – Item type
- bSize – Item data size

Returns

HID Input item
```
HID_INPUT(a)
Define HID Input item with the data length of one byte.
For usage examples, see \texttt{HID\_MOUSE\_REPORT\_DESC()}, \texttt{HID\_KEYBOARD\_REPORT\_DESC()}

\textbf{Parameters}
- \texttt{a} – Input item data

\textbf{Returns}
- HID Input item

HID_OUTPUT(a)
Define HID Output item with the data length of one byte.
For usage examples, see \texttt{HID\_KEYBOARD\_REPORT\_DESC()}

\textbf{Parameters}
- \texttt{a} – Output item data

\textbf{Returns}
- HID Output item

HID_FEATURE(a)
Define HID Feature item with the data length of one byte.

\textbf{Parameters}
- \texttt{a} – Feature item data

\textbf{Returns}
- HID Feature item

HID_COLLECTION(a)
Define HID Collection item with the data length of one byte.
For usage examples, see \texttt{HID\_MOUSE\_REPORT\_DESC()}, \texttt{HID\_KEYBOARD\_REPORT\_DESC()}

\textbf{Parameters}
- \texttt{a} – Collection item data

\textbf{Returns}
- HID Collection item

HID\_END\_COLLECTION
Define HID End Collection (non-data) item.
For usage examples, see \texttt{HID\_MOUSE\_REPORT\_DESC()}, \texttt{HID\_KEYBOARD\_REPORT\_DESC()}

\textbf{Returns}
- HID End Collection item

HID\_USAGE\_PAGE(page)
Define HID Usage Page item.
For usage examples, see \texttt{HID\_MOUSE\_REPORT\_DESC()}, \texttt{HID\_KEYBOARD\_REPORT\_DESC()}

\textbf{Parameters}
- \texttt{page} – Usage Page

\textbf{Returns}
- HID Usage Page item
HID_LOGICAL_MIN8(a)
Define HID Logical Minimum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Minimum value in logical units

Returns
HID Logical Minimum item

HID_LOGICAL_MAX8(a)
Define HID Logical Maximum item with the data length of one byte.
For usage examples, see HID_MOUSE_REPORT_DESC(), HID_KEYBOARD_REPORT_DESC()

Parameters
• a – Maximum value in logical units

Returns
HID Logical Maximum item

HID_LOGICAL_MIN16(a, b)
Define HID Logical Minimum item with the data length of two bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value higher byte

Returns
HID Logical Minimum item

HID_LOGICAL_MAX16(a, b)
Define HID Logical Maximum item with the data length of two bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value higher byte

Returns
HID Logical Maximum item

HID_LOGICAL_MIN32(a, b, c, d)
Define HID Logical Minimum item with the data length of four bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value low middle byte
• c – Minimum value high middle byte
• d – Minimum value higher byte

Returns
HID Logical Minimum item

HID_LOGICAL_MAX32(a, b, c, d)
Define HID Logical Maximum item with the data length of four bytes.

Parameters
• a – Minimum value lower byte
• b – Minimum value low middle byte
• c – Minimum value high middle byte
• d – Minimum value higher byte

**Returns**
HID Logical Maximum item

**HID_REPORT_SIZE(size)**
Define HID Report Size item with the data length of one byte.
For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• size – Report field size in bits

**Returns**
HID Report Size item

**HID_REPORT_ID(id)**
Define HID Report ID item with the data length of one byte.

**Parameters**
• id – Report ID

**Returns**
HID Report ID item

**HID_REPORT_COUNT(count)**
Define HID Report Count item with the data length of one byte.
For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• count – Number of data fields included in the report

**Returns**
HID Report Count item

**HID_USAGE(idx)**
Define HID Usage Index item with the data length of one byte.
For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• idx – Number of data fields included in the report

**Returns**
HID Usage Index item

**HID_USAGE_MIN8(a)**
Define HID Usage Minimum item with the data length of one byte.
For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• a – Starting Usage

**Returns**
HID Usage Minimum item

**HID_USAGE_MAX8(a)**
Define HID Usage Maximum item with the data length of one byte.
For usage examples, see `HID_MOUSE_REPORT_DESC()`, `HID_KEYBOARD_REPORT_DESC()`

**Parameters**
• a – Ending Usage

Returns
HID Usage Maximum item

HID_USAGE_MIN16(a, b)
Define HID Usage Minimum item with the data length of two bytes.
For usage examples, see \textit{HID_MOUSE_REPORT_DESC()}, \textit{HID_KEYBOARD_REPORT_DESC()}

Parameters
• a – Starting Usage lower byte
• b – Starting Usage higher byte

Returns
HID Usage Minimum item

HID_USAGE_MAX16(a, b)
Define HID Usage Maximum item with the data length of two bytes.
For usage examples, see \textit{HID_MOUSE_REPORT_DESC()}, \textit{HID_KEYBOARD_REPORT_DESC()}

Parameters
• a – Ending Usage lower byte
• b – Ending Usage higher byte

Returns
HID Usage Maximum item

\textbf{HID types reference}

group \texttt{usb_hid_types}

\textbf{Defines}

\texttt{USB_DESC_HID}
USB HID Class HID descriptor type

\texttt{USB_DESC_HID_REPORT}
USB HID Class Report descriptor type

\texttt{USB_DESC_HID_PHYSICAL}
USB HID Class physical descriptor type

\texttt{USB_HID_GET_REPORT}
USB HID Class GetReport bRequest value

\texttt{USB_HID_GET_IDLE}
USB HID Class GetIdle bRequest value

\texttt{USB_HID_GET_PROTOCOL}
USB HID Class GetProtocol bRequest value
USB_HID_SET_REPORT
   USB HID Class SetReport bRequest value

USB_HID_SET_IDLE
   USB HID Class SetIdle bRequest value

USB_HID_SET_PROTOCOL
   USB HID Class SetProtocol bRequest value

HID_BOOT_IFACE_CODE_NONE
   USB HID Boot Interface Protocol (bInterfaceProtocol) Code None

HID_BOOT_IFACE_CODE_KEYBOARD
   USB HID Boot Interface Protocol (bInterfaceProtocol) Code Keyboard

HID_BOOT_IFACE_CODE_MOUSE
   USB HID Boot Interface Protocol (bInterfaceProtocol) Code Mouse

HID_PROTOCOL_BOOT
   USB HID Class Boot protocol code

HID_PROTOCOL_REPORT
   USB HID Class Report protocol code

HID_ITEM_TYPE_MAIN
   HID Main item type

HID_ITEM_TYPE_GLOBAL
   HID Global item type

HID_ITEM_TYPE_LOCAL
   HID Local item type

HID_ITEM_TAG_INPUT
   HID Input item tag

HID_ITEM_TAG_OUTPUT
   HID Output item tag

HID_ITEM_TAG_COLLECTION
   HID Collection item tag

HID_ITEM_TAG_FEATURE
   HID Feature item tag

HID_ITEM_TAG_COLLECTION_END
   HID End Collection item tag

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HID_ITEM_TAG_USAGE_PAGE
   HID Usage Page item tag

HID_ITEM_TAG_LOGICAL_MIN
   HID Logical Minimum item tag

HID_ITEM_TAG_LOGICAL_MAX
   HID Logical Maximum item tag

HID_ITEM_TAG_PHYSICAL_MIN
   HID Physical Minimum item tag

HID_ITEM_TAG_PHYSICAL_MAX
   HID Physical Maximum item tag

HID_ITEM_TAG_UNIT_EXPONENT
   HID Unit Exponent item tag

HID_ITEM_TAG_UNIT
   HID Unit item tag

HID_ITEM_TAG_REPORT_SIZE
   HID Report Size item tag

HID_ITEM_TAG_REPORT_ID
   HID Report ID item tag

HID_ITEM_TAG_REPORT_COUNT
   HID Report count item tag

HID_ITEM_TAG_USAGE
   HID Usage item tag

HID_ITEM_TAG_USAGE_MIN
   HID Usage Minimum item tag

HID_ITEM_TAG_USAGE_MAX
   HID Usage Maximum item tag

HID_COLLECTION_PHYSICAL
   Physical collection type

HID_COLLECTION_APPLICATION
   Application collection type

HID_COLLECTION_LOGICAL
   Logical collection type
HID_COLLECTION_REPORT
  Report collection type

HID_COLLECTION NAMED_ARRAY
  Named Array collection type

HID_COLLECTION USAGE SWITCH
  Usage Switch collection type

HID_COLLECTION MODIFIER
  Modifier collection type

HID_USAGE_GEN DESKTOP
  HID Generic Desktop Controls Usage page

HID_USAGE_GEN KEYBOARD
  HID Keyboard Usage page

HID_USAGE_GEN LEDS
  HID LEDs Usage page

HID_USAGE_GEN BUTTON
  HID Button Usage page

HID_USAGE_GEN DESKTOP_UNDEFINED
  HID Generic Desktop Undefined Usage ID

HID_USAGE_GEN DESKTOP_POINTER
  HID Generic Desktop Pointer Usage ID

HID_USAGE_GEN DESKTOP MOUSE
  HID Generic Desktop Mouse Usage ID

HID_USAGE_GEN DESKTOP_JOYSTICK
  HID Generic Desktop Joystick Usage ID

HID_USAGE_GEN DESKTOP_GAMEPAD
  HID Generic Desktop Gamepad Usage ID

HID_USAGE_GEN DESKTOP_KEYBOARD
  HID Generic Desktop Keyboard Usage ID

HID_USAGE_GEN DESKTOP_KEYPAD
  HID Generic Desktop Keypad Usage ID

HID_USAGE_GEN DESKTOP_X
  HID Generic Desktop X Usage ID
HID_USAGE_GEN_DESKTOP_Y
HID Generic Desktop Y Usage ID

HID_USAGE_GEN_DESKTOP_WHEEL
HID Generic Desktop Wheel Usage ID

**HID Mouse and Keyboard report descriptors**

The pre-defined Mouse and Keyboard report descriptors can be used by a HID device implementation or simply as examples.

```c
#define HID_MOUSE_REPORT_DESC(bcnt)

Simple HID mouse report descriptor for n button mouse.

**Parameters**
- bcnt – Button count. Allowed values from 1 to 8.

```c
#define HID_KEYBOARD_REPORT_DESC()

Simple HID keyboard report descriptor.

**Enums**

```c
enum hid_kbd_code

HID keyboard button codes.

**Values:**
- enumerator HID_KEY_A = 4
- enumerator HID_KEY_B = 5
- enumerator HID_KEY_C = 6
- enumerator HID_KEY_D = 7
- enumerator HID_KEY_E = 8
- enumerator HID_KEY_F = 9
- enumerator HID_KEY_G = 10
- enumerator HID_KEY_H = 11
- enumerator HID_KEY_I = 12
```
enumerator HID_KEY_J = 13
enumerator HID_KEY_K = 14
enumerator HID_KEY_L = 15
enumerator HID_KEY_M = 16
enumerator HID_KEY_N = 17
enumerator HID_KEY_O = 18
enumerator HID_KEY_P = 19
enumerator HID_KEY_Q = 20
enumerator HID_KEY_R = 21
enumerator HID_KEY_S = 22
enumerator HID_KEY_T = 23
enumerator HID_KEY_U = 24
enumerator HID_KEY_V = 25
enumerator HID_KEY_W = 26
enumerator HID_KEY_X = 27
enumerator HID_KEY_Y = 28
enumerator HID_KEY_Z = 29
enumerator HID_KEY_1 = 30
enumerator HID_KEY_2 = 31
enumerator HID_KEY_3 = 32
enumerator HID_KEY_4 = 33
enumerator HID_KEY_5 = 34
enumerator HID_KEY_6 = 35
enumerator HID_KEY_7 = 36
enumerator HID_KEY_8 = 37
enumerator HID_KEY_9 = 38
enumerator HID_KEY_0 = 39
enumerator HID_KEY_ENTER = 40
enumerator HID_KEY_ESC = 41
enumerator HID_KEY_BACKSPACE = 42
enumerator HID_KEY_TAB = 43
enumerator HID_KEY_SPACE = 44
enumerator HID_KEY_MINUS = 45
enumerator HID_KEY_EQUAL = 46
enumerator HID_KEY_LEFTBRACE = 47
enumerator HID_KEY_RIGHTBRACE = 48
enumerator HID_KEY_BACKSLASH = 49
enumerator HID_KEY_HASH = 50
enumerator HID_KEY_SEMICOLON = 51
enumerator HID_KEY_APOSTROPHE = 52
enumerator HID_KEY_GRAVE = 53
enumerator HID_KEY_COMMA = 54
enumerator HID_KEY_DOT = 55
enumerator HID_KEY_SLASH = 56
enumerator HID_KEY_CAPSLOCK = 57
enumerator HID_KEY_F1 = 58
enumerator HID_KEY_F2 = 59
enumerator HID_KEY_F3 = 60
enumerator HID_KEY_F4 = 61
enumerator HID_KEY_F5 = 62
enumerator HID_KEY_F6 = 63
enumerator HID_KEY_F7 = 64
enumerator HID_KEY_F8 = 65
enumerator HID_KEY_F9 = 66
enumerator HID_KEY_F10 = 67
enumerator HID_KEY_F11 = 68
enumerator HID_KEY_F12 = 69
enumerator HID_KEY_SYSRQ = 70
enumerator HID_KEY_SCROLLLOCK = 71
enumerator HID_KEY_PAUSE = 72
enumerator HID_KEY_INSERT = 73
enumerator HID_KEY_HOME = 74
enumerator HID_KEY_PAGEUP = 75
enumerator HID_KEY_DELETE = 76
enumerator HID_KEY_END = 77
enumerator HID_KEY_PAGEDOWN = 78
enumerator HID_KEY_RIGHT = 79
enumerator HID_KEY_LEFT = 80
enumerator HID_KEY_DOWN = 81

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enumerator HID_KEY_UP = 82
enumerator HID_KEY_NUMLOCK = 83
enumerator HID_KEY_KPSLASH = 84
enumerator HID_KEY_KPASTERISK = 85
enumerator HID_KEY_KPMINUS = 86
enumerator HID_KEY_KPPLUS = 87
enumerator HID_KEY_KPENTER = 88
enumerator HID_KEY_KP_1 = 89
enumerator HID_KEY_KP_2 = 90
enumerator HID_KEY_KP_3 = 91
enumerator HID_KEY_KP_4 = 92
enumerator HID_KEY_KP_5 = 93
enumerator HID_KEY_KP_6 = 94
enumerator HID_KEY_KP_7 = 95
enumerator HID_KEY_KP_8 = 96
enumerator HID_KEY_KP_9 = 97
enumerator HID_KEY_KP_0 = 98

define
enum hid_kbd_modifier
    HID keyboard modifiers.
    Values:
        enumerator HID_KBD_MODIFIER_NONE = 0x00
        enumerator HID_KBD_MODIFIER_LEFT_CTRL = 0x01
        enumerator HID_KBD_MODIFIER_LEFT_SHIFT = 0x02
        enumerator HID_KBD_MODIFIER_LEFT_ALT = 0x04
enumerator HID_KBD_MODIFIER_LEFT_UI = 0x08
enumerator HID_KBD_MODIFIER_RIGHT_CTRL = 0x10
enumerator HID_KBD_MODIFIER_RIGHT_SHIFT = 0x20
enumerator HID_KBD_MODIFIER_RIGHT_ALT = 0x40
enumerator HID_KBD_MODIFIER_RIGHT_UI = 0x80

enum hid_kbd_led
    HID keyboard LEDs.
    Values:
    enumerator HID_KBD_LED_NUM_LOCK = 0x01
    enumerator HID_KBD_LED_CAPS_LOCK = 0x02
    enumerator HID_KBD_LED_SCROLL_LOCK = 0x04
    enumerator HID_KBD_LED_COMPOSE = 0x08
    enumerator HID_KBD_LED_KANA = 0x10

**HID Class Device API reference**

USB HID devices like mouse, keyboard, or any other specific device use this API.

group usb_hid_device_api

**Typedefs**

typedef int (*hid_cb_t)(const struct device *dev, struct usb_setup_packet *setup, int32_t *len, uint8_t **data)

typedef void (*hid_int_ready_callback)(const struct device *dev)

typedef void (*hid_protocol_cb_t)(const struct device *dev, uint8_t protocol)

typedef void (*hid_idle_cb_t)(const struct device *dev, uint16_t report_id)
Functions

void usb_hid_register_device(const struct device *dev, const uint8_t *desc, size_t size, const struct hid_ops *op)

Register HID device.

Parameters

• dev – [in] Pointer to USB HID device
• desc – [in] Pointer to HID report descriptor
• size – [in] Size of HID report descriptor
• op – [in] Pointer to USB HID device interrupt struct

int hid_int_ep_write(const struct device *dev, const uint8_t *data, uint32_t data_len, uint32_t *bytes_ret)

Write to USB HID interrupt endpoint buffer.

Parameters

• dev – [in] Pointer to USB HID device
• data – [in] Pointer to data buffer
• data_len – [in] Length of data to copy

Returns

0 on success, negative errno code on fail.

int hid_int_ep_read(const struct device *dev, uint8_t *data, uint32_t max_data_len, uint32_t *ret_bytes)

Read from USB HID interrupt endpoint buffer.

Parameters

• dev – [in] Pointer to USB HID device
• data – [in] Pointer to data buffer
• max_data_len – [in] Max length of data to copy
• ret_bytes – [out] Number of bytes to copy. If data is NULL and max_data_len is 0 the number of bytes available in the buffer will be returned.

Returns

0 on success, negative errno code on fail.

int usb_hid_set_proto_code(const struct device *dev, uint8_t proto_code)

Set USB HID class Protocol Code.

Should be called before usb_hid_init().

Parameters

• dev – [in] Pointer to USB HID device
• proto_code – [in] Protocol Code to be used for bInterfaceProtocol

Returns

0 on success, negative errno code on fail.

int usb_hid_init(const struct device *dev)

Initialize USB HID class support.

Parameters

• dev – [in] Pointer to USB HID device
Returns
0 on success, negative errno code on fail.

struct hid_ops
#include <usb_hid.h> USB HID device interface.

4.20.5 USB device stack CDC ACM support

The CDC ACM class is used as backend for different subsystems in Zephyr. However, its configuration
may not be easy for the inexperienced user. Below is a description of the different use cases and some
pitfalls.

The interface for CDC ACM user is UART driver API. But there are two important differences in behavior
to a real UART controller:

• Data transfer is only possible after the USB device stack has been initialized and started, until then
  any data is discarded
• If device is connected to the host, it still needs an application on the host side which requests the
data

The devicetree compatible property for CDC ACM UART is zephyr,cdc-acm-uart. CDC ACM support
is automatically selected when USB device support is enabled and a compatible node in the devicetree
sources is present. If necessary, CDC ACM support can be explicitly disabled by CONFIG_USB_CDC_ACM.
About four CDC ACM UART instances can be defined and used, limited by the maximum number of
supported endpoints on the controller.

CDC ACM UART node is supposed to be child of a USB device controller node. Since the designation of
the controller nodes varies from vendor to vendor, and our samples and application should be as generic
as possible, the default USB device controller is usually assigned an zephyr_udc0 node label. Often, CDC
ACM UART is described in a devicetree overlay file and looks like this:

&zephyr_udc0 {
  cdc_acm_uart0: cdc_acm_uart0 {
    compatible = "zephyr,cdc-acm-uart";
    label = "CDC_ACM_0";
  };
};

Samples usb_cdc-acm and usb_hid-cdc have similar overlay files. And since no special properties are
present, it may seem overkill to use devicetree to describe CDC ACM UART. The motivation behind using
devicetree is the easy interchangeability of a real UART controller and CDC ACM UART in applications.

Console over CDC ACM UART

With the CDC ACM UART node from above and zephyr,console property of the chosen node, we can
describe that CDC ACM UART is to be used with the console. A similar overlay file is used by cdc-acm-console.

/ {
  chosen {
    zephyr,console = &cdc_acm_uart0;
  };
};

&zephyr_udc0 {
  cdc_acm_uart0: cdc_acm_uart0 {
    compatible = "zephyr,cdc-acm-uart";
  };
};

(continues on next page)
Before the application uses the console, it is recommended to wait for the DTR signal:

```c
const struct device *const dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_console));
uint32_t dtr = 0;
if (usb_enable(NULL)) {
    return;
}
while (!dtr) {
    uart_line_ctrl_get(dev, UART_LINE_CTRL_DTR, &dtr);
    k_sleep(K_MSEC(100));
}
printk("nuqneH\\n");
```

**CDC ACM UART as backend**

As for the console sample, it is possible to configure CDC ACM UART as backend for other subsystems by setting `Chosen nodes` properties.

List of few Zephyr specific chosen properties which can be used to select CDC ACM UART as backend for a subsystem or application:

- `zephyr,bt-c2h-uart` used in Bluetooth, for example see `bluetooth-hci-uart-sample`
- `zephyr,ot-uart` used in OpenThread, for example see `coprocessor-sample`
- `zephyr,shell-uart` used by shell for serial backend, for example see `samples/subsys/shell/shell_module`
- `zephyr,uart-mcumgr` used by `smp_svr_sample`

### 4.21 Virtualization

**4.21.1 Inter-VM Shared Memory**

**Overview**

As Zephyr is enabled to run as a guest OS on Qemu and ACRN it might be necessary to make VMs aware of each other, or aware of the host. This is made possible by exposing a shared memory among parties via a feature called ivshmem, which stands for inter-VM Shared Memory.
The two types are supported: a plain shared memory (ivshmem-plain) or a shared memory with the ability for a VM to generate an interruption on another, and thus to be interrupted as well itself (ivshmem-doorbell).

Please refer to the official Qemu ivshmem documentation for more information.

Support

Zephyr supports both version: plain and doorbell. Ivshmem driver can be built by enabling CONFIG_IVSHMEM. By default, this will expose the plain version. CONFIG_IVSHMEM_DOORBELL needs to be enabled to get the doorbell version.

Because the doorbell version uses MSI-X vectors to support notification vectors, the CONFIG_IVSHMEM_MSI_X_VECTORS has to be tweaked to the amount of vectors that will be needed.

Note that a tiny shell module can be exposed to test the ivshmem feature by enabling CONFIG_IVSHMEM_SHELL.

API Reference

group ivshmem

ivshmem reference API

Typedef

typedef size_t (*ivshmem_get_mem_f)(const struct device *dev, uintptr_t *memmap)

typedef uint32_t (*ivshmem_get_id_f)(const struct device *dev)

typedef uint16_t (*ivshmem_get_vectors_f)(const struct device *dev)

typedef int (*ivshmem_int_peer_f)(const struct device *dev, uint32_t peer_id, uint16_t vector)

typedef int (*ivshmem_register_handler_f)(const struct device *dev, struct k_poll_signal *signal, uint16_t vector)

Functions

size_t ivshmem_get_mem(const struct device *dev, uintptr_t *memmap)

Get the inter-VM shared memory.

Parameters

- dev – Pointer to the device structure for the driver instance
- memmap – A pointer to fill in with the memory address

Returns

the size of the memory mapped, or 0
uint32_t ivshmem_get_id(const struct device *dev)
Get our VM ID.

**Parameters**
- dev – Pointer to the device structure for the driver instance

**Returns**
our VM ID or 0 if we are not running on doorbell version

uint16_t ivshmem_get_vectors(const struct device *dev)
Get the number of interrupt vectors we can use.

**Parameters**
- dev – Pointer to the device structure for the driver instance

**Returns**
the number of available interrupt vectors

int ivshmem_int_peer(const struct device *dev, uint32_t peer_id, uint16_t vector)
Interrupt another VM.

**Parameters**
- dev – Pointer to the device structure for the driver instance
- peer_id – The VM ID to interrupt
- vector – The interrupt vector to use

**Returns**
0 on success, a negative errno otherwise

int ivshmem_register_handler(const struct device *dev, struct k_poll_signal *signal, uint16_t vector)
Register a vector notification (interrupt) handler.

Note: The returned status, if positive, to a raised signal is the vector that generated the signal. This lets the possibility to the user to have one signal for all vectors, or one per-vector.

**Parameters**
- dev – Pointer to the device structure for the driver instance
- signal – A pointer to a valid and ready to be signaled struct k_poll_signal. Or NULL to unregister any handler registered for the given vector.
- vector – The interrupt vector to get notification from

**Returns**
0 on success, a negative errno otherwise

struct ivshmem_driver_api
#include <ivshmem.h>

### 4.22 Real Time I/O (RTIO)

- **Problem**
- **Inspiration, introducing io_uring**
RTIO provides a framework for doing asynchronous operation chains with event driven I/O. This section covers the RTIO API, queues, executor, iodev, and common usage patterns with peripheral devices.

RTIO takes a lot of inspiration from Linux's io_uring in its operations and API as that API matches up well with hardware DMA transfer queues and descriptions.

A quick sales pitch on why RTIO works well in many scenarios:

1. API is DMA and interrupt friendly
2. No buffer copying
3. No callbacks
4. Blocking or non-blocking operation

### 4.22.1 Problem

An application wishing to do complex DMA or interrupt driven operations today in Zephyr requires direct knowledge of the hardware and how it works. There is no understanding in the DMA API of other Zephyr devices and how they relate.

This means doing complex audio, video, or sensor streaming requires direct hardware knowledge or leaky abstractions over DMA controllers. Neither is ideal.

To enable asynchronous operations, especially with DMA, a description of what to do rather than direct operations through C and callbacks is needed. Enabling DMA features such as channels with priority, and sequences of transfers requires more than a simple list of descriptions.

Using DMA and/or interrupt driven I/O shouldn’t dictate whether or not the call is blocking or not.

### 4.22.2 Inspiration, introducing io_uring

It’s better not to reinvent the wheel (or ring in this case) and io_uring as an API from the Linux kernel provides a winning model. In io_uring there are two lock-free ring buffers acting as queues shared between the kernel and a userland application. One queue for submission entries which may be chained and flushed to create concurrent sequential requests. A second queue for completion queue events. Only a single syscall is actually required to execute many operations, the io_uring_submit call. This call may block the caller when a number of operations to wait on is given.

This model maps well to DMA and interrupt driven transfers. A request to do a sequence of operations in an asynchronous way directly relates to the way hardware typically works with interrupt driven state machines potentially involving multiple peripheral IPs like bus and DMA controllers.

### 4.22.3 Submission Queue and Chaining

The submission queue (sq), is the description of the operations to perform in concurrent chains.

For example imagine a typical SPI transfer where you wish to write a register address to then read from. So the sequence of operations might be...

1. Chip Select
2. Clock Enable
3. Write register address into SPI transmit register
4. Read from the SPI receive register into a buffer
5. Disable clock
6. Disable Chip Select

If anything in this chain of operations fails give up. Some of those operations can be embodied in a device abstraction that understands a read or write implicitly means setup the clock and chip select. The transactional nature of the request also needs to be embodied in some manner. Of the operations above perhaps the read could be done using DMA as its large enough make sense. That requires an understanding of how to setup the device’s particular DMA to do so.

The above sequence of operations is embodied in RTIO as chain of submission queue entries (sqe). Chaining is done by setting a bitflag in an sqe to signify the next sqe must wait on the current one.

Because the chip select and clocking is common to a particular SPI controller and device on the bus it is embodied in what RTIO calls an iodev.
Multiple operations against the same iodev are done in the order provided as soon as possible. If two operation chains have varying points using the same device its possible one chain will have to wait for another to complete.

4.22.4 Completion Queue

In order to know when a sqe has completed there is a completion queue (cq) with completion queue events (cqe). A sqe once completed results in a cqe being pushed into the cq. The ordering of cqe may not be the same order of sqe. A chain of sqe will however ensure ordering and failure cascading.

Other potential schemes are possible but a completion queue is a well trod idea with io_uring and other similar operating system APIs.

4.22.5 Executor and IODev

Turning submission queue entries (sqe) into completion queue events (cqe) is the job of objects implementing the executor and iodev APIs. These APIs enable coordination between themselves to enable things like DMA transfers.

The end result of these APIs should be a method to resolve the request by deciding some of the following questions with heuristic/constraint based decision making.

- Polling, Interrupt, or DMA transfer?
- If DMA, are the requirements met (peripheral supported by DMAC, etc).

The executor is meant to provide policy for when to use each transfer type, and provide the common code for walking through submission queue chains by providing calls the iodev may use to signal completion, error, or a need to suspend and wait.

4.22.6 Outstanding Questions

RTIO is not a complete API and solution, and is currently evolving to best fit the nature of an RTOS. The general ideas behind a pair of queues to describe requests and completions seems sound and has been proven out in other contexts. Questions remain though.

Timeouts and Deadlines

Timeouts and deadlines are key to being Real-Time. Real-Time in Zephyr means being able to do things when an application wants them done. That could mean different things from a deadline with best effort attempts or a timeout and failure.

These features would surely be useful in many cases, but would likely add some significant complexities. It's something to decide upon, and even if enabled would likely be a compile time optional feature leading to complex testing.

Cancellation

Canceling an already queued operation could be possible with a small API addition to perhaps take both the RTIO context and a pointer to the submission queue entry. However, cancellation as an API induces many potential complexities that might not be appropriate. It's something to be decided upon.
Userspace Support

RTIO with userspace is certainly plausible but would require the equivalent of a memory map call to map the shared ringbuffers and also potentially dma buffers.

Additionally a DMA buffer interface would likely need to be provided for coherence and MMU usage.

IODev and Executor API

Lastly the API between an executor and iodev is incomplete.

There are certain interactions that should be supported. Perhaps things like expanding a submission queue entry into multiple submission queue entries in order to split up work that can be done by a device and work that can be done by a DMA controller.

In some SoCs only specific DMA channels may be used with specific devices. In others there are requirements around needing a DMA handshake or specific triggering setups to tell the DMA when to start its operation.

None of that, from the outward facing API, is an issue.

It is however an unresolved task and issue from an internal API between the executor and iodev. This requires some SoC specifics and enabling those generically isn’t likely possible. That’s ok, an iodev and dma executor should be vendor specific, but an API needs to be there between them that is not!

Special Hardware: Intel HDA

In some cases there’s a need to always do things in a specific order with a specific buffer allocation strategy. Consider a DMA that requires the usage of a circular buffer segmented into blocks that may only be transferred one after another. This is the case of the Intel HDA stream for audio.

In this scenario the above API can still work, but would require an additional buffer allocator to work with fixed sized segments.

4.22.7 When to Use

It’s important to understand when DMA like transfers are useful and when they are not. It’s a poor idea to assume that something made for high throughput will work for you. There is a computational, memory, and latency cost to setup the description of transfers.

Polling at 1Hz an air sensor will almost certainly result in a net negative result compared to ad-hoc sensor (i2c/spi) requests to get the sample.

Continuous transfers, driven by timer or interrupt, of data from a peripheral’s on board FIFO over I2C, I3C, SPI, MIPI, I2S, etc. . . maybe, but not always!

4.22.8 Examples

Examples speak loudly about the intended uses and goals of an API. So several key examples are presented below. Some are entirely plausible today without a big leap. Others (the sensor example) would require additional work in other APIs outside of RTIO as a sub system and are theoretical.

Chained Blocking Requests

A common scenario is needing to write the register address to then read from. This can be accomplished by chaining a write into a read operation.

The transaction on i2c is implicit for each operation chain.
int do_some_io(void)
{
    struct rtio_sqe *write_sqe = rtio_spsc_acquire(ez_io.sq);
    struct rtio_sqe *read_sqe = rtio_spsc_acquire(ez_io.sq);

    rtio_sqe_prep_write(write_sqe, i2c_dev, RTIO_PRIO_LOW, &reg_addr, 2);
    write_sqe->flags = RTIO_SQE_CHAINED; /* the next item in the queue will wait on this one */

    rtio_sqe_prep_read(read_sqe, i2c_dev, RTIO_PRIO_LOW, buf, 32);
    rtio_submit(rtio_inplace_executor, &ez_io, 2);

    struct rtio_cqe *read_cqe = rtio_spsc_consume(ez_io.cq);
    struct rtio_cqe *write_cqe = rtio_spsc_consume(ez_io.cq);

    if(read_cqe->result < 0) {
        LOG_ERR("read failed!");
    }

    if(write_cqe->result < 0) {
        LOG_ERR("write failed!");
    }

    rtio_spsc_release(ez_io.cq);
    rtio_spsc_release(ez_io.cq);
}

Non blocking device to device

Imagine wishing to read from one device on an I2C bus and then write the same buffer to a device on a SPI bus without blocking the thread or setting up callbacks or other IPC notification mechanisms.

Perhaps an I2C temperature sensor and a SPI lowrawan module. The following is a simplified version of that potential operation chain.
/* subsequent ops fail */
struct rtio_sqe *write_sqe = rtio_spsc_acquire(ez_io.sq);
rtio_sqe_prep_write(write_sqe, spi_dev, RTIO_PRIO_LOW, buf, 32);

/* call will return immediately without blocking if possible */
rtio_submit(rtio_inplace_executor, &ez_io, 0);

/* These calls might return NULL if the operations have not yet completed! */
for (int i = 0; i < 2; i++) {
    struct rtio_cqe *cqe = rtio_spsc_consume(ez_io.cq);
    while(cqe == NULL) {
        cqe = rtio_spsc_consume(ez_io.cq);
        k_yield();
    }
    if(cqe->userdata == &read && cqe->result < 0) {
        LOG_ERR("read from i2c failed!");
    }
    if(cqe->userdata == &write && cqe->result < 0) {
        LOG_ERR("write to spi failed!");
    }
    /* Must release the completion queue event after consume */
    rtio_spsc_release(ez_io.cq);
}

Nested iodevs for Devices on Buses (Sensors), Theoretical

Consider a device like a sensor or audio codec sitting on a bus.

It's useful to consider that the sensor driver can use RTIO to do I/O on the SPI bus, while also being an
RTIO device itself. The sensor iodev can set aside a small portion of the buffer in front or in back to
store some metadata describing the format of the data. This metadata could then be used in creating a
sensor readings iterator which lazily lets you map over each reading, doing calculations such as FIR/IIR
filtering, or perhaps translating the readings into other numerical formats with useful measurement units
such as SI. RTIO is a common movement API and allows for such uses while not deciding the mechanism.

This same sort of setup could be done for other data streams such as audio or video.

/* Note that the sensor device itself can use RTIO to get data over I2C/SPI
   * potentially with DMA, but we don't need to worry about that here
   * All we need to know is the device tree node_id and that it can be an iodev
   */
RTIO_SENSOR_IODEV(sensor_dev, DEVICE_DT_GET(DT_NODE(super6axis));

RTIO_DEFINE(ez_io, 4, 4);

/* The sensor driver decides the minimum buffer size for us, we decide how
   * many bufs. This could be a typical multiple of a fifo packet the sensor
   * produces, ICM42688 for example produces a FIFO packet of 20 bytes in
   * 20bit mode at 32KHz so perhaps we'd like to get 4 bufs of 4ms of data
   * each in this setup to process on. and its already been defined here for us.
   */
#include <sensors/icm42688_p.h>
static uint8_t bufs[4][ICM42688_RTIO_BUF_SIZE];

(continues on next page)
int do_some_sensors(void) {
    /* Obtain a dmac executor from the DMA device */
    struct device *dma = DEVICE_DT_GET(DT_NODE(dma0));
    const struct rtio_executor *rtio_dma_exec =
        dma_rtio_executor(dma);

    /*
     * Set the executor for our queue context
     */
    rtio_set_executor(ez_io, rtio_dma_exec);

    /* Mostly we want to feed the sensor driver enough buffers to fill while
     * we wait and process! Small enough to process quickly with low latency,
     * big enough to not spend all the time setting transfers up.
     * It's assumed here that the sensor has been configured already
     * and each FIFO watermark interrupt that occurs it attempts
     * to pull from the queue, fill the buffer with a small metadata
     * offset using its own rtio request to the SPI bus using DMA.
     */
    for(int i = 0; i < 4; i++) {
        struct rtio_sqe *read_sqe = rtio_spsc_acquire(ez_io.sq);

        rtio_sqe_prep_read(read_sqe, sensor_dev, RTIO_PRIO_HIGH, bufs[i],
                        ICM42688_RTIO_BUF_SIZE);
    }
    struct device *sensor = DEVICE_DT_GET(DT_NODE(super6axis));
    struct sensor_reader reader;
    struct sensor_channels channels[4] = {
        SENSOR_TIMESTAMP_CHANNEL,
        SENSOR_CHANNEL(int32_t, SENSOR_ACC_X, 0, SENSOR_RAW),
        SENSOR_CHANNEL(int32_t SENSOR_ACC_Y, 0, SENSOR_RAW),
        SENSOR_CHANNEL(int32_t, SENSOR_ACC_Z, 0, SENSOR_RAW),
    };

    while (true) {
        /* call will wait for one completion event */
        rtio_submit(ez_io, 1);
        struct rtio_cqe *cqe = rtio_spsc_consume(ez_io.cq);
        if(cqe->result < 0) {
            LOG_ERR("read failed!");
            goto next;
        }

        /* Bytes read into the buffer */
        int32_t bytes_read = cqe->result;

        /* Retrieve soon to be reusable buffer pointer from completion */
        uint8_t *buf = cqe->userdata;

        /* Get an iterator (reader) that obtains sensor readings in integer
         * form, 16 bit signed values in the native sensor reading format */
        res = sensor_reader(sensor, buf, cqe->result, &reader, channels,
                            sizeof(channels));
        __ASSERT(res == 0);
    }
}

(continues on previous page)
```c
while(sensor_reader_next(&reader)) {
    printf("time(raw): %d, acc (x,y,z): (%d, %d, %d)\n",
           channels[0].value.u32, channels[1].value.i32,
           channels[2].value.i32, channels[3].value.i32);
}

next:
    /* Release completion queue event */
    rtio_spsc_release(ez_io.cq);

    /* resubmit a read request with the newly freed buffer to the sensor
        */
    struct rtio_sqe *read_sqe = rtio_spsc_acquire(ez_io.sq);
    rtio_sqe_prep_read(read_sqe, sensor_dev, RTIO_PRIO_HIGH, buf,\
                        ICM20649_RTIO_BUF_SIZE);
    rtio_sqe_submit(read_sqe);
}
```

### 4.22.9 API Reference

**RTIO API**

**group rtio_api**

RTIO API.

**Defines**

- **RTIO_OP_NOP**
  An operation that does nothing and will complete immediately

- **RTIO_OP_RX**
  An operation that receives (reads)

- **RTIO_OP_TX**
  An operation that transmits (writes)

- **RTIO_SQ_DEFINE(name, len)**
  Statically define and initialize a fixed length submission queue.

  **Parameters**
  
  - `name` – Name of the submission queue.
  - `len` – Queue length, power of 2 required (2, 4, 8).

- **RTIO_CQ_DEFINE(name, len)**
  Statically define and initialize a fixed length completion queue.

  **Parameters**
  
  - `name` – Name of the completion queue.
  - `len` – Queue length, power of 2 required (2, 4, 8).
RTIO_IODEV_SQ_DEFINE(name, len)
Statically define and initialize a fixed length iodev submission queue.

Parameters
• name – Name of the queue.
• len – Queue length, power of 2 required

RTIO_IODEV_DEFINE(name, iodev_api, qsize, iodev_data)
Statically define and initialize an RTIO IODev.

Parameters
• name – Name of the iodev
• iodev_api – Pointer to struct rtio_iodev_api
• qsize – Size of the submission queue, must be power of 2
• iodev_data – Data pointer

RTIO_DEFINE(name, exec, sq_sz, cq_sz)
Statically define and initialize an RTIO context.

Parameters
• name – Name of the RTIO
• exec – Symbol for rtio_executor (pointer)
• sq_sz – Size of the submission queue, must be power of 2
• cq_sz – Size of the completion queue, must be power of 2

Functions

static inline void rtio_sqe_prep_nop(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, void *userdata)
Prepare a nop (no op) submission.

static inline void rtio_sqe_prep_read(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, uint8_t *buf, uint32_t len, void *userdata)
Prepare a read op submission.

static inline void rtio_sqe_prep_write(struct rtio_sqe *sqe, const struct rtio_iodev *iodev, int8_t prio, uint8_t *buf, uint32_t len, void *userdata)
Prepare a write op submission.

static inline void rtio_set_executor(struct rtio *r, struct rtio_executor *exc)
Set the executor of the rtio context.

static inline void rtio_iodev_submit(const struct rtio_sqe *sqe, struct rtio *r)
Perform a submitted operation with an iodev.

Parameters
• sqe – Submission to work on
• r – RTIO context

static inline uint32_t rtio_sqe_acquirable(struct rtio *r)
Count of acquirable submission queue events.

Parameters
• r – RTIO context
Returns
Count of acquirable submission queue events

static inline struct rtio_sqe *rtio_sqe_acquire(struct rtio *r)
Acquire a single submission queue event if available.

Parameters
• r – RTIO context

Return values
• sqe – A valid submission queue event acquired from the submission queue
• NULL – No submission queue event available

static inline void rtio_sqe_produce_all(struct rtio *r)
Produce all previously acquired sqe.

Parameters
• r – RTIO context

static inline void rtio_sqe_drop_all(struct rtio *r)
Drop all previously acquired sqe.

Parameters
• r – RTIO context

static inline struct rtio_cqe *rtio_cqe_consume(struct rtio *r)
Consume a single completion queue event if available.

If a completion queue event is returned rtio_cq_release(r) must be called at some point to release the cqe spot for the cqe producer.

Parameters
• r – RTIO context

Return values
• cqe – A valid completion queue event consumed from the completion queue
• NULL – No completion queue event available

static inline struct rtio_cqe *rtio_cqe_consume_block(struct rtio *r)
Wait for and consume a single completion queue event.

If a completion queue event is returned rtio_cq_release(r) must be called at some point to release the cqe spot for the cqe producer.

Parameters
• r – RTIO context

Return values
cqe – A valid completion queue event consumed from the completion queue

static inline void rtio_cqe_release_all(struct rtio *r)
Release all consumed completion queue events.

Parameters
• r – RTIO context

static inline void rtio_sqe_ok(struct rtio *r, const struct rtio_sqe *sqe, int result)
Inform the executor of a submission completion with success.

This may start the next asynchronous request if one is available.
Parameters

- \texttt{r} – RTIO context
- \texttt{sqe} – Submission that has succeeded
- \texttt{result} – Result of the request

static inline void \texttt{rtio\_sqe\_err(struct rtio *r, const struct rtio\_sqe *sqe, int result)}

Inform the executor of a submission completion with error.

This \textsc{shall} fail the remaining submissions in the chain.

Parameters

- \texttt{r} – RTIO context
- \texttt{sqe} – Submission that has failed
- \texttt{result} – Result of the request

static inline void \texttt{rtio\_cqe\_submit(struct rtio *r, int result, void *userdata)}

Submit a completion queue event with a given result and userdata.

Called by the executor to produce a completion queue event, no inherent locking is performed and this is not safe to do from multiple callers.

Parameters

- \texttt{r} – RTIO context
- \texttt{result} – Integer result code (could be -errno)
- \texttt{userdata} – Userdata to pass along to completion

static inline void \texttt{rtio\_access\_grant(struct rtio *r, struct k\_thread *t)}

Grant access to an RTIO context to a user thread.

\textbf{Return values}

- \texttt{0} – success
- \texttt{-ENOMEM} – not enough room in the queue

int \texttt{rtio\_sqe\_copy\_in(struct rtio *r, const struct rtio\_sqe *sqes, size\_t sqe\_count)}

Copy an array of SQEs into the queue.

Useful if a batch of submissions is stored in ROM or RTIO is used from user mode where a copy must be made.

Partial copying is not done as chained SQEs need to be submitted as a whole set.

Parameters

- \texttt{r} – RTIO context
- \texttt{sqes} – Pointer to an array of SQEs
- \texttt{sqe\_count} – Count of sqes in array

\textbf{Return values}

- \texttt{0} – success
- \texttt{-ENOMEM} – not enough room in the queue

int \texttt{rtio\_cqe\_copy\_out(struct rtio *r, struct rtio\_cqe *cqes, size\_t cqe\_count, k\_timeout\_t timeout)}

Copy an array of CQEs from the queue.

Copies from the RTIO context and its queue completion queue events, waiting for the given time period to gather the number of completions requested.

Parameters

- \texttt{r} – RTIO context
- \texttt{cqes} – Pointer to an array of SQEs
cqe_count – Count of sqes in array

timeout – Timeout to wait for each completion event. Total wait time is potentially timeout*cqe_count at maximum.

**Return values**
copy_count – Count of copied CQEs (0 to cqe_count)

```c
int rtio_submit(struct rtio *r, uint32_t wait_count)
```
Submit I/O requests to the underlying executor.

Submits the queue of submission queue events to the executor. The executor will do the work of managing tasks representing each submission chain, freeing submission queue events when done, and producing completion queue events as submissions are completed.

**Parameters**

- **r** – RTIO context
- **wait_count** – Number of submissions to wait for completion of.

**Return values**

0 – On success

```c
struct rtio_sqe
```
A submission queue event.

**Public Members**

- **op** – Op code
- **prio** – Op priority
- **flags** – Op Flags
- **iodev** – Device to operation on
- **userdata** – User provided pointer to data which is returned upon operation completion
  
  If unique identification of completions is desired this should be unique as well.
- **buf_len** – Length of buffer
- **buf** – Buffer to use

```c
struct rtio_sq
```
Submission queue.

This is used for typifying the members of an RTIO queue pair but nothing more.
struct rtio_cqe
#include <rtio.h> A completion queue event.

Public Members

int32_t result
Result from operation

void *userdata
Associated userdata with operation

struct rtio_cq
#include <rtio.h> Completion queue.
This is used for typifying the members of an RTIO queue pair but nothing more.

struct rtio_executor_api
#include <rtio.h>

Public Members

int (*submit)(struct rtio *, r)
Submit the request queue to executor.
The executor is responsible for interpreting the submission queue and creating concurrent execution chains.
Concurrency is optional and implementation dependent.

void (*ok)(struct rtio *, const struct rtio_sqe *, int result)
SQE completes successfully.

void (*err)(struct rtio *, const struct rtio_sqe *, int result)
SQE fails to complete.

struct rtio_executor
#include <rtio.h> An executor does the work of executing the submissions.
This could be a DMA controller backed executor, thread backed, or simple in place executor.
A DMA executor might schedule all transfers with priorities and use hardware arbitration.
A threaded executor might use a thread pool where each transfer chain is executed across the thread pool and the priority of the transfer is used as the thread priority.
A simple in place executor might simply loop over and execute each transfer in the calling threads context. Priority is entirely derived from the calling thread then.
An implementation of the executor must place this struct as its first member such that pointer aliasing works.
struct rtio

\#include <rtio.h> An RTIO queue pair that both the kernel and application work with.

The kernel is the consumer of the submission queue, and producer of the completion queue.
The application is the consumer of the completion queue and producer of the submission queue.
Nothing is done until a call is performed to do the work (rtio_execute).

struct rtio_iodev_api

\#include <rtio.h> API that an RTIO IO device should implement.

Public Members

void (*submit)(const struct rtio_sqe *sque, struct rtio *r)

Submission function for a request to the iodev.
The iodev is responsible for doing the operation described as a submission queue entry and reporting results using using rtio_sqe_ok or rtio_sqe_err once done.

struct rtio_iodev_sqe

\#include <rtio.h>

struct rtio_iodev_sq

\#include <rtio.h> IO device submission queue.

This is used for reifying the member of the rtio_iodev struct

struct rtio_iodev

\#include <rtio.h> An IO device with a function table for submitting requests.

RTIO SPSC API

\texttt{group rtio_spsc}

RTIO Single Producer Single Consumer (SPSC) Queue API.

Defines

RTIO_SPSC_INITIALIZER(name, type, sz)

Statically initialize an rtio_spsc.

Parameters

\begin{itemize}
  \item name – Name of the spsc symbol to be provided
  \item type – Type stored in the spsc
  \item sz – Size of the spsc, must be power of 2 (ex: 2, 4, 8)
\end{itemize}

RTIO_SPSC_DECLARE(name, type, sz)

Declare an anonymous struct type for an rtio_spsc.

Parameters

\begin{itemize}
  \item name – Name of the spsc symbol to be provided
\end{itemize}
• type – Type stored in the spsc
• sz – Size of the spsc, must be power of 2 (ex: 2, 4, 8)

RTIO_SPSC_DEFINE(name, type, sz)
Define an rtio_spsc with a fixed size.

Parameters
• name – Name of the spsc symbol to be provided
• type – Type stored in the spsc
• sz – Size of the spsc, must be power of 2 (ex: 2, 4, 8)

rtio_spsc_size(spsc)
Size of the SPSC queue.

Parameters
• spsc – SPSC reference

rtio_spsc_reset(spsc)
Initialize/reset a spsc such that its empty.
Note that this is not safe to do while being used in a producer/consumer situation with multiple calling contexts (isrs/threads).

Parameters
• spsc – SPSC to initialize/reset

rtio_spsc_acquire(spsc)
Acquire an element to produce from the SPSC.

Parameters
• spsc – SPSC to acquire an element from for producing

Returns
A pointer to the acquired element or null if the spsc is full

rtio_spsc_produce(spsc)
Produce one previously acquired element to the SPSC.
This makes one element available to the consumer immediately

Parameters
• spsc – SPSC to produce the previously acquired element or do nothing

rtio_spsc_produce_all(spsc)
Produce all previously acquired elements to the SPSC.
This makes all previous acquired elements available to the consumer immediately

Parameters
• spsc – SPSC to produce all previously acquired elements or do nothing

rtio_spsc_drop_all(spsc)
Drop all previously acquired elements.
This makes all previous acquired elements available to be acquired again

Parameters
• spsc – SPSC to drop all previously acquired elements or do nothing
rtio_spsc_consume(spsc)
Consume an element from the spsc.

Parameters
• spsc – Spsc to consume from

Returns
Pointer to element or null if no consumable elements left

rtio_spsc_release(spsc)
Release a consumed element.

Parameters
• spsc – SPSC to release consumed element or do nothing

rtio_spsc_release_all(spsc)
Release all consumed elements.

Parameters
• spsc – SPSC to release consumed elements or do nothing

rtio_spsc_acquirable(spsc)
Count of acquirable in spsc.

Parameters
• spsc – SPSC to get item count for

rtio_spsc_consumable(spsc)
Count of consumables in spsc.

Parameters
• spsc – SPSC to get item count for

rtio_spsc_peek(spsc)
Peek at the first available item in queue.

Parameters
• spsc – Spsc to peek into

Returns
Pointer to element or null if no consumable elements left

rtio_spsc_next(spsc, item)
Peek at the next item in the queue from a given one.

Parameters
• spsc – SPSC to peek at
  • item – Pointer to an item in the queue

Returns
Pointer to element or null if none left

rtio_spsc_prev(spsc, item)
Get the previous item in the queue from a given one.

Parameters
• spsc – SPSC to peek at
  • item – Pointer to an item in the queue

Returns
Pointer to element or null if none left
struct rtio_spsc

Common SPSC attributes.

**Warning:** Not to be manipulated without the macros!

### 4.23 Zephyr message bus (zbus)

The *Zephyr message bus* - *Zbus* is a lightweight and flexible message bus enabling a simple way for threads to talk to one another.

---

**4.23.1 Concepts**

Threads can broadcast messages to all interested observers using zbus. Many-to-many communication is possible. The bus implements message-passing and publish/subscribe communication paradigms that enable threads to communicate synchronously or asynchronously through shared memory. The communication through zbus is channel-based, where threads publish and read to and from using messages. Additionally, threads can observe channels and receive notifications from the bus when the channels are modified. Fig. 4.12 shows an example of a typical application using zbus in which the application logic (hardware independent) talks to other threads via message bus. Note that the threads are decoupled from each other because they only use zbus' channels and do not need to know each other to talk.

**Fig. 4.13** illustrates zbus' anatomy. The bus comprises:

- Set of channels that consists of a unique identifier, its control metadata information, and the message itself;
- **Virtual distributed event dispatcher** (VDED), the bus logic responsible for sending notifications to the observers. The VDED logic runs inside the publishing action in the same thread context, giving the bus an idea of a distributed execution. When a thread publishes to a channel, it also propagates the notifications to the observers;
- Threads (subscribers) and callbacks (listeners) publishing, reading, and receiving notifications from the bus.
Fig. 4.12: A typical zbus application architecture.

Fig. 4.13: Zbus internals details.
The bus makes the publish, read, and subscribe actions available over channels. Publishing and reading are available in all RTOS contexts except inside an Interrupt Service Routine (ISR). The publish and read operations were designed to be simple and fast; the procedure is a mutex locking followed by a memory copy to and from a shared memory region. Zbus observers' registration can be:

- Static, defined in compile time. It is not possible to remove at runtime, but it is possible to suppress it by calling the `zbus_obs_set_enable();`
- Dynamic, it can be added and removed to and from a channel at runtime.

For illustration purposes, suppose a usual sensor-based solution in Fig. 4.14. When the timer is triggered, it pushes an action to a workqueue that publishes to the `Start trigger` channel. As the sensor thread subscribed to the `Start trigger` channel, it starts to fetch the sensor data. Notice the event dispatcher executes the blink callback because it also listens to the `Start trigger` channel. When the sensor data is ready, the sensor thread publishes it to the `Sensor data` channel. The core thread as a `Sensor data` channel subscriber process the sensor data and stores it in an internal sample buffer. It repeats until the sample buffer is full; when it happens, the core thread aggregates the sample buffer information, prepares a package, and publishes that to the `Payload` channel. The Lora thread receives that because it is a `Payload` channel subscriber and sends the payload to the cloud. When the transmission is completed, the Lora thread publishes to the `Transmission done` channel. The blink callback will be executed again since it listens to the `Transmission done` channel.

For illustration purposes, suppose a usual sensor-based solution in Fig. 4.14. When the timer is triggered, it pushes an action to a workqueue that publishes to the `Start trigger` channel. As the sensor thread subscribed to the `Start trigger` channel, it starts to fetch the sensor data. Notice the event dispatcher executes the blink callback because it also listens to the `Start trigger` channel. When the sensor data is ready, the sensor thread publishes it to the `Sensor data` channel. The core thread as a `Sensor data` channel subscriber process the sensor data and stores it in an internal sample buffer. It repeats until the sample buffer is full; when it happens, the core thread aggregates the sample buffer information, prepares a package, and publishes that to the `Payload` channel. The Lora thread receives that because it is a `Payload` channel subscriber and sends the payload to the cloud. When the transmission is completed, the Lora thread publishes to the `Transmission done` channel. The blink callback will be executed again since it listens to the `Transmission done` channel.

Fig. 4.14: Zbus sensor-based application.

This way of implementing the solution gives us certain flexibility enabling us to change things independently. For example, suppose we would like to change the trigger from a timer to a button press. We can do that, and the change does not affect other parts of the system. Suppose, again, we would like to change the communication interface from LoRa to Bluetooth; for that, we only need to change the LoRa thread. No other change is needed to make that work. Thus, the developer would do that for every block of the image. Based on that, there is a sign zbus promotes decoupling in the system architecture.

Another important aspect of using zbus is the reuse of system modules. If a module, code portion with a set of well-defined behaviors, only uses zbus channels and not hardware interfaces, it can easily be reused in other solutions. For that, the new solution must implement the interfaces (set of channels) the module needs to work. That indicates zbus could improve the module reuse.

The last important note is the zbus solution reach. We can count on many different ways of using zbus to enable the developer to be as free as possible to create what they need with it. Messages can be dynamic or static allocated, notifications can be synchronous or asynchronous, the developer can control the channel in so many different ways claiming the channel, developers can add their metadata information to a channel by using the user-data field, the discretionary use of a validator enables the systems to be accurate over message format, and so on. Those characteristics increase the solutions that can be done with zbus and make it a good fit as an open-source community tool.
Limitations

Based on the fact that developers can use zbus to solve many different problems, some challenges arise. Zbus will not solve every problem, so it is necessary to analyze the situation to be sure zbus is applicable. For instance, based on the zbus benchmark, it would not be well suited to a high-speed stream of bytes between threads. The Pipe kernel object solves this kind of need.

Delivery guarantees Zbus always delivers the messages to the listeners. However, there are no message delivery guarantees for subscribers because zbus only sends the notification, but the message reading depends on the subscriber’s implementation. It is possible to increase the delivery rate by following design tips:

- Keep the listeners quick-as-possible (deal with them as ISRs). If some processing is needed, consider submitting a work to a work-queue;
- Try to give producers a high priority to avoid losses;
- Leave spare CPU for observers to consume data produced;
- Consider using message queues or pipes for intensive byte transfers.

Message delivery sequence The listeners (synchronous observers) will follow the channel definition sequence as the notification and message consumption sequence. However, the subscribers, as they have an asynchronous nature, all will receive the notification as the channel definition sequence but only will consume the data when they execute again, so the delivery respects the order, but the priority assigned to the subscribers will define the reaction sequence. All the listeners (static or dynamic) will receive the message before subscribers receive the notification. The sequence of delivery is: (i) static listeners; (ii) runtime listeners; (iii) static subscribers; at last (iv) runtime subscribers.

4.23.2 Implementation

Zbus operation depends on channels and observers. Therefore, it is necessary to determine its message and observers list during the channel definition. A message is a regular C struct; the observer can be a subscriber (asynchronous) or a listener (synchronous). Channels can have a validator function that enables a channel to accept only valid messages.

The following code defines and initializes a regular channel and its dependencies. This channel exchanges accelerometer data, for example.

```c
struct acc_msg {
    int x;
    int y;
    int z;
};

ZBUS_CHAN_DEFINE(acc_chan, /* Name */
    struct acc_msg, /* Message type */
    NULL, /* Validator */
    NULL, /* User Data */
    ZBUS_OBSERVERS(my_listener, my_subscriber), /* observers */
    ZBUS_MSG_INIT(.x = 0, .y = 0, .z = 0) /* Initial value {0} */
);

void listener_callback_example(const struct zbus_channel *chan)
{
    const struct acc_msg *acc;

    (continues on next page)
```
if (&acc_chan == chan) {
    acc = zbus_chan_const_msg(chan); // Direct message access
    LOG_DBG("From listener -> Acc x=%d, y=%d, z=%d", acc->x, acc->y, acc->z);
} }

ZBUS_LISTENER_DEFINE(my_listener, listener_callback_example);
ZBUS_SUBSCRIBER_DEFINE(my_subscriber, 4);
void subscriber_task(void)
{
    const struct zbus_channel *chan;
    while (!zbus_sub_wait(&my_subscriber, &chan, K_FOREVER)) {
        struct acc_msg acc = {0};
        if (&acc_chan == chan) {
            // Indirect message access
            zbus_chan_read(&acc_chan, &acc, K_NO_WAIT);
            LOG_DBG("From subscriber -> Acc x=%d, y=%d, z=%d", acc.x, acc.
˓
→y, acc.z);
        }
    }
}
K_THREAD_DEFINE(subscriber_task_id, 512, subscriber_task, NULL, NULL, NULL, 3, 0, 0);

Note: It is unnecessary to claim/lock a channel before accessing the message inside the listener since the event dispatcher calls listeners with the notifying channel already locked. Subscribers, however, must claim/lock that or use regular read operations to access the message after being notified.

The following code defines and initializes a hard channel and its dependencies. Only valid messages can be published to a hard channel. It is possible because a Validator function passed to the channel's definition. In this example, only messages with move equal to 0, -1, and 1 are valid. Publish function will discard all other values to move.

struct control_msg {
    int move;
};

bool control_validator(const void* msg, size_t msg_size) {
    const struct control_msg* cm = msg;
    bool is_valid = (cm->move == -1) || (cm->move == 0) || (cm->move == 1);
    return is_valid;
}

static int message_count = 0;

ZBUS_CHAN_DEFINE(control_chan, /* Name */
    struct control_msg, /* Message type */
    control_validator, /* Validator */
    &message_count, /* User data */
    ZBUS_OBSERVERS_EMPTY, /* observers */
    ZBUS_MSG_INIT(.move = 0) /* Initial value .move=0 */)
The following sections describe in detail how to use zbus features.

**Publishing to a channel**

Messages are published to a channel in zbus by calling `zbus_chan_pub()`. For example, the following code builds on the examples above and publishes to channel `acc_chan`. The code is trying to publish the message `acc1` to channel `acc_chan`, and it will wait up to one second for the message to be published. Otherwise, the operation fails.

```c
struct acc_msg acc1 = {.x = 1, .y = 1, .z = 1};
zbus_chan_pub(&acc_chan, &acc1, K_SECONDS(1));
```

**Warning:** Do not use this function inside an ISR.

**Reading from a channel**

Messages are read from a channel in zbus by calling `zbus_chan_read()`. So, for example, the following code tries to read the channel `acc_chan`, which will wait up to 500 milliseconds to read the message. Otherwise, the operation fails.

```c
struct acc_msg acc = {0};
zbus_chan_read(&acc_chan, &acc, K_MSEC(500));
```

**Warning:** Do not use this function inside an ISR.

**Forcing channel notification**

It is possible to force zbus to notify a channel's observers by calling `zbus_chan_notify()`. For example, the following code builds on the examples above and forces a notification for the channel `acc_chan`. Note this can send events with no message, which does not require any data exchange.

```c
zbus_chan_notify(&acc_chan, K_NO_WAIT);
```

**Warning:** Do not use this function inside an ISR.

**Declaring channels and observers**

For accessing channels or observers from files other than its defining files, it is necessary to declare them by calling `ZBUS_CHAN_DECLARE` and `ZBUS_OBS_DECLARE`. It is possible to declare more than one channel or observer at the same call. The following code builds on the examples above and displays the defined channels and observers.

```c
ZBUS_OBS_DECLARE(my_listener, my_subscriber);
ZBUS_CHAN_DECLARE(acc_chan, version_chan);
```
Iterating over channels and observers

There is an iterator mechanism in zbus that enables the developer to execute some procedure per channel and observer. The sequence executed is sorted by channel or observer name.

```c
int count;

bool print_channel_data_iterator(const struct zbus_channel *chan) {
    LOG_DBG("%d - Channel %s:", count, zbus_chan_name(chan));
    LOG_DBG(" Message size: %d", zbus_chan_msg_size(chan));
    ++count;
    LOG_DBG(" Observers:");
    for (struct zbus_observer **obs = chan->observers; *obs != NULL; ++obs) {
        LOG_DBG(" - %s", zbus_obs_name(*obs));
    }
    return true;
}

bool print_observer_data_iterator(const struct zbus_observer *obs) {
    LOG_DBG("%d - %s %s", count, ((obs->queue != NULL) ? "Subscriber" : "Listener"), zbus_obs_name(obs));
    ++count;
    return true;
}

void main(void) {
    LOG_DBG("Channel list:");
    count = 0;
    zbus_iterate_over_channels(print_channel_data_iterator);

    LOG_DBG("Observers list:");
    count = 0;
    zbus_iterate_over_observers(print_observer_data_iterator);
}
```

The code will log the following output:

```
D: Channel list:
D: 0 - Channel acc_chan:
D:   Message size: 12
D:   Observers:
D:     - my_listener
D:     - my_subscriber
D: 1 - Channel version_chan:
D:   Message size: 4
D:   Observers:
D:   Observers list:
D: 0 - Listener my_listener
D: 1 - Subscriber my_subscriber
```

Advanced channel control

Zbus was designed to be as flexible and extensible as possible. Thus there are some features designed to provide some control and extensibility to the bus.
Listeners message access  

For performance purposes, listeners can access the receiving channel message directly since they already have the mutex lock for it. To access the channel's message, the listener should use the `zbus_chan_const_msg` because the channel passed as an argument to the listener function is a constant pointer to the channel. The const pointer ensures that the message will be kept unchanged during the notification process.

```c
void listener_callback_example(const struct zbus_channel *chan)
{
    const struct acc_msg *acc;
    if (&acc_chan == chan) {
        acc = zbus_chan_const_msg(chan); // Use this
        // instead of zbus_chan_read(chan, &acc, K_MSEC(200))
        // or zbus_chan_msg(chan)
        LOG_DBG("From listener -> Acc x=%d, y=%d, z=%d", acc->x, acc->y, acc->z);
    }
}
```

User Data  

There is a possibility of injecting data into the channel's metadata by passing the `user_data` pointer to the channel's definition macro. The `user_data` field enables others to access the data. Note that it needs to be set individually for each channel.

Claim and finish a channel  

To take more control over channels, two function were added `zbus_chan_claim()` and `zbus_chan_finish()`. With these functions, it is possible to access the channel's metadata safely. When a channel is claimed, no actions are available to that channel. After finishing the channel, all the actions are available again.

**Warning:** Never change the fields of the channel struct directly. It may cause zbus behavior inconsistencies and concurrency issues.

The following code builds on the examples above and claims the `acc_chan` to set the `user_data` to the channel. Suppose we would like to count how many times the channels exchange messages. We defined the `user_data` to have the 32 bits integer. This code could be added to the listener code described above.

```c
if (!zbus_chan_claim(&acc_chan, K_MSEC(200))) {
    int *message_counting = (int *) zbus_chan_user_data(acc_chan);
    *message_counting += 1;
    zbus_chan_finish(&acc_chan);
}
```

**Warning:** Do not use these functions inside an ISR.

Runtime observer registration  

It is possible to add observers to channels in runtime. This feature uses the object pool pattern technique in which the dynamic nodes are pre-allocated and can be used and recycled. Therefore, it is necessary to set the pool size by changing the feature `CONFIG_ZBUS_RUNTIME_OBSERVERS_POOL_SIZE` to enable this feature. Furthermore, it uses memory slabs. When necessary, turn on the `CONFIG_MEM_SLAB_TRACE_MAX_UTILIZATION` configuration to track the maximum usage of the pool. The following example illustrates the runtime registration usage.

```c
ZBUS_LISTENER_DEFINE(my_listener, callback);
// ...
```
void thread_entry(void) {
    // ...
    /* Adding the observer to channel chan1 */
    zbus_chan_add_obs(&chan1, &my_listener);
    /* Removing the observer from channel chan1 */
    zbus_chan_rm_obs(&chan1, &my_listener);
}

Zbus can only use a limited number of dynamic observers. The configuration option CONFIG_ZBUS_RUNTIME_OBSERVERS_POOL_SIZE represents the size of the runtime observers pool (memory slab). Change that to fit the solution needs. Use the k_mem_slab_num_used_get() to verify how many runtime observers slots are available. The function k_mem_slab_max_used_get() will provide information regarding the maximum number of used slots count reached during the execution. Use that to set the appropriate pool size avoiding waste. The following code illustrates how to use that.

extern struct k_mem_slab _zbus_runtime_obs_pool;
uint32_t slots_available = k_mem_slab_num_free_get(&_zbus_runtime_obs_pool);
uint32_t max_usage = k_mem_slab_max_used_get(&_zbus_runtime_obs_pool);

Warning: Do not use _zbus_runtime_obs_pool memory slab directly. It may lead to inconsistencies.

4.23.3 Samples

For a complete overview of zbus usage, take a look at the samples. There are the following samples available:

- zbus-hello-world-sample illustrates the code used above in action;
- zbus-work-queue-sample shows how to define and use different kinds of observers. Note there is an example of using a work queue instead of executing the listener as an execution option;
- zbus-dyn-channel-sample demonstrates how to use dynamically allocated exchanging data in zbus;
- zbus-uart-bridge-sample shows an example of sending the operation of the channel to a host via serial;
- zbus-remote-mock-sample illustrates how to implement an external mock (on the host) to send and receive messages to and from the bus.
- zbus-runtime-obs-registration-sample illustrates a way of using the runtime observer registration feature;
- zbus-benchmark-sample implements a benchmark with different combinations of inputs.

4.23.4 Suggested Uses

Use zbus to transfer data (messages) between threads in one-to-one, one-to-many, and many-to-many synchronously or asynchronously.

Note: Zbus can be used to transfer streams from the producer to the consumer. However, this can increase zbus' communication latency. So maybe consider a Pipe a good alternative for this communication topology.
4.23.5 Configuration Options

For enabling zbus, it is necessary to enable the CONFIG_ZBUS option.

Related configuration options:
- CONFIG_ZBUS_CHANNEL_NAME
- CONFIG_ZBUS_OBSERVER_NAME
- CONFIG_ZBUS_STRUCTS_ITERABLE_ACCESS
- CONFIG_ZBUS_RUNTIME_OBSERVERS_POOL_SIZE

4.23.6 API Reference

```group zbus_apis
Zbus API.

Defines

ZBUS_OBS_DECLARE(....)
This macro list the observers to be used in a file. Internally, it declares the observers with the extern statement. Note it is only necessary when the observers are declared outside the file.

ZBUS_CHAN_DECLARE(....)
This macro list the channels to be used in a file. Internally, it declares the channels with the extern statement. Note it is only necessary when the channels are declared outside the file.

ZBUS_OBSERVERS_EMPTY
This macro indicates the channel has no observers.

ZBUS_OBSERVERS(....)
This macro indicates the channel has listed observers. Note the sequence of observer notification will follow the same as listed.

ZBUS_CHAN_DEFINE(_name, _type, _validator, _user_data, _observers, _init_val)
Zbus channel definition.
This macro defines a channel.

See also:

struct zbus_channel

Parameters

- _name – The channel's name.
- _type – The Message type. It must be a struct or union.
- _validator – The validator function.
- _user_data – A pointer to the user data.
- _observers – The observers list. The sequence indicates the priority of the observer. The first the highest priority.
- _init_val – The message initialization.
ZBUS_MSG_INIT(_val, ...)  
Initialize a message.  
This macro initializes a message by passing the values to initialize the message struct or union.  

Parameters  
• _val – [in] Variadic with the initial values. ZBUS_INIT(0) means {0}, as ZBUS_INIT(a=10, b=30) means {a=10, b=30}.  

ZBUS_SUBSCRIBER_DEFINE(_name, _queue_size)  
Define and initialize a subscriber.  
This macro defines an observer of subscriber type. It defines a message queue where the subscriber will receive the notification asynchronously, and initialize the struct zbus_observer defining the subscriber.  

Parameters  
• _name – [in] The subscriber’s name.  
• _queue_size – [in] The notification queue’s size.  

ZBUS_LISTENER_DEFINE(_name, _cb)  
Define and initialize a listener.  
This macro defines an observer of listener type. This macro establishes the callback where the listener will be notified synchronously, and initialize the struct zbus_observer defining the listener.  

Parameters  
• _name – [in] The listener's name.  

Functions  

int zbus_chan_pub(const struct zbus_channel *chan, const void *msg, k_timeout_t timeout)  
Publish to a channel.  
This routine publishes a message to a channel.  

Parameters  
• chan – The channel’s reference.  
• msg – Reference to the message where the publish function copies the channel’s message data from.  
• timeout – Waiting period to publish the channel, or one of the special values K_NO_WAIT and K_FOREVER.  

Return values  
• 0 – Channel published.  
• -ENOMEMSG – The message is invalid based on the validator function or some of the observers could not receive the notification.  
• -EBUSY – The channel is busy.  
• -EAGAIN – Waiting period timed out.  
• -EFAULT – A parameter is incorrect, the notification could not be sent to one or more observer, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.
int zbus_chan_read(const struct zbus_channel *chan, void *msg, k_timeout_t timeout)

Read a channel.

This routine reads a message from a channel.

**Parameters**

- **msg** – [out] Reference to the message where the read function copies the channel's message data to.
- **timeout** – [in] Waiting period to read the channel, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**

- **0** – Channel read.
- **-EBUSY** – The channel is busy.
- **-EAGAIN** – Waiting period timed out.
- **-EFAULT** – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_claim(const struct zbus_channel *chan, k_timeout_t timeout)

Claim a channel.

This routine claims a channel. During the claiming period the channel is blocked for publishing, reading, notifying or claiming again. Finishing is the only available action.

**Warning:** After calling this routine, the channel cannot be used by other thread until the zbus_chan_finish routine is performed.

**Warning:** This routine should only be called once before a zbus_chan_finish.

**Parameters**

- **timeout** – [in] Waiting period to claim the channel, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**

- **0** – Channel claimed.
- **-EBUSY** – The channel is busy.
- **-EAGAIN** – Waiting period timed out.
- **-EFAULT** – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_finish(const struct zbus_channel *chan)

Finish a channel claim.

This routine finishes a channel claim. After calling this routine with success, the channel will be able to be used by other thread.
Warning: This routine must only be used after a zbus_chan_claim.

Parameters
- chan – The channel's reference.

Return values
- 0 – Channel finished.
- -EPERM – The channel was claimed by other thread.
- -EINVAL – The channel's mutex is not locked.
- -EFAULT – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

int zbus_chan_notify(const struct zbus_channel *chan, k_timeout_t timeout)

Force a channel notification.

This routine forces the event dispatcher to notify the channel's observers even if the message has no changes. Note this function could be useful after claiming/finishing actions.

Parameters
- chan – The channel's reference.
- timeout – Waiting period to notify the channel, or one of the special values K_NO_WAIT and K_FOREVER.

Return values
- 0 – Channel notified.
- -EPERM – The current thread does not own the channel.
- -EBUSY – The channel's mutex returned without waiting.
- -EAGAIN – Timeout to acquiring the channel's mutex.
- -EFAULT – A parameter is incorrect, the notification could not be sent to one or more observer, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

static inline const char *zbus_chan_name(const struct zbus_channel *chan)

Get the channel's name.

This routine returns the channel's name reference.

Parameters
- chan – The channel's reference.

Returns
Channel's name reference.

static inline void *zbus_chan_msg(const struct zbus_channel *chan)

Get the reference for a channel message directly.

This routine returns the reference of a channel message.

Warning: This function must only be used directly for acquired (locked by mutex) channels. This can be done inside a listener for the receiving channel or after claim a channel.

Parameters
static inline const void *zbus_chan_const_msg(const struct zbus_channel *chan)

Get a constant reference for a channel message directly.

This routine returns a constant reference of a channel message. This should be used inside
listeners to access the message directly. In this way zbus prevents the listener of changing the
notifying channel's message during the notification process.

**Warning:** This function must only be used directly for acquired (locked by mutex) chan-
nels. This can be done inside a listener for the receiving channel or after claim a channel.

Parameters

- chan – The channel's constant reference.

Returns

A constant channel's message reference.

static inline uint16_t zbus_chan_msg_size(const struct zbus_channel *chan)

Get the channel's message size.

This routine returns the channel's message size.

Parameters

- chan – The channel's reference.

Returns

Channel's message size.

static inline void *zbus_chan_user_data(const struct zbus_channel *chan)

Get the channel's user data.

This routine returns the channel's user data.

Parameters

- chan – The channel's reference.

Returns

Channel's user data.

int zbus_chan_add_obs(const struct zbus_channel *chan, const struct zbus_observer *obs,
                       k_timeout_t timeout)

Add an observer to a channel.

This routine adds an observer to the channel.

Parameters

- chan – The channel's reference.
- obs – The observer's reference to be added.
- timeout – Waiting period to add an observer, or one of the special values
  K_NO_WAIT and K_FOREVER.

Return values

- 0 – Observer added to the channel.
- -EALREADY – The observer is already present in the channel's runtime observers list.
• -ENOMEM – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -EINVAL – Some parameter is invalid.

int zbus_chan_rm_obs(const struct zbus_channel *chan, const struct zbus_observer *obs,
                      k_timeout_t timeout)

Remove an observer from a channel.

This routine removes an observer to the channel.

Parameters

• chan – The channel’s reference.
• obs – The observer’s reference to be removed.
• timeout – Waiting period to remove an observer, or one of the special values
  K_NO_WAIT and K_FOREVER.

Return values

• 0 – Observer removed to the channel.
• -EINVAL – Invalid data supplied.
• -EBUSY – Returned without waiting.
• -EAGAIN – Waiting period timed out.
• -ENODATA – no observer found in channel’s runtime observer list.
• -ENOMEM – Returned without waiting.

struct k_mem_slab *zbus_runtime_obs_pool(void)

Get zbus runtime observers pool.

This routine returns a reference of the runtime observers pool.

Returns

Reference of runtime observers pool.

static inline int zbus_obs_set_enable(struct zbus_observer *obs, bool enabled)

Change the observer state.

This routine changes the observer state. A channel when disabled will not receive notifications
from the event dispatcher.

Parameters

• enabled – [in] State to be. When false the observer stops to receive notifica-
  tions.

Return values

• 0 – Observer set enable.
• -EFAULT – A parameter is incorrect, or the function context is invalid
  (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

static inline const char *zbus_obs_name(const struct zbus_observer *obs)

Get the observer’s name.

This routine returns the observer’s name reference.

Parameters

• obs – The observer’s reference.
**Returns**
The observer's name reference.

```c
int zbus_sub_wait(const struct zbus_observer *sub, const struct zbus_channel **chan, k_timeout_t timeout)
```
Wait for a channel notification.

This routine makes the subscriber to wait a notification. The notification comes as a channel reference.

**Parameters**
- **chan** – [out] The notification channel's reference.
- **timeout** – [in] Waiting period for a notification arrival, or one of the special values K_NO_WAIT and K_FOREVER.

**Return values**
- **0** – Notification received.
- **-ENOMSG** – Returned without waiting.
- **-EAGAIN** – Waiting period timed out.
- **-EINVAL** – The observer is not a subscriber.
- **-EFAULT** – A parameter is incorrect, or the function context is invalid (inside an ISR). The function only returns this value when the CONFIG_ZBUS_ASSERT_MOCK is enabled.

```c
bool zbus_iterate_over_channels(bool (*iterator_func)(const struct zbus_channel *chan))
```
Iterate over channels.

Enables the developer to iterate over the channels giving to this function an iterator_func which is called for each channel. If the iterator_func returns false all the iteration stops.

**Return values**
- **true** – Iterator executed for all channels.
- **false** – Iterator could not be executed. Some iterate returned false.

```c
bool zbus_iterate_over_observers(bool (*iterator_func)(const struct zbus_observer *obs))
```
Iterate over observers.

Enables the developer to iterate over the observers giving to this function an iterator_func which is called for each observer. If the iterator_func returns false all the iteration stops.

**Return values**
- **true** – Iterator executed for all channels.
- **false** – Iterator could not be executed. Some iterate returned false.

```c
struct zbus_channel
```

```
#include <zbus.h>
```

Type used to represent a channel.

Every channel has a `zbus_channel` structure associated used to control the channel access and usage.

**Public Members**
const char *const name
    Channel name.

const uint16_t message_size
    Message size. Represents the channel's message size.

void *const user_data
    User data available to extend zbus features. The channel must be claimed before using
    this field.

void *const message
    Message reference. Represents the message's reference that points to the actual shared
    memory region.

bool (*const validator)(const void *msg, size_t msg_size)
    Message validator. Stores the reference to the function to check the message validity
    before actually performing the publishing. No invalid messages can be published. Every
    message is valid when this field is empty.

struct k_mutex *mutex
    Access control mutex. Points to the mutex used to avoid race conditions for accessing the
    channel.

sys_slist_t *runtime_observers
    Dynamic channel observer list. Represents the channel's observers list, it can be empty or
    have listeners and subscribers mixed in any sequence. It can be changed in runtime.

const struct zbus_observer *const *observers
    Channel observer list. Represents the channel's observers list, it can be empty or have
    listeners and subscribers mixed in any sequence.

struct zbus_observer
    
    #include <zbus.h> Type used to represent an observer.

    Every observer has an representation structure containing the relevant information. An ob-
    server is a code portion interested in some channel. The observer can be notified syn-
    chronously or asynchronously and it is called listener and subscriber respectively. The ob-
    server can be enabled or disabled during runtime by change the enabled boolean field of the
    structure. The listeners have a callback function that is executed by the bus with the index
    of the changed channel as argument when the notification is sent. The subscribers have a
    message queue where the bus enqueues the index of the changed channel when a notification
    is sent.

    See also:
    
    zbus_obs_set_enable function to properly change the observer's enabled field.

Public Members

const char *const name
    Observer name.
```c
bool enabled
   Enabled flag. Indicates if observer is receiving notification.

struct k_msgq *const queue
   Observer message queue. It turns the observer into a subscriber.

void (*const callback)(const struct zbus_channel *chan)
   Observer callback function. It turns the observer into a listener.
```

## 4.24 Miscellaneous

### 4.24.1 Checksum APIs

**CRC**

```c

group crc

Enums

enum crc_type
   CRC algorithm enumeration.
   These values should be used with the CRC dispatch function.
   Values:

enumerator CRC7_BE
   Use `crc7_be`

enumerator CRC8
   Use `crc8`

enumerator CRC8_CCITT
   Use `crc8_ccitt`

enumerator CRC16
   Use `crc16`

enumerator CRC16_ANSI
   Use `crc16_ansi`

enumerator CRC16_CCITT
   Use `crc16_ccitt`

enumerator CRC16_ITU_T
   Use `crc16_itu_t`
```
enumerator CRC32_C
   Use \texttt{crc32_c}

enumerator CRC32_IEEE
   Use \texttt{crc32_ieee}

Functions

\begin{verbatim}
uint16_t crc16(uint16_t poly, uint16_t seed, const uint8_t *src, size_t len)
\end{verbatim}
Generic function for computing a CRC-16 without input or output reflection.
Compute CRC-16 by passing in the address of the input, the input length and polynomial used in addition to the initial value. This is $O(n \cdot 8)$ where $n$ is the length of the buffer provided. No reflection is performed.

\textbf{Note:} If you are planning to use a CRC based on poly \texttt{0x1012} the functions \texttt{crc16_itu_t()} is faster and thus recommended over this one.

\begin{itemize}
\item \texttt{poly} – The polynomial to use omitting the leading $x^{16}$ coefficient
\item \texttt{seed} – Initial value for the CRC computation
\item \texttt{src} – Input bytes for the computation
\item \texttt{len} – Length of the input in bytes
\end{itemize}

Returns
The computed CRC16 value (without any XOR applied to it)

\begin{verbatim}
uint16_t crc16_reflect(uint16_t poly, uint16_t seed, const uint8_t *src, size_t len)
\end{verbatim}
Generic function for computing a CRC-16 with input and output reflection.
Compute CRC-16 by passing in the address of the input, the input length and polynomial used in addition to the initial value. This is $O(n \cdot 8)$ where $n$ is the length of the buffer provided. Both input and output are reflected.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

\begin{itemize}
\item CRC-16/ANSI, CRC-16/MODBUS, CRC-16/USB, CRC-16/IBM \url{https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-modbus} \texttt{poly: 0x8005 (0xA001)}
   \texttt{initial seed: 0xffff, xor output: 0x0000}
\end{itemize}

\textbf{Note:} If you are planning to use a CRC based on poly \texttt{0x1012} the function \texttt{crc16_ccitt()} is faster and thus recommended over this one.

\begin{itemize}
\item \texttt{poly} – The polynomial to use omitting the leading $x^{16}$ coefficient. Important: please reflect the poly. For example, use \texttt{0xA001} instead of \texttt{0x8005} for CRC-16-MODBUS.
\item \texttt{seed} – Initial value for the CRC computation
\end{itemize}
• src – Input bytes for the computation
• len – Length of the input in bytes

Returns
The computed CRC16 value (without any XOR applied to it)

uint8_t crc8(const uint8_t *src, size_t len, uint8_t polynomial, uint8_t initial_value, bool reversed)

Generic function for computing CRC 8.
Compute CRC 8 by passing in the address of the input, the input length and polynomial used in addition to the initial value.

Parameters
• src – Input bytes for the computation
• len – Length of the input in bytes
• polynomial – The polynomial to use omitting the leading x^8 coefficient
• initial_value – Initial value for the CRC computation
• reversed – Should we use reflected/reversed values or not

Returns
The computed CRC8 value

uint16_t crc16_ccitt(uint16_t seed, const uint8_t *src, size_t len)

Compute the checksum of a buffer with polynomial 0x1021, reflecting input and output.
This function is able to calculate any CRC that uses 0x1021 as its polynomial and requires reflecting both the input and the output. It is a fast variant that runs in O(n) time, where n is the length of the input buffer.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

• CRC-16/CCITT, CRC-16/CCITT-TRUE, CRC-16/KERMIT https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-kermit initial seed: 0x0000, xor output: 0x0000


Note: To calculate the CRC across non-contiguous blocks use the return value from block N-1 as the seed for block N.
uint16_t crc16_itu_t(uint16_t seed, const uint8_t *src, size_t len)

Compute the checksum of a buffer with polynomial 0x1021, no reflection of input or output.

This function is able to calculate any CRC that uses 0x1021 as its polynomial and requires no reflection on both the input and the output. It is a fast variant that runs in \( O(n) \) time, where \( n \) is the length of the input buffer.

The following checksums can, among others, be calculated by this function, depending on the value provided for the initial seed and the value the final calculated CRC is XORed with:

- CRC-16/XMODEM, CRC-16/ACORN, CRC-16/LTE https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-xmodem initial seed: 0x0000, xor output: 0x0000
- CRC16/CCITT-FALSE, CRC-16/IBM-3740, CRC-16/AUTOSAR https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-ibm-3740 initial seed: 0xffff, xor output: 0x0000
- CRC-16/GSM https://reveng.sourceforge.io/crc-catalogue/16.htm#crc.cat.crc-16-gsm initial seed: 0x0000, xor output: 0xffff


Note: To calculate the CRC across non-contiguous blocks use the return value from block N-1 as the seed for block N.

Parameters
- seed – Value to seed the CRC with
- src – Input bytes for the computation
- len – Length of the input in bytes

Returns
The computed CRC16 value (without any XOR applied to it)

static inline uint16_t crc16_ansi(const uint8_t *src, size_t len)

Compute the ANSI (or Modbus) variant of CRC-16.

The ANSI variant of CRC-16 uses 0x8005 (0xA001 reflected) as its polynomial with the initial * value set to 0xffff.

Parameters
- src – Input bytes for the computation
- len – Length of the input in bytes

Returns
The computed CRC16 value

uint32_t crc32_ieee(const uint8_t *data, size_t len)

Generate IEEE conform CRC32 checksum.

Parameters
- *data – Pointer to data on which the CRC should be calculated.
- len – Data length.

Returns
CRC32 value.


```c
uint32_t crc32_ieee_update(uint32_t crc, const uint8_t *data, size_t len)
Update an IEEE conforming CRC32 checksum.

Parameters
• crc – CRC32 checksum that needs to be updated.
• *data – Pointer to data on which the CRC should be calculated.
• len – Data length.

Returns
CRC32 value.
```

```c
uint32_t crc32_c(uint32_t crc, const uint8_t *data, size_t len, bool first_pkt, bool last_pkt)
Calculate CRC32C (Castagnoli) checksum.

Parameters
• crc – CRC32C checksum that needs to be updated.
• *data – Pointer to data on which the CRC should be calculated.
• len – Data length.
• first_pkt – Whether this is the first packet in the stream.
• last_pkt – Whether this is the last packet in the stream.

Returns
CRC32 value.
```

```c
uint8_t crc8_ccitt(uint8_t initial_value, const void *buf, size_t len)
Compute CCITT variant of CRC 8.
Normal CCITT variant of CRC 8 is using 0x07.

Parameters
• initial_value – Initial value for the CRC computation
• buf – Input bytes for the computation
• len – Length of the input in bytes

Returns
The computed CRC8 value
```

```c
uint8_t crc7_be(uint8_t seed, const uint8_t *src, size_t len)
Compute the CRC-7 checksum of a buffer.
See JESD84-A441. Used by the MMC protocol. Uses 0x09 as the polynomial with no reflection. The CRC is left justified, so bit 7 of the result is bit 6 of the CRC.

Parameters
• seed – Value to seed the CRC with
• src – Input bytes for the computation
• len – Length of the input in bytes

Returns
The computed CRC7 value
```

```c
static inline uint32_t crc_by_type(enum crc_type type, const uint8_t *src, size_t len, uint32_t seed, uint32_t poly, bool reflect, bool first, bool last)
Compute a CRC checksum, in a generic way.
This is a dispatch function that calls the individual CRC routine determined by type.
```
For 7, 8, and 16-bit CRCs, the relevant seed and poly values should be passed in via the least-significant byte(s).

Similarly, for 7, 8, and 16-bit CRCs, the relevant result is stored in the least-significant byte(s) of the returned value.

**Parameters**

- **type** – CRC algorithm to use.
- **src** – Input bytes for the computation
- **len** – Length of the input in bytes
- **seed** – Value to seed the CRC with
- **poly** – The polynomial to use omitting the leading coefficient
- **reflect** – Should we use reflected/reversed values or not
- **first** – Whether this is the first packet in the stream.
- **last** – Whether this is the last packet in the stream.

**Returns**

`uint32_t` the computed CRC value

### 4.24.2 Structured Data APIs

**JSON**

**group** `json`

**Defines**

```c
JSON_OBJ_DESCR_PRIM(struct_, field_name_, type_)
```

Helper macro to declare a descriptor for supported primitive values.

Here's an example of use:

```c
struct foo {
    int some_int;
};

struct json_obj_descr foo[] = {
    JSON_OBJ_DESCR_PRIM(struct foo, some_int, JSON_TOK_NUMBER),
};
```

**Parameters**

- **struct_** – Struct packing the values
- **field_name_** – Field name in the struct
- **type_** – Token type for JSON value corresponding to a primitive type. Must be one of: `JSON_TOK_STRING` for strings, `JSON_TOK_NUMBER` for numbers, `JSON_TOK_TRUE` (or `JSON_TOK_FALSE`) for booleans.
**JSON_OBJ_DESCR_OBJECT**

```c
JSON_OBJ_DESCR_OBJECT(struct_, field_name_, sub_descr_)
```

Helper macro to declare a descriptor for an object value.

Here's an example of use:

```c
struct nested {
    int foo;
    struct {
        int baz;
    } bar;
};
```

```c
struct json_obj_descr nested_bar[] = {
    { ... declare bar.baz descriptor ... },
};
```

```c
struct json_obj_descr nested[] = {
    { ... declare foo descriptor ... },
    JSON_OBJ_DESCR_OBJECT(struct nested, bar, nested_bar),
};
```

**Parameters**

- `struct_` – Struct packing the values
- `field_name_` – Field name in the struct
- `sub_descr_` – Array of `json_obj_descr` describing the subobject

**JSON_OBJ_DESCR_ARRAY**

```c
JSON_OBJ_DESCR_ARRAY(struct_, field_name_, max_len_, len_field_, elem_type_)
```

Helper macro to declare a descriptor for an array of primitives.

Here's an example of use:

```c
struct example {
    int foo[10];
    size_t foo_len;
};
```

```c
struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_ARRAY(struct example, foo, 10, foo_len,
                          JSON_TOK_NUMBER)
};
```

**Parameters**

- `struct_` – Struct packing the values
- `field_name_` – Field name in the struct
- `max_len_` – Maximum number of elements in array
- `len_field_` – Field name in the struct for the number of elements in the array
- `elem_type_` – Element type, must be a primitive type

**JSON_OBJ_DESCR_OBJ_ARRAY**

```c
JSON_OBJ_DESCR_OBJ_ARRAY(struct_, field_name_, max_len_, len_field_, elem_descr_,
                          elem_descr_len_)
```

Helper macro to declare a descriptor for an array of objects.
Here's an example of use:

```c
struct person_height {
    const char *name;
    int height;
};

struct people_heights {
    struct person_height heights[10];
    size_t heights_len;
};

struct json_obj_descr person_height_descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_OBJ_ARRAY(struct people_heights, heights, 10,
                              heights_len, person_height_descr,
                              ARRAY_SIZE(person_height_descr)),
};
```

Parameters

- `struct_` – Struct packing the values
- `field_name_` – Field name in the struct containing the array
- `max_len_` – Maximum number of elements in the array
- `len_field_` – Field name in the struct for the number of elements in the array
- `elem_descr_` – Element descriptor, pointer to a descriptor array
- `elem descr_len_` – Number of elements in elem descr_

`JSON_OBJ_DESCR_ARRAY_ARRAY(struct_, field_name_, max_len_, len_field_, elem descr_,
                             elem descr_len_)`

Helper macro to declare a descriptor for an array of array.

Here's an example of use:

```c
struct person_height {
    const char *name;
    int height;
};

struct person_heights_array {
    struct person_height heights;
}

struct people_heights {
    struct person_heights_array heights[10];
    size_t heights_len;
};
```

(continues on next page)
struct json_obj_descr person_height_descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr person_height_array_descr[] = {
    JSON_OBJ_DESCR_OBJECT(struct person_heights_array,
                            heights, person_height_descr),
};

struct json_obj_descr array_array[] = {
    JSON_OBJ_DESCR_ARRAY_ARRAY(struct people_heights, heights, 10,
                                heights_len, person_height_array_descr,
                                ARRAY_SIZE(person_height_array_descr)),
};

**Parameters**

- struct - Struct packing the values
- field_name - Field name in the struct containing the array
- max_len - Maximum number of elements in the array
- len_field - Field name in the struct for the number of elements in the array
- elem_descr - Element descriptor, pointer to a descriptor array
- elem_descr_len - Number of elements in elem_descr

`JSON_OBJ_DESCR_PRIM_NAMED(struct_, json_field_name_, struct_field_name_, type_)`

Variant of `JSON_OBJ_DESCR_PRIM` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

**See also:**

`JSON_OBJ_DESCR_PRIM`

**Parameters**

- struct - Struct packing the values.
- json_field_name - String, field name in JSON strings
- struct_field_name - Field name in the struct
- type - Token type for JSON value corresponding to a primitive type.

`JSON_OBJ_DESCR_OBJECT_NAMED(struct_, json_field_name_, struct_field_name_, sub_descr_)`

Variant of `JSON_OBJ_DESCR_OBJECT` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

**See also:**

`JSON_OBJ_DESCR_OBJECT`
• **struct_** – Struct packing the values
• **json_field_name_** – String, field name in JSON strings
• **struct_field_name_** – Field name in the struct
• **sub_descr_** – Array of `json_obj_descr` describing the subobject

```c
JSON_OBJ_DESCR_ARRAY_NAMED(struct_, json_field_name_, struct_field_name_, max_len_,
     len_field_, elem_type_)
```

Variant of `JSON_OBJ_DESCR_ARRAY` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

**See also:**

`JSON_OBJ_DESCR_ARRAY`

**Parameters**

• **struct_** – Struct packing the values
• **json_field_name_** – String, field name in JSON strings
• **struct_field_name_** – Field name in the struct
• **max_len_** – Maximum number of elements in array
• **len_field_** – Field name in the struct for the number of elements in the array
• **elem_type_** – Element type, must be a primitive type

```c
JSON_OBJ_DESCR_OBJ_ARRAY_NAMED(struct_, json_field_name_, struct_field_name_, max_len_,
     len_field_, elem_descr_, elem_descr_len_)
```

Variant of `JSON_OBJ_DESCR_OBJ_ARRAY` that can be used when the structure and JSON field names differ.

This is useful when the JSON field is not a valid C identifier.

Here's an example of use:

```c
struct person_height {
    const char *name;
    int height;
};

struct people_heights {
    struct person_height heights[10];
    size_t heights_len;
};

struct json_obj_descr person_height_descr[] = {
    JSON_OBJ_DESCR_PRIM(struct person_height, name, JSON_TOK_STRING),
    JSON_OBJ_DESCR_PRIM(struct person_height, height, JSON_TOK_NUMBER),
};

struct json_obj_descr array[] = {
    JSON_OBJ_DESCR_OBJ_ARRAY_NAMED(struct people_heights, 
        "people-heights", heights, 10, heights_len,
    )
};
```

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Parameters

- `struct_` – Struct packing the values
- `json_field_name_` – String, field name of the array in JSON strings
- `struct_field_name_` – Field name in the struct containing the array
- `max_len_` – Maximum number of elements in the array
- `len_field_` – Field name in the struct for the number of elements in the array
- `elem_descr_` – Element descriptor, pointer to a descriptor array
- `elem_descr_len_` – Number of elements in `elem descr_`

Typedefs

typedef int (*json_append_bytes_t)(const char *bytes, size_t len, void *data)
Function pointer type to append bytes to a buffer while encoding JSON data.

**Param bytes**
Contents to write to the output

**Param len**
Number of bytes to append to output

**Param data**
User-provided pointer

**Return**
This callback function should return a negative number on error (which will be propagated to the return value of `json_objEncode()`), or 0 on success.

Enums

enum json_tokens

**Values:**

- enumerator `JSON_TOK_NONE` = '\''
- enumerator `JSON_TOK_OBJECT_START` = '{'
- enumerator `JSON_TOK_OBJECT_END` = '}'
- enumerator `JSON_TOK_LIST_START` = '['
- enumerator `JSON_TOK_ARRAY_START` = '['
- enumerator `JSON_TOK_LIST_END` = ']'

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Functions

```c
int json_obj_parse(char *json, size_t len, const struct json_obj_descr *descr, size_t descr_len, void *val)
```

Parses the JSON-encoded object pointed to by `json`, with size `len`, according to the descriptor pointed to by `descr`. Values are stored in a struct pointed to by `val`. Set up the descriptor like this:

```c
struct s { int foo; char *bar; } struct json_obj_descr descr[] = { JSON_OBJ_DESCR_PRIM(struct s, foo, JSON_TOK_NUMBER), JSON_OBJ_DESCR_PRIM(struct s, bar, JSON_TOK_STRING), };
```

Since this parser is designed for machine-to-machine communications, some liberties were taken to simplify the design: (1) strings are not unescaped (but only valid escape sequences are accepted); (2) no UTF-8 validation is performed; and (3) only integer numbers are supported (no `strtod()` in the minimal libc).

**Parameters**

- `json` – Pointer to JSON-encoded value to be parsed
- `len` – Length of JSON-encoded value
- `descr` – Pointer to the descriptor array
- `descr_len` – Number of elements in the descriptor array. Must be less than 31 due to implementation detail reasons (if more fields are necessary, use two descriptors)
• **val** – Pointer to the struct to hold the decoded values

**Returns**

< 0 if error, bitmap of decoded fields on success (bit 0 is set if first field in the descriptor has been properly decoded, etc).

```c
int json_arr_parse(char *json, size_t len, const struct json_obj_descr *descr, void *val)
```
Parses the JSON-encoded array pointed to by `json`, with size `len`, according to the descriptor pointed to by `descr`. Values are stored in a struct pointed to by `val`. Set up the descriptor like this:

```c
struct s { int foo; char *bar; } struct json_obj_descr descr[] = {
  JSON_OBJ_DESCR_PRIM(struct s, foo, JSON_TOK_NUMBER),
  JSON_OBJ_DESCR_PRIM(struct s, bar, JSON_TOK_STRING),
};
```

Since this parser is designed for machine-to-machine communications, some liberties were taken to simplify the design: (1) strings are not unescaped (but only valid escape sequences are accepted); (2) no UTF-8 validation is performed; and (3) only integer numbers are supported (no `strtod()` in the minimal libc).

**Parameters**

• `json` – Pointer to JSON-encoded array to be parsed
• `len` – Length of JSON-encoded array
• `descr` – Pointer to the descriptor array
• `val` – Pointer to the struct to hold the decoded values

**Returns**

0 if array has been successfully parsed. A negative value indicates an error (as defined on `errno.h`).

```c
int json_arr_separate_object_parse_init(struct json_obj *json, char *payload, size_t len)
```
Initialize single-object array parsing.

JSON-encoded array data is going to be parsed one object at a time. Data is provided by `payload` with the size of `len` bytes.

Function validate that Json Array start is detected and initialize `json` object for Json object parsing separately.

**Parameters**

• `json` – Provide storage for parser states. To be used when parsing the array.
• `payload` – Pointer to JSON-encoded array to be parsed
• `len` – Length of JSON-encoded array

**Returns**

0 if array start is detected and initialization is successful or negative error code in case of failure.

```c
int json_arr_separate_parse_object(struct json_obj *json, const struct json_obj_descr *descr, size_t descr_len, void *val)
```
Parse a single object from array.

Parses the JSON-encoded object pointed to by `json` object array, with size `len`, according to the descriptor pointed to by `descr`.

**Parameters**

• `json` – Pointer to JSON-object message state
• `descr` – Pointer to the descriptor array
• descr_len – Number of elements in the descriptor array. Must be less than 31.
• val – Pointer to the struct to hold the decoded values

Returns
< 0 if error, 0 for end of message, bitmap of decoded fields on success (bit 0 is set if first field in the descriptor has been properly decoded, etc).

ssize_t json_escape(char *str, size_t *len, size_t buf_size)
Escapes the string so it can be used to encode JSON objects.

Parameters
• str – The string to escape; the escape string is stored the buffer pointed to by this parameter
• len – Points to a size_t containing the size before and after the escaping process
• buf_size – The size of buffer str points to

Returns
0 if string has been escaped properly, or -ENOMEM if there was not enough space to escape the buffer

size_t json_calc_escaped_len(const char *str, size_t len)
Calculates the JSON-escaped string length.

Parameters
• str – The string to analyze
• len – String size

Returns
The length str would have if it were escaped

ssize_t json_calc_encoded_len(const struct json_obj_descr *descr, size_t descr_len, const void *val)
Calculates the string length to fully encode an object.

Parameters
• descr – Pointer to the descriptor array
• descr_len – Number of elements in the descriptor array
• val – Struct holding the values

Returns
Number of bytes necessary to encode the values if >0, an error code is returned.

int json_obj_encode_buf(const struct json_obj_descr *descr, size_t descr_len, const void *val, char *buffer, size_t buf_size)
Encodes an object in a contiguous memory location.

Parameters
• descr – Pointer to the descriptor array
• descr_len – Number of elements in the descriptor array
• val – Struct holding the values
• buffer – Buffer to store the JSON data
• buf_size – Size of buffer, in bytes, with space for the terminating NUL character

Returns
0 if object has been successfully encoded. A negative value indicates an error (as defined on errno.h).
int json_arr_encode_buf(const struct json_obj_descr *descr, const void *val, char *buffer, size_t buf_size)

Encodes an array in a contiguous memory location.

**Parameters**

- **descr** – Pointer to the descriptor array
- **val** – Struct holding the values
- **buffer** – Buffer to store the JSON data
- **buf_size** – Size of buffer, in bytes, with space for the terminating NUL character

**Returns**

0 if object has been successfully encoded. A negative value indicates an error (as defined on errno.h).

int json_obj_encode(const struct json_obj_descr *descr, size_t descr_len, const void *val, json_append_bytes_t append_bytes, void *data)

Encodes an object using an arbitrary writer function.

**Parameters**

- **descr** – Pointer to the descriptor array
- **descr_len** – Number of elements in the descriptor array
- **val** – Struct holding the values
- **append_bytes** – Function to append bytes to the output
- **data** – Data pointer to be passed to the append_bytes callback function.

**Returns**

0 if object has been successfully encoded. A negative value indicates an error.

int json_arr_encode(const struct json_obj_descr *descr, const void *val, json_append_bytes_t append_bytes, void *data)

Encodes an array using an arbitrary writer function.

**Parameters**

- **descr** – Pointer to the descriptor array
- **val** – Struct holding the values
- **append_bytes** – Function to append bytes to the output
- **data** – Data pointer to be passed to the append_bytes callback function.

**Returns**

0 if object has been successfully encoded. A negative value indicates an error.

struct json_token

#include <json.h>

struct json_lexer

#include <json.h>

struct json_obj

#include <json.h>
JSON Web Tokens (JWT) are an open, industry standard [RFC 7519](https://tools.ietf.org/html/rfc7519) method for representing claims securely between two parties. Although JWT is fairly flexible, this API is limited to creating the simplistic tokens needed to authenticate with the Google Core IoT infrastructure.

**group jwt**

JSON Web Token (JWT)

**Functions**

```c
int jwt_init_builder(struct jwt_builder *builder, char *buffer, size_t buffer_size)
```

Initialize the JWT builder.

Initialize the given JWT builder for the creation of a fresh token. The buffer size should at least be as long as JWT_BUILDER_MAX_SIZE returns.

**Parameters**

- `builder` – The builder to initialize.
- `buffer` – The buffer to write the token to.
- `buffer_size` – The size of this buffer. The token will be NULL terminated, which needs to be allowed for in this size.

**Return values**

- `0` – Success
- `-ENOSPC` – Buffer is insufficient to initialize

```c
int jwt_add_payload(struct jwt_builder *builder, int32_t exp, int32_t iat, const char *aud)
```

add JWT primary payload.

```c
int jwt_sign(struct jwt_builder *builder, const char *der_key, size_t der_key_len)
```

Sign the JWT token.

```c
static inline size_t jwt_payload_len(struct jwt_builder *builder)
```

**struct jwt_builder**

#include `<jwt.h>` JWT data tracking.

JSON Web Tokens contain several sections, each encoded in base-64. This structure tracks the token as it is being built, including limits on the amount of available space. It should be initialized with `jwt_init()`.
Public Members

char *base
   The base of the buffer we are writing to.

char *buf
   The place in this buffer where we are currently writing.

size_t len
   The length remaining to write.

bool overflowed
   Flag that is set if we try to write past the end of the buffer. If set, the token is not valid.
Chapter 5

Build and Configuration Systems

5.1 Build System (CMake)

CMake is used to build your application together with the Zephyr kernel. A CMake build is done in two stages. The first stage is called configuration. During configuration, the CMakeLists.txt build scripts are executed. After configuration is finished, CMake has an internal model of the Zephyr build, and can generate build scripts that are native to the host platform.

CMake supports generating scripts for several build systems, but only Ninja and Make are tested and supported by Zephyr. After configuration, you begin the build stage by executing the generated build scripts. These build scripts can recompile the application without involving CMake following most code changes. However, after certain changes, the configuration step must be executed again before building. The build scripts can detect some of these situations and reconfigure automatically, but there are cases when this must be done manually.

Zephyr uses CMake's concept of a 'target' to organize the build. A target can be an executable, a library, or a generated file. For application developers, the library target is the most important to understand. All source code that goes into a Zephyr build does so by being included in a library target, even application code.

Library targets have source code, that is added through CMakeLists.txt build scripts like this:

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

In the above CMakeLists.txt, an existing library target named app is configured to include the source file src/main.c. The PRIVATE keyword indicates that we are modifying the internals of how the library is being built. Using the keyword PUBLIC would modify how other libraries that link with app are built. In this case, using PUBLIC would cause libraries that link with app to also include the source file src/main.c, behavior that we surely do not want. The PUBLIC keyword could however be useful when modifying the include paths of a target library.

5.1.1 Build and Configuration Phases

The Zephyr build process can be divided into two main phases: a configuration phase (driven by CMake) and a build phase (driven by Make or Ninja).

Configuration Phase

The configuration phase begins when the user invokes CMake to generate a build system, specifying a source application directory and a board target.
Configuration overview...

*.dts/*.dtsi files

C preprocessor

Preprocessed devicetree...

Bindings (YAML files)

Scripts in scripts/d...

Final devicetree, zephyr.dts

dtc: optional, for warning...

Kconfig can read...

Kconfig files

Scripts in scripts/kconfig...

devicetree_generated.h...

Outputs

autocnf.h

.config

devicetree.h...

Makefile or Ninja file (...

Viewer does not support full SVG 1.1
CMake begins by processing the \texttt{CMakeLists.txt} file in the application directory, which refers to the \texttt{CMakeLists.txt} file in the Zephyr top-level directory, which in turn refers to \texttt{CMakeLists.txt} files throughout the build tree (directly and indirectly). Its primary output is a set of Makefiles or Ninja files to drive the build process, but the CMake scripts also do some processing of their own, which is explained here.

Note that paths beginning with \texttt{build/} below refer to the build directory you create when running CMake.

**Devicetree**

\texttt{*.dts} (\textit{devicetree source}) and \texttt{*.dtsi} (\textit{devicetree source include}) files are collected from the target's architecture, SoC, board, and application directories.

\texttt{*.dtsi} files are included by \texttt{*.dts} files via the C preprocessor (often abbreviated \texttt{cpp}, which should not be confused with C++). The C preprocessor is also used to merge in any devicetree \texttt{*.overlay} files, and to expand macros in \texttt{*.dts}, \texttt{*.dtsi}, and \texttt{*.overlay} files. The preprocessor output is placed in \texttt{build/zephyr/zephyr.dts.pre}.

The preprocessed devicetree sources are parsed by \texttt{gen\_defines.py} to generate a \texttt{build/zephyr/include/generated/devicetree\_generated.h} header with preprocessor macros.

Source code should access preprocessor macros generated from devicetree by including the \texttt{devicetree.h} header, which includes \texttt{devicetree\_generated.h}.

\texttt{gen\_defines.py} also writes the final devicetree to \texttt{build/zephyr/zephyr.dts} in the build directory. This file's contents may be useful for debugging.

If the devicetree compiler \texttt{dtc} is installed, it is run on \texttt{build/zephyr/zephyr.dts} to catch any extra warnings and errors generated by this tool. The output from \texttt{dtc} is unused otherwise, and this step is skipped if \texttt{dtc} is not installed.

The above is just a brief overview. For more information on devicetree, see \textit{Devicetree Guide}.

**Kconfig**

Kconfig files define available configuration options for for the target architecture, SoC, board, and application, as well as dependencies between options.

Kconfig configurations are stored in \textit{configuration files}. The initial configuration is generated by merging configuration fragments from the board and application (e.g. \texttt{prj.conf}).

The output from Kconfig is an \texttt{autoconf.h} header with preprocessor assignments, and a \texttt{.config} file that acts both as a saved configuration and as configuration output (used by CMake). The definitions in \texttt{autoconf.h} are automatically exposed at compile time, so there is no need to include this header.

Information from devicetree is available to Kconfig, through the functions defined in \texttt{kconfigfunctions.py}.

See \textit{the Kconfig section of the manual} for more information.

**Build Phase**

The build phase begins when the user invokes \texttt{make} or \texttt{ninja}. Its ultimate output is a complete Zephyr application in a format suitable for loading/flashign on the desired target board (\texttt{zephyr.elf}, \texttt{zephyr.hex}, etc.) The build phase can be broken down, conceptually, into four stages: the pre-build, first-pass binary, final binary, and post-processing.

**Pre-build**

Pre-build occurs before any source files are compiled, because during this phase header files used by the source files are generated.

**Offset generation**

Access to high-level data structures and members is sometimes required when the definitions of
those structures is not immediately accessible (e.g., assembly language). The generation of `offsets.h` (by `gen_offset_header.py`) facilitates this.

**System call boilerplate**

The `gen_syscall.py` and `parse_syscalls.py` scripts work together to bind potential system call functions with their implementations.

**Intermediate binaries**

Compilation proper begins with the first intermediate binary. Source files (C and assembly) are collected from various subsystems (which ones is decided during the configuration phase), and compiled into archives (with reference to header files in the tree, as well as those generated during the configuration phase and the pre-build stage(s)).

The exact number of intermediate binaries is decided during the configuration phase.

If memory protection is enabled, then:
Partition grouping

The `gen_app_partitions.py` script scans all the generated archives and outputs linker scripts to ensure that application partitions are properly grouped and aligned for the target's memory protection hardware.

Then `cpp` is used to combine linker script fragments from the target's architecture/SoC, the kernel tree, optionally the partition output if memory protection is enabled, and any other fragments selected during the configuration process, into a `linker.cmd` file. The compiled archives are then linked with `ld` as specified in the `linker.cmd`.

Unfixed size binary

The unfixed size intermediate binary is produced when `User Mode` is enabled or `Devicetree` is in use. It produces a binary where sizes are not fixed and thus it may be used by post-process steps that will impact the size of the final binary.

Fixed size binary

The fixed size intermediate binary is produced when `User Mode` is enabled or when generated IRQ tables are used, `CONFIG_GEN_ISR_TABLES` It produces a binary where sizes are fixed and thus the size must not change between the intermediate binary and the final binary.

Intermediate binaries post-processing  The binaries from the previous stage are incomplete, with empty and/or placeholder sections that must be filled in by, essentially, reflection.

To complete the build procedure the following scripts are executed on the intermediate binaries to produce the missing pieces needed for the final binary.

When `User Mode` is enabled:

Partition alignment

The `gen_app_partitions.py` script scans the unfixed size binary and generates an app shared memory aligned linker script snippet where the partitions are sorted in descending order.

When `Devicetree` is used:
Device dependencies
The `gen_handles.py` script scans the unfixed size binary to determine relationships between devices that were recorded from devicetree data, and replaces the encoded relationships with values that are optimized to locate the devices actually present in the application.

When `CONFIG_GEN_ISR_TABLES` is enabled:
The `gen_isr_tables.py` script scant the fixed size binary and creates an `isr_tables.c` source file with a hardware vector table and/or software IRQ table.

When `User Mode` is enabled:
Kernel object hashing
The `gen_kobject_list.py` scans the `ELF DWARF` debug data to find the address of the all kernel objects. This list is passed to `gperf`, which generates a perfect hash function and table of those addresses, then that output is optimized by `process_gperf.py`, using known properties of our special case.

When no intermediate binary post-processing is required then the first intermediate binary will be directly used as the final binary.

Final binary   The binary from the previous stage is incomplete, with empty and/or placeholder sections that must be filled in by, essentially, reflection.
The link from the previous stage is repeated, this time with the missing pieces populated.

Post processing   Finally, if necessary, the completed kernel is converted from `ELF` to the format expected by the loader and/or flash tool required by the target. This is accomplished in a straightforward manner with `objdump`.

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5.1.2 Supporting Scripts and Tools

The following is a detailed description of the scripts used during the build process.

scripts/build/gen_syscalls.py

Script to generate system call invocation macros

This script parses the system call metadata JSON file emitted by parse_syscalls.py to create several files:

- A file containing weak aliases of any potentially unimplemented system calls, as well as the system call dispatch table, which maps system call type IDs to their handler functions.
- A header file defining the system call type IDs, as well as function prototypes for all system call handler functions.
- A directory containing header files. Each header corresponds to a header that was identified as containing system call declarations. These generated headers contain the inline invocation functions for each system call in that header.

scripts/build/gen_handles.py

Translate generic handles into ones optimized for the application.

Immutable device data includes information about dependencies, e.g. that a particular sensor is controlled through a specific I2C bus and that it signals event on a pin on a specific GPIO controller. This information is encoded in the first-pass binary using identifiers derived from the devicetree. This script extracts those identifiers and replaces them with ones optimized for use with the devices actually present.
For example the sensor might have a first-pass handle defined by its devicetree ordinal 52, with the I2C driver having ordinal 24 and the GPIO controller ordinal 14. The runtime ordinal is the index of the corresponding device in the static devicetree array, which might be 6, 5, and 3, respectively.

The output is a C source file that provides alternative definitions for the array contents referenced from the immutable device objects. In the final link these definitions supersede the ones in the driver-specific object file.

scripts/build/gen_kobject_list.py

Script to generate gperf tables of kernel object metadata

User mode threads making system calls reference kernel objects by memory address, as the kernel/driver APIs in Zephyr are the same for both user and supervisor contexts. It is necessary for the kernel to be able to validate accesses to kernel objects to make the following assertions:

• That the memory address points to a kernel object
• The kernel object is of the expected type for the API being invoked
• The kernel object is of the expected initialization state
• The calling thread has sufficient permissions on the object

For more details see the Kernel Objects section in the documentation.

The zephyr build generates an intermediate ELF binary, zephyr_prebuilt.elf, which this script scans looking for kernel objects by examining the DWARF debug information to look for instances of data structures that are considered kernel objects. For device drivers, the API struct pointer populated at build time is also examined to disambiguate between various device driver instances since they are all ‘struct device’.

This script can generate five different output files:

• A gperf script to generate the hash table mapping kernel object memory addresses to kernel object metadata, used to track permissions, object type, initialization state, and any object-specific data.

• A header file containing generated macros for validating driver instances inside the system call handlers for the driver subsystem APIs.

• A code fragment included by kernel.h with one enum constant for each kernel object type and each driver instance.

• The inner cases of a switch/case C statement, included by kernel/userspace.c, mapping the kernel object types and driver instances to their human-readable representation in the otype_to_str() function.

• The inner cases of a switch/case C statement, included by kernel/userspace.c, mapping kernel object types to their sizes. This is used for allocating instances of them at runtime (CONFIG_DYNAMIC_OBJECTS) in the obj_size_get() function.

scripts/build/gen_offset_header.py

This script scans a specified object file and generates a header file that defined macros for the offsets of various found struct type members (particularly symbols ending with _OFFSET or _SIZEOF), primarily intended for use in assembly code.

scripts/build/parse_syscalls.py

Script to scan Zephyr include directories and emit system call and subsystem metadata

System calls require a great deal of boilerplate code in order to implement completely. This script is the first step in the build system's process of auto-generating this code by doing a text scan of directories
containing C or header files, and building up a database of system calls and their function call prototypes. This information is emitted to a generated JSON file for further processing.

This script also scans for struct definitions such as __subsystem and __net_socket, emitting a JSON dictionary mapping tags to all the struct declarations found that were tagged with them.

If the output JSON file already exists, its contents are checked against what information this script would have outputted; if the result is that the file would be unchanged, it is not modified to prevent unnecessary incremental builds.

**arch/x86/gen_idt.py**

Generate Interrupt Descriptor Table for x86 CPUs.

This script generates the interrupt descriptor table (IDT) for x86. Please consult the IA Architecture SW Developer Manual, volume 3, for more details on this data structure.

This script accepts as input the zephyr_prebuilt.elf binary, which is a link of the Zephyr kernel without various build-time generated data structures (such as the IDT) inserted into it. This kernel image has been properly padded such that inserting these data structures will not disturb the memory addresses of other symbols. From the kernel binary we read a special section “intList” which contains the desired interrupt routing configuration for the kernel, populated by instances of the IRQ_CONNECT() macro.

This script outputs three binary tables:

1. The interrupt descriptor table itself.
2. A bitfield indicating which vectors in the IDT are free for installation of dynamic interrupts at runtime.
3. An array which maps configured IRQ lines to their associated vector entries in the IDT, used to program the APIC at runtime.

**arch/x86/gen_gdt.py**

Generate a Global Descriptor Table (GDT) for x86 CPUs.

For additional detail on GDT and x86 memory management, please consult the IA Architecture SW Developer Manual, vol. 3.

This script accepts as input the zephyr_prebuilt.elf binary, which is a link of the Zephyr kernel without various build-time generated data structures (such as the GDT) inserted into it. This kernel image has been properly padded such that inserting these data structures will not disturb the memory addresses of other symbols.

The input kernel ELF binary is used to obtain the following information:

- Memory addresses of the Main and Double Fault TSS structures so GDT descriptors can be created for them
- Memory addresses of where the GDT lives in memory, so that this address can be populated in the GDT pseudo descriptor
- whether userspace or HW stack protection are enabled in Kconfig

The output is a GDT whose contents depend on the kernel configuration. With no memory protection features enabled, we generate flat 32-bit code and data segments. If hardware-based stack overflow protection or userspace is enabled, we additionally create descriptors for the main and double-fault IA tasks, needed for userspace privilege elevation and double-fault handling. If userspace is enabled, we also create flat code/data segments for ring 3 execution.
scripts/build/gen_relocate_app.py

This script will relocate .text, .rodata, .data and .bss sections from required files and places it in the required memory region. This memory region and file are given to this python script in the form of a string.

Example of such a string would be:

```
SRAM2:COPY:/home/xyz/zephyr/samples/hello_world/src/main.c,
SRAM1:COPY:/home/xyz/zephyr/samples/hello_world/src/main2.c, 
FLASH2:NOCOPY:/home/xyz/zephyr/samples/hello_world/src/main3.c
```

One can also specify the program header for a given memory region:

```
SRAM2:\.phdr0:COPY:/home/xyz/zephyr/samples/hello_world/src/main.c
```

To invoke this script:

```
python3 gen_relocate_app.py -i input_string -o generated_linker -c generated_code
```

Configuration that needs to be sent to the python script.

- If the memory is like SRAM1/SRAM2/CCD/AON then place full object in the sections
- If the memory type is appended with _DATA / _TEXT/ _RODATA/ _BSS only the selected memory is placed in the required memory region. Others are ignored.
- COPY/NOCOPY defines whether the script should generate the relocation code in code_relocation.c or not

Multiple regions can be appended together like SRAM2_DATA_BSS this will place data and bss inside SRAM2.

scripts/build/process_gperf.py

gperf C file post-processor

We use gperf to build up a perfect hashtable of pointer values. The way gperf does this is to create a table ‘wordlist’ indexed by a string representation of a pointer address, and then doing memcmp() on a string passed in for comparison

We are exclusively working with 4-byte pointer values. This script adjusts the generated code so that we work with pointers directly and not strings. This saves a considerable amount of space.

scripts/build/gen_app_partitions.py

Script to generate a linker script organizing application memory partitions

Applications may declare build-time memory domain partitions with K_APPMEM_PARTITION_DEFINE, and assign globals to them using K_APP_DMEM or K_APP_BMEM macros. For each of these partitions, we need to route all their data into appropriately-sized memory areas which meet the size/alignment constraints of the memory protection hardware.

This linker script is created very early in the build process, before the build attempts to link the kernel binary, as the linker script this tool generates is a necessary pre-condition for kernel linking. We extract the set of memory partitions to generate by looking for variables which have been assigned to input sections that follow a defined naming convention. We also allow entire libraries to be pulled in to assign their globals to a particular memory partition via command line directives.

This script takes as inputs:

- The base directory to look for compiled objects
- key/value pairs mapping static library files to what partitions their globals should end up in.
The output is a linker script fragment containing the definition of the app shared memory section, which is further divided, for each partition found, into data and BSS for each partition.

5.2 Devicetree

A devicetree is a hierarchical data structure primarily used to describe hardware. Zephyr uses devicetree in two main ways:

- to describe hardware to the Device Driver Model
- to provide that hardware's initial configuration

This page links to a high level guide on devicetree as well as reference material.

5.2.1 Devicetree Guide

The pages in this section are a high-level guide to using devicetree for Zephyr development.

Introduction to devicetree

Tip: This is a conceptual overview of devicetree and how Zephyr uses it. For step-by-step guides and examples, see Devicetree HOWTOs.

A devicetree is a hierarchical data structure that describes hardware. The Devicetree specification defines its source and binary representations. Zephyr uses devicetree to describe the hardware available on its boards, as well as that hardware's initial configuration.

There are two types of devicetree input files: devicetree sources and devicetree bindings. The sources contain the devicetree itself. The bindings describe its contents, including data types. The build system uses devicetree sources and bindings to produce a generated C header. The generated header's contents are abstracted by the devicetree.h API, which you can use to get information from your devicetree.

Here is a simplified view of the process:

Fig. 5.1: Devicetree build flow

All Zephyr and application source code files can include and use devicetree.h. This includes device drivers, applications, tests, the kernel, etc.

The API itself is based on C macros. The macro names all start with DT_. In general, if you see a macro that starts with DT_ in a Zephyr source file, it's probably a devicetree.h macro. The generated C header contains macros that start with DT_ as well; you might see those in compiler error messages. You always can tell a generated- from a non-generated macro: generated macros have some lowercased letters, while the devicetree.h macro names have all capital letters.
Some information defined in devicetree is available via CONFIG_ macros generated from Kconfig. This is often done for backwards compatibility, since Zephyr has used Kconfig for longer than devicetree, and is still in the process of converting some information from Kconfig to devicetree. It is also done to allow Kconfig overrides of default values taken from devicetree. Devicetree information is referenced from Kconfig via Kconfig functions. See Devicetree versus Kconfig for some additional comparisons with Kconfig.

Syntax and structure  As the name indicates, a devicetree is a tree. The human-readable text format for this tree is called DTS (for devicetree source), and is defined in the Devicetree specification. Here is an example DTS file:

```
/dts-v1/
/
  a-node {
    subnode_nodelabel: a-sub-node {
      foo = <3>;
    };
  }

```
The /dts-v1/; line means the file's contents are in version 1 of the DTS syntax, which has replaced a now-obsolete “version 0”.

The tree has three nodes:

1. A root node: /
2. A node named a-node, which is a child of the root node
3. A node named a-sub-node, which is a child of a-node

Nodes can be assigned node labels, which are unique shorthands that can be used to refer to the labeled node elsewhere in the devicetree. Above, a-sub-node has the node label subnode_nodelabel, which can be accessed via DT_NODELABEL(subnode_nodelabel). A node can have zero, one, or multiple node labels.

Devicetree nodes have paths identifying their locations in the tree. Like Unix file system paths, devicetree paths are strings separated by slashes (/), and the root node's path is a single slash: /. Otherwise, each node's path is formed by concatenating the node's ancestors' names with the node's own name, separated by slashes. For example, the full path to a-sub-node is /a-node/a-sub-node.

Devicetree nodes can also have properties. Properties are name/value pairs. Property values can be any sequence of bytes. In some cases, the values are an array of what are called cells. A cell is just a 32-bit unsigned integer.

Node a-sub-node has a property named foo, whose value is a cell with value 3. The size and type of foo's value are implied by the enclosing angle brackets (< and >) in the DTS.

See Writing property values below for more example property values.

In practice, devicetree nodes usually correspond to some hardware, and the node hierarchy reflects the hardware's physical layout. For example, let's consider a board with three I2C peripherals connected to an I2C bus controller on an SoC, like this:

Nodes corresponding to the I2C bus controller and each I2C peripheral would be present in the devicetree. Reflecting the hardware layout, the I2C peripheral nodes would be children of the bus controller node. Similar conventions exist for representing other types of hardware.

The DTS would look something like this:
Properties are used in practice to describe or configure the hardware the node represents. For example, an I2C peripheral's node has a property whose value is the peripheral's address on the bus.

Here's a tree representing the same example, but with real-world node names and properties you might see when working with I2C devices.

This is the corresponding DTS:

```
/dts-v1/
/
{
  soc {
    i2c@40003000 {
      i2c-peripheral-1 {
      }
      i2c-peripheral-2 {
      }
      i2c-peripheral-3 {
      }
    }
  }
};

apds9960@39 {
  compatible = "avago,apds9960";
  reg = <0x39>;
};
ti_hdc@43 {
  compatible = "ti,hdc", "ti,hdc1010";
  reg = <0x43>;
}
```
In addition to showing more realistic names and properties, the above example introduces a new devicetree concept: unit addresses. Unit addresses are the parts of node names after an "at" sign (@), like 40003000 in i2c@40003000, or 39 in apds9960@39. Unit addresses are optional: the soc node does not have one.

Some more details about unit addresses and important properties follow.

**Unit address examples**  In devicetree, unit addresses give a node’s address in the address space of its parent node. Here are some example unit addresses for different types of hardware.

**Memory-mapped peripherals**

The peripheral’s register map base address. For example, the node named i2c@40003000 represents an I2C controller whose register map base address is 0x40003000.

**I2C peripherals**

The peripheral’s address on the I2C bus. For example, the child node apds9960@39 of the I2C controller in the previous section has I2C address 0x39.

**SPI peripherals**

An index representing the peripheral’s chip select line number. (If there is no chip select line, 0 is
Memory
The physical start address. For example, a node named `memory@2000000` represents RAM starting at physical address 0x2000000.

Memory-mapped flash
Like RAM, the physical start address. For example, a node named `flash@8000000` represents a flash device whose physical start address is 0x8000000.

Fixed flash partitions
This applies when the devicetree is used to store a flash partition table. The unit address is the partition’s start offset within the flash memory. For example, take this flash device and its partitions:

```c
flash@8000000 {
    /* ... */
    partitions {
        partition@0 { /* ... */ };
        partition@20000 { /* ... */ };
        /* ... */
    };
}
```

The node named `partition@0` has offset 0 from the start of its flash device, so its base address is 0x8000000. Similarly, the base address of the node named `partition@20000` is 0x8020000.

Important properties
Some important properties are:

compatible
The name of the hardware device the node represents.

The recommended format is "vendor,device", like "avago,apds9960", or a sequence of these, like "ti,hdc", "ti,hdc1010". The vendor part is an abbreviated name of the vendor. The file `dts/bindings/vendor-prefixes.txt` contains a list of commonly accepted vendor names. The device part is usually taken from the datasheet.

It is also sometimes a value like `gpio-keys`, `mmio-sram`, or `fixed-clock` when the hardware’s behavior is generic.

The build system uses the compatible property to find the right bindings for the node. Device drivers use `devicetree.h` to find nodes with relevant compatibles, in order to determine the available hardware to manage.

The compatible property can have multiple values. Additional values are useful when the device is a specific instance of a more general family, to allow the system to match from most- to least-specific device drivers.

Within Zephyr’s bindings syntax, this property has type `string-array`.

reg
Information used to address the device. The value is specific to the device (i.e. is different depending on the compatible property).

The reg property is a sequence of `(address, length)` pairs. Each pair is called a “register block”. Here are some common patterns:

- Devices accessed via memory-mapped I/O registers (like `i2c@40003000`): `address` is usually the base address of the I/O register space, and `length` is the number of bytes occupied by the registers.
- I2C devices (like `apds9960@39` and its siblings): `address` is a slave address on the I2C bus. There is no `length` value.
- SPI devices: `address` is a chip select line number; there is no `length`.

5.2. Devicetree
You may notice some similarities between the `reg` property and common unit addresses described above. This is not a coincidence. The `reg` property can be seen as a more detailed view of the addressable resources within a device than its unit address.

**status**

A string which describes whether the node is enabled.

The devicetree specification allows this property to have values "okay", "disabled", "reserved", "fail", and "fail-sss". Only the values "okay" and "disabled" are currently relevant to Zephyr; use of other values currently results in undefined behavior.

A node is considered enabled if its status property is either "okay" or not defined (i.e. does not exist in the devicetree source). Nodes with status "disabled" are explicitly disabled. (For backwards compatibility, the value "ok" is treated the same as "okay", but this usage is deprecated.) Device-tree nodes which correspond to physical devices must be enabled for the corresponding `struct device` in the Zephyr driver model to be allocated and initialized.

**interrupts**

Information about interrupts generated by the device, encoded as an array of one or more `interrupt specifiers`. Each interrupt specifier has some number of cells. See section 2.4, `Interrupts and Interrupt Mapping`, in the Devicetree Specification release v0.3 for more details.

Zephyr's devicetree bindings language lets you give a name to each cell in an interrupt specifier.

---

**Note:** Earlier versions of Zephyr made frequent use of the `label` property, which is distinct from the standard `node label`. Use of the label `property` in new devicetree bindings, as well as use of the `DT_LABEL` macro in new code, are actively discouraged. Label properties continue to persist for historical reasons in some existing bindings and overlays, but should not be used in new bindings or device implementations.

---

**Writing property values**

This section describes how to write property values in DTS format. The property types in the table below are described in detail in `Devicetree bindings`.

Some specifics are skipped in the interest of keeping things simple; if you're curious about details, see the devicetree specification.

<table>
<thead>
<tr>
<th>Property type</th>
<th>How to write</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>string</td>
<td>Double quoted</td>
<td><code>a-string = &quot;hello, world!&quot;;</code></td>
</tr>
<tr>
<td>int</td>
<td>Between angle brackets (<code>&lt;</code> and <code>&gt;</code>)</td>
<td><code>an-int = &lt;1&gt;;</code></td>
</tr>
<tr>
<td>boolean</td>
<td>For <code>true</code>, with no value (for <code>false</code>, use <code>/delete-property/</code>)</td>
<td><code>my-true-boolean;</code></td>
</tr>
<tr>
<td>array</td>
<td>Between angle brackets (<code>&lt;</code> and <code>&gt;</code>) separated by spaces</td>
<td><code>foo = &lt;0xdeadbeef 1234 0&gt;;</code></td>
</tr>
<tr>
<td>uint8-array</td>
<td>In hexadecimal without leading 0x, between square brackets ([ and ]).</td>
<td><code>a-byte-array = [00 01 ab];</code></td>
</tr>
<tr>
<td>string-array</td>
<td>Separated by commas</td>
<td><code>a-string-array = &quot;string one&quot;, &quot;string two&quot;, &quot;string three&quot;;</code></td>
</tr>
<tr>
<td>phandle</td>
<td>Between angle brackets (<code>&lt;</code> and <code>&gt;</code>)</td>
<td><code>a-phandle = &lt;&amp;mynode&gt;;</code></td>
</tr>
<tr>
<td>handles</td>
<td>Between angle brackets (<code>&lt;</code> and <code>&gt;</code>) separated by spaces</td>
<td><code>some-handles = &lt;&amp;mynode0 &amp;mynode1 &amp;mynode2&gt;;</code></td>
</tr>
<tr>
<td>handle-array</td>
<td>Between angle brackets (<code>&lt;</code> and <code>&gt;</code>) separated by spaces</td>
<td><code>a-handle-array = &lt;&amp;mynode0 1 2 &amp;mynode1 3 4&gt;;</code></td>
</tr>
</tbody>
</table>

Additional notes on the above:

- Boolean properties are true if present. They should not have a value. A boolean property is only false if it is completely missing in the DTS.
• The `foo` property value above has three cells with values `0xdeadbeef`, `1234`, and `0`, in that order. Note that hexadecimal and decimal numbers are allowed and can be intermixed. Since Zephyr transforms DTS to C sources, it is not necessary to specify the endianness of an individual cell here.

• 64-bit integers are written as two 32-bit cells in big-endian order. The value `0xaaaa0000babb1111` would be written `<0xaaaa0000 0xbabb1111>`.

• The `a-byte-array` property value is the three bytes `0x00`, `0x01`, and `0xab`, in that order.

• Parentheses, arithmetic operators, and bitwise operators are allowed. The `bar` property contains a single cell with value 64:

```
bar = <(2 * (1 << 5))>;  
```

Note that the entire expression must be parenthesized.

• Property values refer to other nodes in the devicetree by their phandles. You can write a phandle using `&foo`, where `foo` is a node label. Here is an example devicetree fragment:

```
foo: device@0 { };  
device@1 {  
    sibling = <&foo 1 2>;  
};  
```

The `sibling` property of node `device@1` contains three cells, in this order:

1. The `device@0` node's phandle, which is written here as `&foo` since the `device@0` node has a node label `foo`
2. The value 1
3. The value 2

In the devicetree, a phandle value is a cell – which again is just a 32-bit unsigned int. However, the Zephyr devicetree API generally exposes these values as node identifiers. Node identifiers are covered in more detail in Devicetree access from C/C++.

• Array and similar type property values can be split into several `<>` blocks, like this:

```
foo = <1 2>, <3 4>;  // Okay for 'type: array'
foo = <&label1 &label2>, <&label3 &label4>;  // Okay for 'type: phandles'
foo = <&label1 1 2>, <&label2 3 4>;  // Okay for 'type: phandle-array'
```

This is recommended for readability when possible if the value can be logically grouped into blocks of sub-values.

Aliases and chosen nodes  There are two additional ways beyond node labels to refer to a particular node without specifying its entire path: by alias, or by chosen node.

Here is an example devicetree which uses both:

```
/dts-v1/;  
/ {  
    chosen {  
        zephyr,console = &uart0;  
    };  
    aliases {  
        my-uart = &uart0;  
    };  
    soc {  
```

(continues on next page)
The /aliases and /chosen nodes do not refer to an actual hardware device. Their purpose is to specify other nodes in the devicetree.

Above, my-uart is an alias for the node with path /soc/serial@12340000. Using its node label uart0, the same node is set as the value of the chosen zephyr,console node.

Zephyr sample applications sometimes use aliases to allow overriding the particular hardware device used by the application in a generic way. For example, blinky-sample uses this to abstract the LED to blink via the led0 alias.

The /chosen node’s properties are used to configure system- or subsystem-wide values. See Chosen nodes for more information.

**Input and output files** This section describes the input and output files shown in the figure at the top of this introduction in more detail.

![Devicetree input (green) and output (yellow) files](image)

**Input files** There are four types of devicetree input files:
The devicetree files inside the `zephyr` directory look like this:

```
boards/<ARCH>/<BOARD>/<BOARD>.dts
dts/common/skeleton.dtsi
dts/<ARCH>/*/*<SOC>.dtsi
dts/bindings/*/*/binding.yaml
```

Generally speaking, every supported board has a `BOARD.dts` file describing its hardware. For example, the `reel_board` has `boards/arm/reel_board/reel_board.dts`.

`BOARD.dts` includes one or more `.dtsi` files. These `.dtsi` files describe the CPU or system-on-chip Zephyr runs on, perhaps by including other `.dtsi` files. They can also describe other common hardware features shared by multiple boards. In addition to these includes, `BOARD.dts` also describes the board’s specific hardware.

The `dts/common` directory contains `skeleton.dtsi`, a minimal include file for defining a complete devicetree. Architecture-specific subdirectories (`dts/<ARCH>`) contain `.dtsi` files for CPUs or SoCs which extend `skeleton.dtsi`.

The C preprocessor is run on all devicetree files to expand macro references, and includes are generally done with `#include <filename>` directives, even though DTS has a `/include/ "<filename>"` syntax.

`BOARD.dts` can be extended or modified using `overlays`. Overlays are also DTS files; the `.overlay` extension is just a convention which makes their purpose clear. Overlays adapt the base devicetree for different purposes:

- Zephyr applications can use overlays to enable a peripheral that is disabled by default, select a sensor on the board for an application specific purpose, etc. Along with `Configuration System (Kconfig)`, this makes it possible to reconfigure the kernel and device drivers without modifying source code.

- Overlays are also used when defining `Shields`.

The build system automatically picks up `.overlay` files stored in certain locations. It is also possible to explicitly list the overlays to include, via the `DTC_OVERLAY_FILE` CMake variable. See `Set devicetree overlays` for details.

The build system combines `BOARD.dts` and any `.overlay` files by concatenating them, with the overlays put last. This relies on DTS syntax which allows merging overlapping definitions of nodes in the devicetree. See `Example: FRDM-K64F and Hexiwear K64` for an example of how this works (in the context of `.dtsi` files, but the principle is the same for overlays). Putting the contents of the `.overlay` files last allows them to override `BOARD.dts`.

`Devicetree bindings` (which are YAML files) are essentially glue. They describe the contents of devicetree sources, includes, and overlays in a way that allows the build system to generate C macros usable by device drivers and applications. The `dts/bindings` directory contains bindings.

**Scripts and tools** The following libraries and scripts, located in `scripts/dts/`, create output files from input files. Their sources have extensive documentation.

- `dtlib.py` A low-level DTS parsing library.
- `edtlib.py` A library layered on top of dtlib that uses bindings to interpret properties and give a higher-level view of the devicetree. Uses dtlib to do the DTS parsing.
gen_defines.py
A script that uses edtlib to generate C preprocessor macros from the devicetree and bindings.

In addition to these, the standard dtc (devicetree compiler) tool is run on the final devicetree if it is installed on your system. This is just to catch errors or warnings. The output is unused. Boards may need to pass dtc additional flags, e.g. for warning suppression. Board directories can contain a file named pre_dt_board.cmake which configures these extra flags, like this:

```bash
list(APPEND EXTRA_DTC_FLAGS "-Wno-simple_bus_reg")
```

Output files These are created in your application’s build directory.

**Warning:** Don’t include the header files directly. *Devicetree access from C/C++ explains what to do instead.*

<build>/zephyr/zephyr.dts.pre
The preprocessed DTS source. This is an intermediate output file, which is input to gen_defines.py and used to create zephyr.dts and devicetree_generated.h.

<build>/zephyr/include/generated/devicetree_generated.h
The generated macros and additional comments describing the devicetree. Included by devicetree.h.

<build>/zephyr/zephyr.dts
The final merged devicetree. This file is output by gen_defines.py. It is useful for debugging any issues. If the devicetree compiler dtc is installed, it is also run on this file, to catch any additional warnings or errors.

Design goals

Zephyr’s use of devicetree has evolved significantly over time, and further changes are expected. The following are the general design goals, along with specific examples about how they impact Zephyr’s source code, and areas where more work remains to be done.

**Single source for all hardware information** Zephyr shall obtain its hardware descriptions exclusively from devicetree.

**Examples**

- New device drivers shall use devicetree APIs to determine which devices to create if possible.
- In-tree sample applications shall use aliases to determine which of multiple possible generic devices of a given type will be used in the current build. For example, the blinky-sample uses this to determine the LED to blink.
- Boot-time pin muxing and pin control can be accomplished via devicetree.

**Example remaining work**

- Zephyr’s Test Runner (Twister) currently use board.yaml files to determine the hardware supported by a board. This should be obtained from devicetree instead.
- Various device drivers currently use Kconfig to determine which instances of a particular compatible are enabled. This can and should be done with devicetree overlays instead.
- Board-level documentation still contains tables of hardware support which are generated and maintained by hand. This can and should be obtained from the board level devicetree instead.
• Runtime determination of \texttt{struct device} relationships should be done using information obtained from devicetree, e.g. for device power management.

**Source compatibility with other operating systems**  Zephyr’s devicetree tooling is based on a generic layer which is interoperable with other devicetree users, such as the Linux kernel. Zephyr’s binding language \textit{semantics} can support Zephyr-specific attributes, but shall not express Zephyr-specific relationships.

**Examples**

• Zephyr’s devicetree source parser, \texttt{dtlib.py}, is source-compatible with other tools like \texttt{dtc} in both directions: \texttt{dtlib.py} can parse \texttt{dtc} output, and \texttt{dtc} can parse \texttt{dtlib.py} output.

• Zephyr’s “extended dtlib” library, \texttt{edtlib.py}, shall not include Zephyr-specific features. Its purpose is to provide a higher-level view of the devicetree for common elements like interrupts and buses. Only the high-level \texttt{gen_defines.py} script, which is built on top of \texttt{edtlib.py}, contains Zephyr-specific knowledge and features.

**Example remaining work**

• Zephyr has a custom \textit{Devicetree bindings} language \textit{syntax}. While Linux’s \texttt{dtschema} does not yet meet Zephyr’s needs, we should try to follow what it is capable of representing in Zephyr’s own bindings.

• Due to inflexibility in the bindings language, Zephyr cannot support the full set of bindings supported by Linux.

• Devicetree source sharing between Zephyr and Linux is not done.

**Devicetree bindings**

A devicetree on its own is only half the story for describing hardware, as it is a relatively unstructured format. \textit{Devicetree bindings} provide the other half.

A devicetree binding declares requirements on the contents of nodes, and provides semantic information about the contents of valid nodes. Zephyr devicetree bindings are YAML files in a custom format (Zephyr does not use the dt-schema tools used by the Linux kernel).

This page introduces bindings, describes what they do, notes where they are found, and explains their data format.

\textbf{Note:}  See the \textit{Bindings index} for reference information on bindings built in to Zephyr.
Properties

Child-binding

Bus

On-bus

Specifier cell names (*-cells)

Include

Rules for mainline bindings

- Always check for existing bindings

- General rules

- Rules for vendor prefixes

- Rules for default values

Inferred bindings

Introduction

Devicetree nodes are matched to bindings using their compatible properties.

During the Configuration Phase, the build system tries to match each node in the devicetree to a binding file. When this succeeds, the build system uses the information in the binding file both when validating the node's contents and when generating macros for the node.

A simple example

Here is an example devicetree node:

```c
/* Node in a DTS file */
bar-device {
    compatible = "foo-company,bar-device";
    num-foos = <3>;
};
```

Here is a minimal binding file which matches the node:

```
# A YAML binding matching the node

compatible: "foo-company,bar-device"

properties:
    num-foos:
        type: int
        required: true
```

The build system matches the bar-device node to its YAML binding because the node's compatible property matches the binding's compatible: line.

What the build system does with bindings

The build system uses bindings both to validate devicetree nodes and to convert the devicetree's contents into the generated devicetree_generated.h header file.

For example, the build system would use the above binding to check that the required num-foos property is present in the bar-device node, and that its value, <3>, has the correct type.

The build system will then generate a macro for the bar-device node's num-foos property, which will expand to the integer literal 3. This macro lets you get the value of the property in C code using the API which is discussed later in this guide in Devicetree access from C/C++.
For another example, the following node would cause a build error, because it has no `num-foos` property, and this property is marked required in the binding:

```yaml
bad-node {
    compatible = "foo-company,bar-device";
};
```

**Other ways nodes are matched to bindings** If a node has more than one string in its `compatible` property, the build system looks for compatible bindings in the listed order and uses the first match. Take this node as an example:

```yaml
baz-device {
    compatible = "foo-company,baz-device", "generic-baz-device";
};
```

The `baz-device` node would get matched to a binding with a `compatible: "generic-baz-device"` line if the build system can't find a binding with a `compatible: "foo-company,baz-device"` line.

Nodes without compatible properties can be matched to bindings associated with their parent nodes. These are called "child bindings". If a node describes hardware on a bus, like I2C or SPI, then the bus type is also taken into account when matching nodes to bindings. (The Bindings file syntax section below describes how to write child bindings and bus-specific bindings.)

Some special nodes without compatible properties are matched to **Inferred bindings**. For these nodes, the build system generates macros based on the properties in the final devicetree.

**Where bindings are located** Binding file names usually match their `compatible:` lines. For example, the above example binding would be named `foo-company,bar-device.yaml` by convention.

The build system looks for bindings in `dts/bindings` subdirectories of the following places:

- the zephyr repository
- your application source directory
- your board directory
- any directories in the `DTS_ROOT` CMake variable
- any module that defines a `dts_root` in its `Build settings`

The build system will consider any YAML file in any of these, including in any subdirectories, when matching nodes to bindings. A file is considered YAML if its name ends with `.yaml` or `.yml`.

**Warning:** The binding files must be located somewhere inside the `dts/bindings` subdirectory of the above places.

For example, if `my-app` is your application directory, then you must place application-specific bindings inside `my-app/dts/bindings`. So `my-app/dts/bindings/serial/my-company,my-serial-port.yaml` would be found, but `my-app/my-company,my-serial-port.yaml` would be ignored.

**Bindings file syntax** Zephyr bindings files are YAML files. The top-level value in the file is a mapping. A simple example is given above.

The top-level keys in the mapping look like this:

```yaml
# A high level description of the device the binding applies to:
description: |
    This is the Vendomatic company's foo-device.
```

(continues on next page)
Descriptions which span multiple lines (like this) are OK, and are encouraged for complex bindings.

See https://yaml-multiline.info/ for formatting help.

# You can include definitions from other bindings using this syntax:
include: other.yaml

# Used to match nodes to this binding as discussed above:
compatible: "manufacturer,foo-device"

properties:
  # Requirements for and descriptions of the properties that this
  # binding's nodes need to satisfy go here.

child-binding:
  # You can constrain the children of the nodes matching this binding
  # using this key.

  # If the node describes bus hardware, like an SPI bus controller
  # on an SoC, use 'bus:' to say which one, like this:
  bus: spi

  # If the node instead appears as a device on a bus, like an external
  # SPI memory chip, use 'on-bus:' to say what type of bus, like this.
  # Like 'compatible', this key also influences the way nodes match
  # bindings.
  on-bus: spi

foo-cells:
  # "Specifier" cell names for the 'foo' domain go here; example 'foo'
  # values are 'gpio', 'pwm', and 'dma'. See below for more information.

The following sections describe these keys in more detail:

- Description
- Compatible
- Properties
- Child-binding
- Bus
- On-bus
- Specifier cell names (*-cells)
- Include

The `include:` key usually appears early in the binding file, but it is documented last here because you need to know how the other keys work before understanding `include:`.

**Description** A free-form description of node hardware goes here. You can put links to datasheets or example nodes or properties as well.

**Compatible** This key is used to match nodes to this binding as described above. It should look like this in a binding file:
# Note the comma-separated vendor prefix and device name
compatible: "manufacturer,device"

This devicetree node would match the above binding:

device {
    compatible = "manufacturer,device";
};

Assuming no binding has compatible: "manufacturer,device-v2", it would also match this node:

device-2 {
    compatible = "manufacturer,device-v2", "manufacturer,device";
};

Each node's compatible property is tried in order. The first matching binding is used. The on-bus: key can be used to refine the search.

If more than one binding for a compatible is found, an error is raised.

The manufacturer prefix identifies the device vendor. See dts/bindings/vendor-prefixes.txt for a list of accepted vendor prefixes. The device part is usually from the datasheet.

Some bindings apply to a generic class of devices which do not have a specific vendor. In these cases, there is no vendor prefix. One example is the gpio-leds compatible which is commonly used to describe board LEDs connected to GPIOs.

If more than one binding for a compatible is found, an error is raised.

**Properties**

The properties: key describes the properties that nodes which match the binding can contain.

For example, a binding for a UART peripheral might look something like this:

compatible: "manufacturer,serial"

properties:
    reg:
        type: array
description: UART peripheral MMIO register space
required: true
current-speed:
    type: int
description: current baud rate
required: true

The properties in the following node would be validated by the above binding:

my-serial@deadbeef {
    compatible = "manufacturer,serial";
    reg = <0xdeadbeef 0x1000>;
    current-speed = <115200>;
};

This is used to check that required properties appear, and to control the format of output generated for them.

Except for some special properties, like reg, whose meaning is defined by the devicetree specification itself, only properties listed in the properties: key will have generated macros.

5.2. Devicetree
Example property definitions  Here are some more examples.

properties:
  # Describes a property like 'current-speed = <115200>;'. We pretend that
  # it's obligatory for the example node and set 'required: true'.
  current-speed:
    type: int
    required: true
    description: Initial baud rate for bar-device

  # Describes an optional property like 'keys = "foo", "bar";'
  keys:
    type: string-array
    description: Keys for bar-device

  # Describes an optional property like 'maximum-speed = "full-speed";
  # the enum specifies known values that the string property may take
  maximum-speed:
    type: string
    description: Configures USB controllers to work up to a specific speed.
    enum:
      - "low-speed"
      - "full-speed"
      - "high-speed"
      - "super-speed"

  # Describes an optional property like 'resolution = <16>;'
  # the enum specifies known values that the int property may take
  resolution:
    type: int
    enum:
      - 8
      - 16
      - 24
      - 32

  # Describes a required property '#address-cells = <1>'; the const
  # specifies that the value for the property is expected to be the value 1
  "#address-cells":
    type: int
    required: true
    const: 1

  int-with-default:
    type: int
    default: 123
    description: Value for int register, default is power-up configuration.

  array-with-default:
    type: array
    default: [1, 2, 3]
    description: Same as 'array-with-default = <1 2 3>,'

  string-with-default:
    type: string
    default: "foo"

  string-array-with-default:
    type: string-array
Property entry syntax  As shown by the above examples, each property entry in a binding looks like this:

```
<property name>:
  required: <true | false>
  type: <string | int | boolean | array | uint8-array | string-array | phandle | phandles | phandle-array | path | compound>
  deprecated: <true | false>
  default: <default>
  description: <description of the property>
  enum:
    - <item1>
    - <item2>
    ...
    - <itemN>
  const: <string | int | array | uint8-array | string-array
```

Required properties  If a node matches a binding but is missing any property which the binding defines with `required: true`, the build fails.

Note: A property is implicitly optional unless `required: true` is specified. Using `required: false` is therefore redundant and strongly discouraged.

Property types  The type of a property constrains its values. The following types are available. See Writing property values for more details about writing values of each type in a DTS file.

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
<th>Example in DTS</th>
</tr>
</thead>
<tbody>
<tr>
<td>string</td>
<td>exactly one string</td>
<td>status = &quot;disabled&quot;;</td>
</tr>
<tr>
<td>int</td>
<td>exactly one 32-bit value (cell)</td>
<td>current-speed = &lt;115200&gt;;</td>
</tr>
<tr>
<td>boolean</td>
<td>flags that don't take a value when true, and are absent if false</td>
<td>hw-flow-control;</td>
</tr>
<tr>
<td>array</td>
<td>zero or more 32-bit values (cells)</td>
<td>offsets = &lt;0x100 0x200 0x300&gt;;</td>
</tr>
<tr>
<td>uint8-array</td>
<td>zero or more bytes, in hex ('bytestring' in the Devicetree specification)</td>
<td>local-mac-address = [de ad be ef 12 34];</td>
</tr>
<tr>
<td>string-array</td>
<td>zero or more strings</td>
<td>dma-names = &quot;tx&quot;, &quot;rx&quot;;</td>
</tr>
<tr>
<td>phandle</td>
<td>exactly one phandle</td>
<td>interrupt-parent = &amp;gic;</td>
</tr>
<tr>
<td>phandles</td>
<td>zero or more phandles</td>
<td>pinctrl-0 = &amp;usart2_tx_pd5 &amp;usart2_rx_pd6;</td>
</tr>
<tr>
<td>phandle-array</td>
<td>a list of phandles and 32-bit cells (usually specifiers)</td>
<td>dmas = &amp;dma0 2, &amp;dma0 3;</td>
</tr>
<tr>
<td>path</td>
<td>a path to a node as a phandle path reference or path string</td>
<td>zephyr,bt-c2h-uart = &amp;uart0; or foo = &quot;/path/to/some/node&quot;;</td>
</tr>
<tr>
<td>compound</td>
<td>a catch-all for more complex types (no macros will be generated)</td>
<td>foo = &amp;label, [01 02];</td>
</tr>
</tbody>
</table>
**Deprecated properties**  A property with `deprecated: true` indicates to both the user and the tooling that the property is meant to be phased out.

The tooling will report a warning if the devicetree includes the property that is flagged as deprecated. (This warning is upgraded to an error in the Test Runner (Twister) for upstream pull requests.)

**Default values for properties**  The optional `default:` setting gives a value that will be used if the property is missing from the devicetree node.

For example, with this binding fragment:

```yaml
properties:
  foo:
    type: int
    default: 3
```

If property `foo` is missing in a matching node, then the output will be as if `foo = <3>;` had appeared in the DTS (except YAML data types are used for the default value).

Note that combining `default:` with `required: true` will raise an error.

For rules related to `default` in upstream Zephyr bindings, see [Rules for default values](#).

See [Example property definitions](#) for examples. Putting `default:` on any property type besides those used in the examples will raise an error.

**Enum values**  The `enum:` line is followed by a list of values the property may contain. If a property value in DTS is not in the `enum:` list in the binding, an error is raised. See [Example property definitions](#) for examples.

**Const**  This specifies a constant value the property must take. It is mainly useful for constraining the values of common properties for a particular piece of hardware.

**Child-binding**  `child-binding` can be used when a node has children that all share the same properties. Each child gets the contents of `child-binding` as its binding, though an explicit `compatible = ...` on the child node takes precedence, if a binding is found for it.

Consider a binding for a PWM LED node like this one, where the child nodes are required to have a `pwms` property:

```yaml
pwmleds {
  compatible = "pwm-leds";

  red_pwmLed {
    pwms = <&pwm3 4 15625000>;
  };

  green_pwmLed {
    pwms = <&pwm3 0 15625000>;
  };
  /* ... */
}
```

The binding would look like this:

```yaml
compatible: "pwm-leds"

child-binding:
  description: LED that uses PWM
```

(continues on next page)
child-binding also works recursively. For example, this binding:

```yaml
compatible: foo

child-binding:
  child-binding:
    properties:
      my-property:
        type: int
        required: true
```

will apply to the grandchild node in this DTS:

```yaml
parent {
  compatible = "foo";
  child {
    grandchild {
      my-property = <123>;
    };
  };
};
```

**Bus**  If the node is a bus controller, use `bus:` in the binding to say what type of bus. For example, a binding for a SPI peripheral on an SoC would look like this:

```yaml
compatible: "manufacturer,spi-peripheral"
bus: spi
# ...
```

The presence of this key in the binding informs the build system that the children of any node matching this binding appear on this type of bus.

This in turn influences the way `on-bus:` is used to match bindings for the child nodes.

For a single bus supporting multiple protocols, e.g. I3C and I2C, the `bus:` in the binding can have a list as value:

```yaml
compatible: "manufacturer,i3c-controller"
bus: [i3c, i2c]
# ...
```

**On-bus**  If the node appears as a device on a bus, use `on-bus:` in the binding to say what type of bus. For example, a binding for an external SPI memory chip should include this line:

```yaml
on-bus: spi
```

And a binding for an I2C based temperature sensor should include this line:

```yaml
on-bus: i2c
```
When looking for a binding for a node, the build system checks if the binding for the parent node contains `bus: <bus type>`. If it does, then only bindings with a matching `on-bus: <bus type>` and bindings without an explicit `on-bus` are considered. Bindings with an explicit `on-bus: <bus type>` are searched for first, before bindings without an explicit `on-bus`. The search repeats for each item in the node's `compatible` property, in order.

This feature allows the same device to have different bindings depending on what bus it appears on. For example, consider a sensor device with compatible `manufacturer,sensor` which can be used via either I2C or SPI.

The sensor node may therefore appear in the devicetree as a child node of either an SPI or an I2C controller, like this:

```plaintext
spi-bus@0 {
    /* ... some compatible with 'bus: spi', etc. ... */

    sensor@0 {
        compatible = "manufacturer,sensor";
        reg = <0>;
    }/* ... */
};

i2c-bus@0 {
    /* ... some compatible with 'bus: i2c', etc. ... */

    sensor@79 {
        compatible = "manufacturer,sensor";
        reg = <79>;
    }/* ... */
};
```

You can write two separate binding files which match these individual sensor nodes, even though they have the same compatible:

```plaintext
# manufacturer,sensor-spi.yaml, which matches sensor@0 on the SPI bus:
compatible: "manufacturer,sensor"
on-bus: spi

# manufacturer,sensor-i2c.yaml, which matches sensor@79 on the I2C bus:
compatible: "manufacturer,sensor"
properties:
    uses-clock-stretching:
        type: boolean
on-bus: i2c
```

Only `sensor@79` can have a `use-clock-stretching` property. The bus-sensitive logic ignores `manufacturer,sensor-i2c.yaml` when searching for a binding for `sensor@0`.

**Specifier cell names (**-cells**)** Specifier cells are usually used with `phandle-array` type properties briefly introduced above.

To understand the purpose of **-cells**, assume that some node has the following `pwms` property with type `phandle-array`:

```plaintext
my-device {
    pwms = &pwm0 1 2>, &pwm3 4>;
};
```
The tooling strips the final s from the property name of such properties, resulting in pwm. Then the value of the #pwm-cells property is looked up in each of the PWM controller nodes pwm0 and pwm3, like so:

```
pwm0: pwm@0 {
    compatible = "foo,pwm";
    #pwm-cells = <2>;
};
pwm3: pwm@3 {
    compatible = "bar,pwm";
    #pwm-cells = <1>;
};
```

The 1 2 part of the property value has two cells, 1 and 2, which matches #pwm-cells = <2>; so these cells are considered the specifier associated with pwm0 in the phandle array.

Similarly, the cell 4 is the specifier associated with pwm3.

The number of PWM cells in the specifiers in pwms must match the #pwm-cells values, as shown above. If there is a mismatch, an error is raised. For example, this node would result in an error:

```
my-bad-device {
    /* wrong: 2 cells given in the specifier, but #pwm-cells is 1 in pwm3. */
    pwms = <&pwm3 5 6>;
};
```

The binding for each PWM controller must also have a *-cells key, in this case pwm-cells, giving names to the cells in each specifier:

```
# foo,pwm.yaml
compatible: "foo,pwm"
...
pwm-cells:
    - channel
    - period

# bar,pwm.yaml
compatible: "bar,pwm"
...
pwm-cells:
    - period
```

A *-names (e.g. pwm-names) property can appear on the node as well, giving a name to each entry. This allows the cells in the specifiers to be accessed by name, e.g. using APIs like DT_PWMS_CHANNEL_BY_NAME.

Because other property names are derived from the name of the property by removing the final s, the property name must end in s. An error is raised if it doesn’t.

An alternative is using a specifier-space property to indicate the base property name for *-names and *-cells.

*-gpios properties are special-cased so that e.g. foo-gpios resolves to #gpio-cells rather than #foo-gpio-cells.

If the specifier is empty (e.g. #clock-cells = <0>), then *-cells can either be omitted (recommended) or set to an empty array. Note that an empty array is specified as e.g. clock-cells: [] in YAML.

All phandle-array type properties support mapping through *-map properties, e.g. gpio-map, as defined by the Devicetree specification.

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Include Bindings can include other files, which can be used to share common property definitions between bindings. Use the `include:` key for this. Its value is either a string or a list.

In the simplest case, you can include another file by giving its name as a string, like this:

```
include: foo.yaml
```

If any file named `foo.yaml` is found (see *Where bindings are located* for the search process), it will be included into this binding.

Included files are merged into bindings with a simple recursive dictionary merge. The build system will check that the resulting merged binding is well-formed. It is allowed to include at any level, including child-binding, like this:

```
# foo.yaml will be merged with content at this level
include: foo.yaml

child-binding:
  # bar.yaml will be merged with content at this level
  include: bar.yaml
```

It is an error if a key appears with a different value in a binding and in a file it includes, with one exception: a binding can have `required:` true for a property definition for which the included file has `required:` false. The `required:` true takes precedence, allowing bindings to strengthen requirements from included files.

Note that weakening requirements by having `required:` false where the included file has `required:` true is an error. This is meant to keep the organization clean.

The file `base.yaml` contains definitions for many common properties. When writing a new binding, it is a good idea to check if `base.yaml` already defines some of the needed properties, and include it if it does.

Note that you can make a property defined in `base.yaml` obligatory like this, taking `reg` as an example:

```
reg:
  required: true
```

This relies on the dictionary merge to fill in the other keys for `reg`, like `type`.

To include multiple files, you can use a list of strings:

```
include:
  - foo.yaml
  - bar.yaml
```

This includes the files `foo.yaml` and `bar.yaml`. (You can write this list in a single line of YAML as `include: [foo.yaml, bar.yaml]`.)

When including multiple files, any overlapping `required` keys on properties in the included files are ORed together. This makes sure that a `required:` true is always respected.

In some cases, you may want to include some property definitions from a file, but not all of them. In this case, `include:` should be a list, and you can filter out just the definitions you want by putting a mapping in the list, like this:

```
include:
  - name: foo.yaml
    property-allowlist:
      - i-want-this-one
      - and-this-one
    - name: bar.yaml
      property-blocklist:
```

(continues on next page)
Each map element must have a name key which is the filename to include, and may have property-allowlist and property-blocklist keys that filter which properties are included.

You cannot have a single map element with both property-allowlist and property-blocklist keys. A map element with neither property-allowlist nor property-blocklist is valid; no additional filtering is done.

You can freely intermix strings and mappings in a single include:

```yaml
include:
  - foo.yaml
  - name: bar.yaml
    property-blocklist:
      - do-not-include-this-one
      - or-this-one
```

Finally, you can filter from a child binding like this:

```yaml
include:
  - name: bar.yaml
    child-binding:
      property-allowlist:
        - child-prop-to-allow
```

**Rules for mainline bindings**  This section includes general rules for writing bindings that you want to submit to the mainline Zephyr Project. (You don't need to follow these rules for bindings you don't intend to contribute to the Zephyr Project, but it's a good idea.)

Decisions made by the Zephyr devicetree maintainer override the contents of this section. If that happens, though, please let them know so they can update this page, or you can send a patch yourself.

**Always check for existing bindings**  Zephyr aims for devicetree *source compatibility with other operating systems*. Therefore, if there is an existing binding for your device in an authoritative location, you should try to replicate its properties when writing a Zephyr binding, and you must justify any Zephyr-specific divergences.

In particular, this rule applies if:

- There is an existing binding in the mainline Linux kernel. See `Documentation/devicetree/bindings` in *Linus's tree* for existing bindings and the *Linux devicetree documentation* for more information.
- Your hardware vendor provides an official binding outside of the Linux kernel.

**General rules**

- Bindings which match a compatible must have file names based on the compatible.
  - For example, a binding for compatible `vnd,foo` must be named `vnd,foo.yaml`.
  - If the binding is bus-specific, you can append the bus to the file name; for example, if the binding YAML has `on-bus: bar`, you may name the file `vnd,foo-bar.yaml`.
- All recommendations in *Default values for properties* are requirements when submitting the binding.

In particular, if you use the `default:` feature, you must justify the value in the property's description.
There are two ways to write property description: strings that are always OK.

If your description is short, it's fine to use this style:

```
description: my short string
```

If your description is long or spans multiple lines, you must use this style:

```
description: |
  My very long string
  goes here.
  Look at all these lines!
```

This | style prevents YAML parsers from removing the newlines in multi-line descriptions. This in turn makes these long strings display properly in the `Bindings index`.

Do not use any other style for long or multi-line strings.

Do not use uppercase letters (A through Z) or underscores (_). Use lowercase letters (a through z) instead of uppercase. Use dashes (-) instead of underscores. (The one exception to this rule is if you are replicating a well-established binding from somewhere like Linux.)

### Rules for vendor prefixes

The following general rules apply to vendor prefixes in `compatible` properties.

- If your device is manufactured by a specific vendor, then its compatible should have a vendor prefix.
- If your binding describes hardware with a well known vendor from the list in `dts/bindings/vendor-prefixes.txt`, you must use that vendor prefix.
- If your device is not manufactured by a specific hardware vendor, do not invent a vendor prefix. Vendor prefixes are not mandatory parts of compatible properties, and compatibles should not include them unless they refer to an actual vendor. There are some exceptions to this rule, but the practice is strongly discouraged.
- Do not submit additions to Zephyr's `dts/bindings/vendor-prefixes.txt` file unless you also include users of the new prefix. This means at least a binding and a devicetree using the vendor prefix, and should ideally include a device driver handling that compatible.

For custom bindings, you can add a custom `dts/bindings/vendor-prefixes.txt` file to any directory in your `DTS_ROOT`. The devicetree tooling will respect these prefixes, and will not generate warnings or errors if you use them in your own bindings or devicetrees.

- We sometimes synchronize Zephyr's vendor-prefixes.txt file with the Linux kernel's equivalent file; this process is exempt from the previous rule.
- If your binding is describing an abstract class of hardware with Zephyr specific drivers handling the nodes, it's usually best to use `zephyr` as the vendor prefix. See [Zephyr-specific binding (zephyr)] for examples.

### Rules for default values

In any case where `default:` is used in a devicetree binding, the description: for that property must explain why the value was selected and any conditions that would make it necessary to provide a different value. Additionally, if changing one property would require changing another to create a consistent configuration, then those properties should be made required.

There is no need to document the default value itself; this is already present in the `Bindings index` output.

There is a risk in using `default:` when the value in the binding may be incorrect for a particular board or hardware configuration. For example, defaulting the capacity of the connected power cell in a charging IC binding is likely to be incorrect. For such properties it's better to make the property `required: true`, forcing the user to make an explicit choice.
Driver developers should use their best judgment as to whether a value can be safely defaulted. Candidates for default values include:

- delays that would be different only under unusual conditions (such as intervening hardware)
- configuration for devices that have a standard initial configuration (such as a USB audio headset)
- defaults which match the vendor-specified power-on reset value (as long as they are independent from other properties)

Examples of how to write descriptions according to these rules:

```
properties:
cs-interval:
  type: int
default: 0
description: |
  Minimum interval between chip select deassertion and assertion.
  The default corresponds to the reset value of the register field.

hold-time-ms:
  type: int
default: 20
description: |
  Amount of time to hold the power enable GPIO asserted before initiating communication. The default was recommended in the manufacturer datasheet, and would only change under very cold temperatures.
```

Some examples of what **not** to do, and why:

```
properties:
  # Description doesn't mention anything about the default
  foo:
    type: int
default: 1
description: number of foos

  # Description mentions the default value instead of why it was chosen
  bar:
    type: int
default: 2
description: bar size; default is 2

  # Explanation of the default value is in a comment instead of the description. This won't be shown in the bindings index.
  baz:
    type: int
    # This is the recommended value chosen by the manufacturer.
    default: 2
description: baz time in milliseconds
```

**Inferred bindings**  Zephyr's devicetree scripts can “infer” a binding for the special `/zephyr/user` node based on the values observed in its properties.

This node matches a binding which is dynamically created by the build system based on the values of its properties in the final devicetree. It does not have a `compatible` property.

This node is meant for sample code and applications. The devicetree API provides it as a convenient container when only a few simple properties are needed, such as storing a hardware-dependent value,
phandle(s), or GPIO pin.

For example, with this DTS fragment:

```c
#include <zephyr/dt-bindings/gpio/gpio.h>

/ {
    zephyr,user {
        boolean;
        bytes = [81 82 83];
        number = <23>;
        numbers = <1>, <2>, <3>;
        string = "text";
        strings = "a", "b", "c";
        handle = <&gpio0>;
        handles = <&gpio0>, <&gpio1>;
        signal-gpios = <&gpio0 1 GPIO_ACTIVE_HIGH>;
    }
};
```

You can get the simple values like this:

```c
#define ZEPHYR_USER_NODE DT_PATH(zephyr_user)

DT_PROP(ZEPHYR_USER_NODE, boolean) // 1
DT_PROP(ZEPHYR_USER_NODE, bytes) // {0x81, 0x82, 0x83}
DT_PROP(ZEPHYR_USER_NODE, number) // 23
DT_PROP(ZEPHYR_USER_NODE, numbers) // {1, 2, 3}
DT_PROP(ZEPHYR_USER_NODE, string) // "text"
DT_PROP(ZEPHYR_USER_NODE, strings) // {"a", "b", "c"}
```

You can convert the phandles in the handle and handles properties to device pointers like this:

```c
const struct device *my_device =
    DEVICE_RT_GET(DT_PROP(ZEPHYR_USER_NODE, handle));
```

```c
const struct device *my_devices[] = {
    DEVICE_RT_GET(DT_PROP(ZEPHYR_USER_NODE, handles) idx),
};
```

And you can convert the pin defined in signal-gpios to a struct gpio_dt_spec, then use it like this:
```
#include <zephyr/drivers/gpio.h>
#define ZEPHYR_USER_NODE DT_PATH(zephyr_user)

const struct gpio_dt_spec signal =
    GPIO_DT_SPEC_GET(ZEPHYR_USER_NODE, signal_gpios);

/* Configure the pin */
gpio_pin_configure_dt(&signal, GPIO_OUTPUT_INACTIVE);

/* Set the pin to its active level */
gpio_pin_set_dt(&signal, 1);
```

(See `gpio_dt_spec`, `GPIO_DT_SPEC_GET`, and `gpio_pin_configure_dt()` for details on these APIs.)

Devicetree access from C/C++

This guide describes Zephyr's `<devicetree.h>` API for reading the devicetree from C source files. It assumes you're familiar with the concepts in Introduction to devicetree and Devicetree bindings. See Devicetree Reference for reference material.

A note for Linux developers  Linux developers familiar with devicetree should be warned that the API described here differs significantly from how devicetree is used on Linux.

Instead of generating a C header with all the devicetree data which is then abstracted behind a macro API, the Linux kernel would instead read the devicetree data structure in its binary form. The binary representation is parsed at runtime, for example to load and initialize device drivers.

Zephyr does not work this way because the size of the devicetree binary and associated handling code would be too large to fit comfortably on the relatively constrained devices Zephyr supports.

Node identifiers  To get information about a particular devicetree node, you need a node identifier for it. This is a just a C macro that refers to the node.

These are the main ways to get a node identifier:

**By path**
Use `DT_PATH()` along with the node's full path in the devicetree, starting from the root node. This is mostly useful if you happen to know the exact node you're looking for.

**By node label**
Use `DT_NODELABEL()` to get a node identifier from a node label. Node labels are often provided by SoC .dtsi to give nodes names that match the SoC datasheet, like i2c1, spi2, etc.

**By alias**
Use `DT_ALIAS()` to get a node identifier for a property of the special /aliases node. This is sometimes done by applications (like blinky, which uses the led0 alias) that need to refer to some device of a particular type ("the board's user LED") but don't care which one is used.

**By instance number**
This is done primarily by device drivers, as instance numbers are a way to refer to individual nodes based on a matching compatible. Get these with `DT_INST()`, but be careful doing so. See below.

**By chosen node**
Use `DT_CHOSEN()` to get a node identifier for /chosen node properties.

**By parent/child**
Use `DT_PARENT()` and `DT_CHILD()` to get a node identifier for a parent or child node, starting from a node identifier you already have.

5.2. Devicetree
Two node identifiers which refer to the same node are identical and can be used interchangeably. Here’s a DTS fragment for some imaginary hardware we’ll return to throughout this file for examples:

```dts
/dts-v1/;
/
{
    aliases {
        sensor-controller = &i2c1;
    };
    soc {
        i2c1: i2c@40002000 {
            compatible = "vnd,soc-i2c";
            label = "I2C_1";
            reg = <0x40002000 0x1000>;
            status = "okay";
            clock-frequency = < 100000 >;
        }
    }
};
```

Here are a few ways to get node identifiers for the `i2c@40002000` node:

- `DT_PATH(soc, i2c_40002000)`
- `DT_NODELABEL(i2c1)`
- `DT_ALIAS(sensor_controller)`
- `DT_INST(x, vnd_soc_i2c)` for some unknown number `x`. See the `DT_INST()` documentation for details.

**Important:** Non-alphanumeric characters like dash (-) and the at sign (@) in devicetree names are converted to underscores (_). The names in a DTS are also converted to lowercase.

**Node identifiers are not values** There is no way to store one in a variable. You cannot write:

```c
/* These will give you compiler errors: */
void *i2c_0 = DT_INST(0, vnd_soc_i2c);
unsigned int i2c_1 = DT_INST(1, vnd_soc_i2c);
long my_i2c = DT_NODELABEL(i2c1);
```

If you want something short to save typing, use C macros:

```c
/* Use something like this instead: */
#define MY_I2C DT_NODELABEL(i2c1)
#define INST(i) DT_INST(i, vnd_soc_i2c)
#define I2C_0 INST(0)
#define I2C_1 INST(1)
```

**Property access** The right API to use to read property values depends on the node and property.
• Simple properties
• reg properties
• interrupts properties
• phandle properties

Checking properties and values You can use `DT_NODE_HAS_PROP()` to check if a node has a property. For the example devicetree above:

```
DT_NODE_HAS_PROP(DT_NODELABEL(i2c1), clock_frequency) /* expands to 1 */
DT_NODE_HAS_PROP(DT_NODELABEL(i2c1), not_a_property) /* expands to 0 */
```

Simple properties Use `DT_PROP(node_id, property)` to read basic integer, boolean, string, numeric array, and string array properties.

For example, to read the clock-frequency property's value in the above example:

```
DT_PROP(DT_PATH(soc, i2c_40002000), clock_frequency) /* This is 100000, */
DT_PROP(DT_NODELABEL(i2c1), clock_frequency) /* and so is this, */
DT_PROP(DT_ALIAS(sensor_controller), clock_frequency) /* and this. */
```

**Important:** The DTS property `clock-frequency` is spelled `clock_frequency` in C. That is, properties also need special characters converted to underscores. Their names are also forced to lowercase.

Properties with string and boolean types work the exact same way. The `DT_PROP()` macro expands to a string literal in the case of strings, and the number 0 or 1 in the case of booleans. For example:

```
#define I2C1 DT_NODELABEL(i2c1)

DT_PROP(I2C1, status) /* expands to the string literal "okay" */
```

**Note:** Don’t use `DT_NODE_HAS_PROP()` for boolean properties. Use `DT_PROP()` instead as shown above. It will expand to either 0 or 1 depending on if the property is present or absent.

Properties with type array, uint8-array, and string-array work similarly, except `DT_PROP()` expands to an array initializer in these cases. Here is an example devicetree fragment:

```
foo: foo@1234 {
   a = <1000 2000 3000>; /* array */
   b = [aa bb cc dd]; /* uint8-array */
   c = "bar", "baz"; /* string-array */
};
```

Its properties can be accessed like this:

```
#define FOO DT_NODELABEL(foo)

int a[] = DT_PROP(FOO, a); /* {1000, 2000, 3000} */
unsigned char b[] = DT_PROP(FOO, b); /* {0xaa, 0xbb, 0xcc, 0xdd} */
char* c[] = DT_PROP(FOO, c); /* {"foo", "bar"} */
```

You can use `DT_PROP_LEN()` to get logical array lengths in number of elements.
size_t a_len = DT_PROP_LEN(FOO, a); /* 3 */
size_t b_len = DT_PROP_LEN(FOO, b); /* 4 */
size_t c_len = DT_PROP_LEN(FOO, c); /* 2 */

DT_PROP_LEN() cannot be used with the special reg or interrupts properties. These have alternative macros which are described next.

**reg properties**  
See *Important properties* for an introduction to reg.

Given a node identifier node_id, DT_NUM_REGS(node_id) is the total number of register blocks in the node's reg property.

You **cannot** read register block addresses and lengths with DT_PROP(node, reg). Instead, if a node only has one register block, use `DT_REG_ADDR()` or `DT_REG_SIZE()`:

- `DT_REG_ADDR(node_id)`: the given node's register block address
- `DT_REG_SIZE(node_id)`: its size

Use `DT_REG_ADDR_BY_IDX()` or `DT_REG_SIZE_BY_IDX()` instead if the node has multiple register blocks:

- `DT_REG_ADDR_BY_IDX(node_id, idx)`: address of register block at index idx
- `DT_REG_SIZE_BY_IDX(node_id, idx)`: size of block at index idx

The idx argument to these must be an integer literal or a macro that expands to one without requiring any arithmetic. In particular, idx cannot be a variable. This won't work:

```c
/* This will cause a compiler error. */
for (size_t i = 0; i < DT_NUM_REGS(node_id); i++) {
    size_t addr = DT_REG_ADDR_BY_IDX(node_id, i);
}
```

**interrupts properties**  
See *Important properties* for a brief introduction to interrupts.

Given a node identifier node_id, DT_NUM_IRQS(node_id) is the total number of interrupt specifiers in the node's interrupts property.

The most general purpose API macro for accessing these is `DT_IRQ_BY_IDX()`:

```
DT_IRQ_BY_IDX(node_id, idx, val)
```

Here, idx is the logical index into the interrupts array, i.e. it is the index of an individual interrupt specifier in the property. The val argument is the name of a cell within the interrupt specifier. To use this macro, check the bindings file for the node you are interested in to find the val names.

Most Zephyr devicetree bindings have a cell named irq, which is the interrupt number. You can use `DT_IRQN()` as a convenient way to get a processed view of this value.

**Warning:** Here, "processed" reflects Zephyr's devicetree *Scripts and tools*, which change the irq number in zephyr.dts to handle hardware constraints on some SoCs and in accordance with Zephyr's multilevel interrupt numbering.

This is currently not very well documented, and you'll need to read the scripts' source code and existing drivers for more details if you are writing a device driver.
phandle properties  Property values can refer to other nodes using the &another-node phandle syntax introduced in Writing property values. Properties which contain phandles have type phandle, phandles, or phandle-array in their bindings. We'll call these "phandle properties" for short.

You can convert a phandle to a node identifier using DT_PHANDLE(), DT_PHANDLE_BY_IDX(), or DT_PHANDLE_BY_NAME(), depending on the type of property you are working with.

One common use case for phandle properties is referring to other hardware in the tree. In this case, you usually want to convert the devicetree-level phandle to a Zephyr driver-level struct device. See Get a struct device from a devicetree node for ways to do that.

Another common use case is accessing specifier values in a phandle array. The general purpose APIs for this are DT_PHA_BY_IDX() and DT_PHA(). There are also hardware-specific short-hands like DT_GPIO_CTLR_BY_IDX(), DT_GPIO_CTLR(), DT_GPIO_LABEL_BY_IDX(), DT_GPIO_LABEL(), DT_GPIO_PIN_BY_IDX(), DT_GPIO_PIN(), DT_GPIO_FLAGS_BY_IDX(), and DT_GPIO_FLAGS().

See DT_PHA_HAS_CELL_AT_IDX() and DT_PROP_HAS_IDX() for ways to check if a specifier value is present in a phandle property.

Other APIs  Here are pointers to some other available APIs.

- DT_CHOSEN(), DT_HAS_CHOSEN(): for properties of the special /chosen node
- DT_HAS_COMPAT_STATUS_OKAY(), DT_NODE_HAS_COMPAT(): global- and node-specific tests related to the compatible property
- DT_BUS(): get a node’s bus controller, if there is one
- DT_ENUM_IDX(): for properties whose values are among a fixed list of choices
- Fixed flash partitions: APIs for managing fixed flash partitions. Also see Flash map, which wraps this in a more user-friendly API.

Device driver conveniences  Special purpose macros are available for writing device drivers, which usually rely on instance identifiers.

To use these, you must define DT_DRV_COMPAT to the compat value your driver implements support for. This compat value is what you would pass to DT_INST().

If you do that, you can access the properties of individual instances of your compatible with less typing, like this:

```c
#include <zephyr/devicetree.h>

#define DT_DRV_COMPAT my_driver_compat

/* This is same thing as DT_INST(0, my_driver_compat): */
DT_DRV_INST(0)

/*
 * This is the same thing as
 * DT_PROP(DT_INST(0, my_driver_compat), clock_frequency)
 */
DT_INST_PROP(0, clock_frequency)
```

See Instance-based APIs for a generic API reference.

Hardware specific APIs  Convenience macros built on top of the above APIs are also defined to help readability for hardware specific code. See Hardware specific APIs for details.
Generated macros  While the devicetree.h API is not generated, it does rely on a generated C header which is put into every application build directory: devicetree_generated.h. This file contains macros with devicetree data.

These macros have tricky naming conventions which the Devicetree API abstracts away. They should be considered an implementation detail, but it’s useful to understand them since they will frequently be seen in compiler error messages.

This section contains an Augmented Backus-Naur Form grammar for these generated macros, with examples and more details in comments. See RFC 7405 (which extends RFC 5234) for a syntax specification.

```
; An RFC 7405 ABNF grammar for devicetree macros.
;
; This does *not* cover macros pulled out of DT via Kconfig,
; like CONFIG_SRAM_BASE_ADDRESS, etc. It only describes the
; ones that start with DT_ and are directly generated.

; dt-macro: the top level nonterminal for a devicetree macro
;
; A dt-macro starts with uppercase "DT_", and is one of:
;
; - a <node-macro>, generated for a particular node
; - some <other-macro>, a catch-all for other types of macros

dt-macro = node-macro / other-macro

; node-macro: a macro related to a node
;
; A macro about a property value
node-macro = property-macro
; A macro about the pinctrl properties in a node.
node-macro = pinctrl-macro
; EXISTS macro: node exists in the devicetree
node-macro = / %s"DT_N" path-id %s"_EXISTS"
; Bus macros: the plain BUS is a way to access a node's bus controller.
; The additional dt-name suffix is added to match that node's bus type;
; the dt-name in this case is something like "spi" or "i2c".
node-macro = / %s"DT_N" path-id %s"_BUS" ["_" dt-name]
node-macro = / %s"DT_N" path-id %s"_REG_NUM"
node-macro = / %s"DT_N" path-id %s"_REG_IDX_" DIGIT "_EXISTS"
node-macro = / %s"DT_N" path-id %s"_REG_IDX_" DIGIT
   %s"_VAL_" ( %s"ADDRESS" / %s"SIZE")
node-macro = / %s"DT_N" path-id %s"_REG_NAME_" dt-name
   %s"_VAL_" ( %s"ADDRESS" / %s"SIZE")
;
; The interrupts property is also special.
node-macro = / %s"DT_N" path-id %s"_IRQ_NUM"
node-macro = / %s"DT_N" path-id %s"_IRQ_IDX_" DIGIT "_EXISTS"
node-macro = / %s"DT_N" path-id %s"_IRQ_IDX_" DIGIT
   %s"_VAL_" dt-name [ %s"_EXISTS" ]
node-macro = / %s"DT_N" path-id %s"_IRQ_NAME_" dt-name
   %s"_VAL_" dt-name [ %s"_EXISTS" ]
;
; The ranges property is also special.
node-macro = / %s"DT_N" path-id %s"_RANGES_NUM"
node-macro = / %s"DT_N" path-id %s"_RANGES_IDX_" DIGIT "_EXISTS"
node-macro = / %s"DT_N" path-id %s"_RANGES_IDX_" DIGIT
   %s"_VAL_" ( %s"CHILD_BUS_FLAGS" / %s"CHILD_BUS_ADDRESS" /
   %s"PARENT_BUS_ADDRESS" / %s"LENGTH")
```
node-macro =/ %s"DT_N" path-id %s"_RANGES_IDX_" DIGIT %s"_VAL_CHILD_BUS_FLAGS_EXISTS"

; Subnodes of the fixed-partitions compatible get macros which contain
; a unique ordinal value for each partition
node-macro =/ %s"DT_N" path-id %s"_PARTITION_ID_" DIGIT
; Macros are generated for each of a node's compatibles;
; dt-name in this case is something like "vnd_device".
node-macro =/ %s"DT_N" path-id %s"_COMPAT_MATCHES_" dt-name
node-macro =/ %s"DT_N" path-id %s"_COMPAT_VENDOR_IDX_" DIGIT "_EXISTS"
node-macro =/ %s"DT_N" path-id %s"_COMPAT_VENDOR_IDX_" DIGIT
node-macro =/ %s"DT_N" path-id %s"_COMPAT_MODEL_IDX_" DIGIT "_EXISTS"
node-macro =/ %s"DT_N" path-id %s"_COMPAT_MODEL_IDX_" DIGIT

; Every non-root node gets one of these macros, which expands to the node
; identifier for that node's parent in the devicetree.
node-macro =/ %s"DT_N" path-id %s"_PARENT"
; These are used internally by DT_FOREACH_PROP_ELEM(_SEP)(_VARGS), which
; iterates over each property element.
node-macro =/ %s"DT_N" path-id %s"_P_" prop-id %s"_FOREACH_PROP_ELEM"
node-macro =/ %s"DT_N" path-id %s"_P_" prop-id %s"_FOREACH_PROP_ELEM_SEP"
node-macro =/ %s"DT_N" path-id %s"_P_" prop-id %s"_FOREACH_PROP_ELEM_VARGS"
node-macro =/ %s"DT_N" path-id %s"_P_" prop-id %s"_FOREACH_PROP_ELEM_SEP_VARGS"

; These are used internally by DT_FOREACH_CHILD, which iterates over
; each child node.
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD"
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_SEP"
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_VARGS"
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_SEP_VARGS"

; These are used internally by DT_FOREACH_CHILD_STATUS_OKAY, which iterates
; over each child node with status "okay".
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY"
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY_SEP"
node-macro =/ %s"DT_N" path-id %s"_FOREACH_CHILD_STATUS_OKAY_VARGS"

; The node's zero-based index in the list of it's parent's child nodes.
node-macro =/ %s"DT_N" path-id %s"_CHILD_IDX"

node-macro =/ %s"DT_N" path-id %s"_STATUS_" dt-name
; The node's status macro; dt-name in this case is something like "okay"
; or "disabled".
node-macro =/ %s"DT_N" path-id %s"_ORD"
; The node's dependency ordinal. This is a non-negative integer
; value that is used to represent dependency information.
node-macro =/ %s"DT_N" path-id %s"_PATH"
; The node's path, as a string literal
node-macro =/ %s"DT_N" path-id %s"_FULL_NAME"
; The dependency ordinals of a node's requirements (direct dependencies).
node-macro =/ %s"DT_N" path-id %s"_REQUIRES_ORDS"
; The dependency ordinals of a node supports (reverse direct dependencies).
node-macro =/ %s"DT_N" path-id %s"_SUPPORTS_ORDS"

; pinctrl-macro: a macro related to the pinctrl properties in a node
; These are a bit of a special case because they kind of form an array,
; but the array indexes correspond to pinctrl-DIGIT properties in a node.
So they're related to a node, but not just one property within the node.

The following examples assume something like this:

```
foo {
    pinctrl-0 = @bar@;
    pinctrl-1 = @baz@;
    pinctrl-names = "default", "sleep";
};
```

Total number of pinctrl-DIGIT properties in the node. May be zero.

```
#define DT_N_<node path>_PINCTRL_NUM 2
pinctrl-macro = %s"DT_N" path-id %s"_PINCTRL_NUM"
```

A given pinctrl-DIGIT property exists.

```
#define DT_N_<node path>_PINCTRL_IDX_0_EXISTS 1
#define DT_N_<node path>_PINCTRL_IDX_1_EXISTS 1
pinctrl-macro =/ %s"DT_N" path-id %s"_PINCTRL_IDX_" DIGIT %s"_EXIST"
```

A given pinctrl property name exists.

```
#define DT_N_<node path>_PINCTRL_NAME_default_EXISTS 1
#define DT_N_<node path>_PINCTRL_NAME_sleep_EXISTS 1
pinctrl-macro =/ %s"DT_N" path-id %s"_PINCTRL_NAME_" dt-name %s"_EXIST"
```

The corresponding index number of a named pinctrl property.

```
#define DT_N_<node path>_PINCTRL_NAME_default_IDX 0
#define DT_N_<node path>_PINCTRL_NAME_sleep_IDX 1
pinctrl-macro =/ %s"DT_N" path-id %s"_PINCTRL_NAME_" dt-name %s"_IDX"
```

The node identifier for the phandle in a named pinctrl property.

```
#define DT_N_<node path>_PINCTRL_NAME_default_IDX_0_PH <node id for 'bar'>
```

There's no need for a separate macro for access by index: that's covered by property-macro. We only need this because the map from names to properties is implicit in the structure of the DT.

```
pinctrl-macro =/ %s"DT_N" path-id %s"_PINCTRL_NAME_" dt-name %s"_IDX_" DIGIT %s"_PH"
```

----------------------------------------

property-macro: a macro related to a node property

These combine a node identifier with a "lowercase-and-underscores form" property name. The value expands to something related to the property's value.

The optional prop-suf suffix is when there's some specialized subvalue that deserves its own macro, like the macros for an array property's individual elements.

The "plain vanilla" macro for a property's value, with no prop-suf, looks like this:

```
DT_N_<node path>_P_<property name>
```

Components:
property-macro = %s"DT_N" path-id %s"_P_" prop-id [prop-suf]

; --------------------------------------------------------------------
; path-id: a node's path-based macro identifier
; This in "lowercase-and-underscores" form. I.e. it is
; the node's devicetree path converted to a C token by changing:
; - each slash (/) to _S_
; - all letters to lowercase
; - non-alphanumerics characters to underscores
;
; For example, the leaf node "bar-BAZ" in this devicetree:
;
; / {
;   foo@123 {
;     bar-BAZ {};
;   };
; }
;
; has path-id "_S_foo_123_S_bar_baz".
path-id = 1*( %s"_S_" dt-name )

;----------------------------------------------------------------------
; prop-id: a property identifier
; A property name converted to a C token by changing:
; - all letters to lowercase
; - non-alphanumeric characters to underscores
;
; Example node:
;
; chosen {
;   zephyr,console = &uart1;
;   WHY,AM_I_SHOUTING = "unclear";
; }
;
; The 'zephyr,console' property has prop-id 'zephyr_console'.
; 'WHY,AM_I_SHOUTING' has prop-id 'why_am_i_shouting'.
prop-id = dt-name

;----------------------------------------------------------------------
; prop-suf: a property-specific macro suffix
; Extra macros are generated for properties:
; - that are special to the specification ("reg", "interrupts", etc.)
; - with array types (uint8-array, phandle-array, etc.)
; - with "enum:" in their bindings
; - that have zephyr device API specific macros for phandle-arrays
; - related to phandle specifier names ("foo-names")

(continues on next page)
Here are some examples:

- `_EXISTS`: property, index or name existence flag
- `_SIZE`: logical property length
- `_IDX_<i>`: values of individual array elements
- `_IDX_<DIGIT>_VAL_<dt-name>`: values of individual specifier
- `_ADDR_<i>`: for reg properties, the i-th register block address
- `_LEN_<i>`: for reg properties, the i-th register block length

The different cases are not exhaustively documented here to avoid this file going stale. Please see devicetree.h if you need to know the details.

```
prop-suf = 1*( "_" gen-name ["_" dt-name] )
```

See examples below.

```
other-macro = %s"DT_N_" alternate-id
other-macro =/ %s"DT_N_INST_" dt-name %s"NUM_OKAY"
other-macro =/ %s"DT_FOREACH_HELPER"
other-macro =/ %s"DT_FOREACH_OKAY_HELPER"
other-macro =/ %s"DT_FOREACH_OKAY_" dt-name
other-macro =/ %s"DT_FOREACH_OKAY_VARGS_" dt-name
other-macro =/ %s"DT_CHOSEN_" dt-name
other-macro =/ %s"DT_COMPAT_" dt-name %s"BUS_" dt-name
other-macro =/ %s"DT_COMPAT_HAS_OKAY_" dt-name
other-macro =/ %s"DT_COMPAT_LABEL_" dt-name
```

Alternate-id: another way to specify a node besides a path-id

Example devicetree:
Node device@123 has these alternate-id values:

- ALIAS_dev
- NODELABEL_dev_1
- INST_0_vnd_device

The full alternate-id macros are:

```c
#define DT_N_INST_0_vnd_device DT_N_S_soc_S_device_123
#define DT_N_ALIAS_dev DT_N_S_soc_S_device_123
#define DT_N_NODELABEL_dev_1 DT_N_S_soc_S_device_123
```

These mainly exist to allow pasting an alternate-id macro onto a
"_P_<prop-id>" to access node properties given a node's alias, etc.

Notice that "inst"-type IDs have a leading instance identifier,
which is generated by the devicetree scripts. The other types of
alternate-id begin immediately with names taken from the devicetree.

**alternate-id = ( %s"ALIAS" / %s"NODELABEL" ) dt-name**

**alternate-id =/ %s"INST" 1*DIGIT "_" dt-name**

---

**miscellaneous helper definitions**

A dt-name is one or more:

- lowercase ASCII letters (a-z)
- numbers (0-9)
- underscores ("_")

They are the result of converting names or combinations of names
from devicetree to a valid component of a C identifier by
lowercasing letters (in practice, this is a no-op) and converting
non-alphanumeric characters to underscores.

You'll see these referred to as "lowercase-and-underscores" forms of
various devicetree identifiers throughout the documentation.

**dt-name = 1*( lower / DIGIT / "_" )**

**gen-name is used as a stand-in for a component of a generated macro
name which does not come from devicetree (dt-name covers that case).**

- uppercase ASCII letters (a-z)
- numbers (0-9)

(continues on next page)
Devicetree HOWTOs

This page has step-by-step advice for getting things done with devicetree.

Tip: See Troubleshooting devicetree for troubleshooting advice.

Get your devicetree and generated header  A board’s devicetree (BOARD.dts) pulls in common node definitions via #include preprocessor directives. This at least includes the SoC’s .dtsi. One way to figure out the devicetree’s contents is by opening these files, e.g. by looking in dts/<ARCH>/<vendor>/<soc>.dtsi, but this can be time consuming.

If you just want to see the “final” devicetree for your board, build an application and open the zephyr.dts file in the build directory.

Tip: You can build hello_world to see the “base” devicetree for your board without any additional changes from overlay files.

For example, using the qemu_cortex_m3 board to build hello_world:

```bash
# --cmake-only here just forces CMake to run, skipping the # build process to save time.
west build -b qemu_cortex_m3 samples/hello_world --cmake-only
```

You can change qemu_cortex_m3 to match your board.

CMake prints the input and output file locations like this:

```
-- Found BOARD.dts: .../zephyr/boards/arm/qemu_cortex_m3/qemu_cortex_m3.dts
-- Generated zephyr.dts: .../zephyr/build/zephyr/zephyr.dts
-- Generated devicetree_generated.h: .../zephyr/build/zephyr/include/generated/
    → devicetree_generated.h
```

The zephyr.dts file is the final devicetree in DTS format.
The devicetree_generated.h file is the corresponding generated header.
See Input and output files for details about these files.

Get a struct device from a devicetree node  When writing Zephyr applications, you’ll often want to get a driver-level struct device corresponding to a devicetree node.

For example, with this devicetree fragment, you might want the struct device for serial@0x0002000:
Start by making a **node identifier** for the device you are interested in. There are different ways to do this; pick whichever one works best for your requirements. Here are some examples:

```c
/* Option 1: by node label */
#define MY_SERIAL DT_NODELABEL(serial0)

/* Option 2: by alias */
#define MY_SERIAL DT_ALIAS(my_serial)

/* Option 3: by chosen node */
#define MY_SERIAL DT_CHOSEN(zephyr_console)

/* Option 4: by path */
#define MY_SERIAL DT_PATH(soc, serial@40002000)
```

Once you have a node identifier there are two ways to proceed. One way to get a device is to use `DEVICE_DT_GET()`:

```c
const struct device *const uart_dev = DEVICE_DT_GET(MY_SERIAL);
if (!device_is_ready(uart_dev)) {
    /* Not ready, do not use */
    return -ENODEV;
}
```

There are variants of `DEVICE_DT_GET()` such as `DEVICE_DT_GET_OR_NULL()`, `DEVICE_DT_GET_ONE()` or `DEVICE_DT_GET_ANY()`. This idiom fetches the device pointer at build-time, which means there is no runtime penalty. This method is useful if you want to store the device pointer as configuration data. But because the device may not be initialized, or may have failed to initialize, you must verify that the device is ready to be used before passing it to any API functions. (This check is done for you by `device_get_binding()`.)

In some situations the device cannot be known at build-time, e.g., if it depends on user input like in a shell application. In this case you can get the `struct device` by combining `device_get_binding()` with the device name:

```c
const char *dev_name = /* TODO: insert device name from user */;
const struct device *uart_dev = device_get_binding(dev_name);
```

You can then use `uart_dev` with UART API functions like `uart_configure()`. Similar code will work for other device types; just make sure you use the correct API for the device.

5.2. Devicetree
If you're having trouble, see *Troubleshooting devicetree*. The first thing to check is that the node has status = "okay", like this:

```c
#define MY_SERIAL DT_NODELABEL(my_serial)

#if DT_NODE_HAS_STATUS(MY_SERIAL, okay)
    const struct device *const uart_dev = DEVICE_DT_GET(MY_SERIAL);
#else
    #error "Node is disabled"
#endif
```

If you see the #error output, make sure to enable the node in your devicetree. In some situations your code will compile but it will fail to link with a message similar to:

```
...undefined reference to `_device_dts_ord_N'
collect2: error: ld returned 1 exit status
```

This likely means there's a Kconfig issue preventing the device driver from being built, resulting in a reference that does not exist. If your code compiles successfully, the last thing to check is if the device is ready, like this:

```c
if (!device_is_ready(uart_dev)) {
    printk("Device not ready\n");
}
```

If you find that the device is not ready, it likely means that the device's initialization function failed. Enabling logging or debugging driver code may help in such situations. Note that you can also use `device_get_binding()` to obtain a reference at runtime. If it returns `NULL` it can either mean that device's driver failed to initialize or that it does not exist.

### Find a devicetree binding

Devicetree bindings are YAML files which declare what you can do with the nodes they describe, so it's critical to be able to find them for the nodes you are using.

If you don't have them already, *Get your devicetree and generated header*. To find a node's binding, open the generated header file, which starts with a list of nodes in a block comment:

```c
/*
 * [...]
 * Nodes in dependency order (ordinal and path):
 * 0 /
 * 1 /aliases
 * 2 /chosen
 * 3 /flash@0
 * 4 /memory@20000000
 * (etc.)
 * [...]
 */
```

Make note of the path to the node you want to find, like `/flash@0`. Search for the node's output in the file, which starts with something like this if the node has a matching binding:

```c
/*
 * Devicetree node:
 * /flash@0
 * * Binding (compatible = soc-nv-flash):
 *   $ZEPHYR_BASE/dts/bindings/mtd/soc-nv-flash.yaml
 * [...]
 */
```
See \textit{Check for missing bindings} for troubleshooting.

**Set devicetree overlays** Devicetree overlays are explained in \textit{Introduction to devicetree}. The CMake variable DTC\_OVERLAY\_FILE contains a space- or semicolon-separated list of overlay files to use. If DTC\_OVERLAY\_FILE specifies multiple files, they are included in that order by the C preprocessor. A file in a Zephyr module can be referred to by escaping the Zephyr module dir variable like \\
\$\{ZEPHYR\_<module>_MODULE\_DIR\}/\<path-to>/dts.overlay when setting the DTC\_OVERLAY\_FILE variable.

You can set DTC\_OVERLAY\_FILE to contain exactly the files you want to use. Here is an example using using west build.

If you don't set DTC\_OVERLAY\_FILE, the build system will follow these steps, looking for files in your application configuration directory to use as devicetree overlays:

1. If the file boards/<BOARD>.overlay exists, it will be used.
2. If the current board has multiple revisions and boards/<BOARD>_<revision>.overlay exists, it will be used. This file will be used in addition to boards/<BOARD>.overlay if both exist.
3. If one or more files have been found in the previous steps, the build system stops looking and just uses those files.
4. Otherwise, if <BOARD>.overlay exists, it will be used, and the build system will stop looking for more files.
5. Otherwise, if app.overlay exists, it will be used.

All configuration files will be taken from the application's configuration directory except for files with an absolute path that are given with the DTC\_OVERLAY\_FILE argument.

See Application Configuration Directory on how the application configuration directory is defined.

Using Shields will also add devicetree overlay files.

The DTC\_OVERLAY\_FILE value is stored in the CMake cache and used in successive builds.

The \textit{build system} prints all the devicetree overlays it finds in the configuration phase, like this:

```
-- Found devicetree overlay: .../some/file.overlay
```

**Use devicetree overlays** See \textit{Set devicetree overlays} for how to add an overlay to the build.

Overlays can override node property values in multiple ways. For example, if your BOARD.dts contains this node:

```
/ {
    soc {
        serial0: serial@40002000 {
            status = "okay";
            current-speed = <115200>;
        };
        /* ... */
    };
}
```

These are equivalent ways to override the current-speed value in an overlay:

```
/* Option 1 */
&serial0 {
    current-speed = <9600>;
};
```

(continues on next page)
/* Option 2 */
&{soc/serial@40002000} {
    current-speed = <9600>;
};

We'll use the &serial0 style for the rest of these examples.

You can add aliases to your devicetree using overlays: an alias is just a property of the /aliases node. For example:

/ {
    aliases {
        my-serial = &serial0;
    }
};

Chosen nodes work the same way. For example:

/ {
    chosen {
        zephyr,console = &serial0;
    }
};

To delete a property (in addition to deleting properties in general, this is how to set a boolean property to false if it's true in BOARD.dts):

&serial0 {
    /delete-property/ some-unwanted-property;
};

You can add subnodes using overlays. For example, to configure a SPI or I2C child device on an existing bus node, do something like this:

/* SPI device example */
&spi1 {
    my_spi_device: temp-sensor@0 {
        compatible = "...";
        label = "TEMP_SENSOR_0";
        /* reg is the chip select number, if needed;
         * If present, it must match the node's unit address. */
        reg = <0>;

        /* Configure other SPI device properties as needed.
         * Find your device's DT binding for details. */
        spi-max-frequency = <4000000>;
    }
};

/* I2C device example */
&i2c2 {
    my_i2c_device: touchscreen@76 {
        compatible = "...";
        label = "TOUCHSCREEN";
        /* reg is the I2C device address.
         * It must match the node's unit address. */
        reg = <76>;
    }
};

(continues on next page)
Other bus devices can be configured similarly:

- create the device as a subnode of the parent bus
- set its properties according to its binding

Assuming you have a suitable device driver associated with the `my_spi_device` and `my_i2c_device` compatibles, you should now be able to enable the driver via Kconfig and get the struct device for your newly added bus node, then use it with that driver API.

**Write device drivers using devicetree APIs**  “Devicetree-aware” device drivers should create a struct device for each status = “okay” devicetree node with a particular compatible (or related set of compatibles) supported by the driver.

Writing a devicetree-aware driver begins by defining a devicetree binding for the devices supported by the driver. Use existing bindings from similar drivers as a starting point. A skeletal binding to get started needs nothing more than this:

```plaintext
description: <Human-readable description of your binding>
compatible: "foo-company,bar-device"
include: base.yaml
```

See [Find a devicetree binding](#) for more advice on locating existing bindings.

After writing your binding, your driver C file can then use the devicetree API to find status = "okay" nodes with the desired compatible, and instantiate a struct device for each one. There are two options for instantiating each struct device: using instance numbers, and using node labels.

In either case:

- Each struct device's name should be set to its devicetree node's label property. This allows the driver's users to get a struct device from a devicetree node in the usual way.
- Each device's initial configuration should use values from devicetree properties whenever practical. This allows users to configure the driver using devicetree overlays.

Examples for how to do this follow. They assume you've already implemented the device-specific configuration and data structures and API functions, like this:

```c
/* my_driver.c */
#include <zephyr/drivers/some_api.h>

/* Define data (RAM) and configuration (ROM) structures: */
struct my_dev_data {
    /* per-device values to store in RAM */
};
struct my_dev_cfg {
    uint32_t freq; /* Just an example: initial clock frequency in Hz */
    /* other configuration to store in ROM */
};

/* Implement driver API functions (drivers/some_api.h callbacks): */
static int my_driver_api_func1(const struct device *dev, uint32_t *foo) {
    /* ... */
}
static int my_driver_api_func2(const struct device *dev, uint64_t bar) {
    /* ... */
}
```

(continues on next page)
static struct some_api my_api_funcs = {
    .func1 = my_driver_api_func1,
    .func2 = my_driver_api_func2,
};

Option 1: create devices using instance numbers  Use this option, which uses Instance-based APIs, if possible. However, they only work when devicetree nodes for your driver's compatible are all equivalent, and you do not need to be able to distinguish between them.

To use instance-based APIs, begin by defining DT_DRV_COMPAT to the lowercase-and-underscores version of the compatible that the device driver supports. For example, if your driver's compatible is "vnd, my-device" in devicetree, you would define DT_DRV_COMPAT to vnd_my_device in your driver C file:

/*
 * Put this near the top of the file. After the includes is a good place.
 * (Note that you can therefore run "git grep DT_DRV_COMPAT drivers" in
 * the zephyr Git repository to look for example drivers using this style).
 */
#define DT_DRV_COMPAT vnd_my_device

Important:  As shown, the DT_DRV_COMPAT macro should have neither quotes nor special characters. Remove quotes and convert special characters to underscores when creating DT_DRV_COMPAT from the compatible property.

Finally, define an instantiation macro, which creates each struct device using instance numbers. Do this after defining my_api_funcs.

/*
 * This instantiation macro is named "CREATE_MY_DEVICE".
 * Its "inst" argument is an arbitrary instance number.
 * 
 */
#define CREATE_MY_DEVICE(inst) 
    static struct my_dev_data my_data_##inst = { 
        /* initialize RAM values as needed, e.g.: */ 
        .freq = DT_INST_PROP(inst, clock_frequency), 
    }; 
    static const struct my_dev_cfg my_cfg_##inst = { 
        /* initialize ROM values as needed. */ 
    }; 
static const struct my_dev_data my_data = { 
    /* initialize RAM values as needed, e.g.: */ 
    .freq = DT_INST_PROP(drv_comp, clock_frequency), 
}; 
static const struct my_dev_cfg my_cfg = { 
    /* initialize ROM values as needed. */ 
}; 
DEVICE_DT_INST_DEFINE(inst, 
    my_dev_init_function, 
    NULL, 
    my_data_##inst, 
    my_cfg_##inst, 
    MY_DEV_INIT_LEVEL, MY_DEV_INIT_PRIORITY, 
    &my_api_funcs);

Notice the use of APIs like DT_INST_PROP() and DEVICE_DT_INST_DEFINE() to access devicetree node data. These APIs retrieve data from the devicetree for instance number inst of the node with compatible determined by DT_DRV_COMPAT.

Finally, pass the instantiation macro to DT_INST_FOREACH_STATUS_OKAY():

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/* Call the device creation macro for each instance: */
DT_INST_FOREACH_STATUS_OKAY(CREATE_MY_DEVICE)

DT_INST_FOREACH_STATUS_OKAY expands to code which calls CREATE_MYDEVICE once for each enabled node with the compatible determined by DT_DRV_COMPAT. It does not append a semicolon to the end of the expansion of CREATE_MYDEVICE, so the macro’s expansion must end in a semicolon or function definition to support multiple devices.

**Option 2: create devices using node labels** Some device drivers cannot use instance numbers. One example is an SoC peripheral driver which relies on vendor HAL APIs specialized for individual IP blocks to implement Zephyr driver callbacks. Cases like this should use DT_NODELABEL to refer to individual nodes in the devicetree representing the supported peripherals on the SoC. The devicetree.h Generic APIs can then be used to access node data.

For this to work, your SoC’s dti file must define node labels like mydevice0, mydevice1, etc. appropriately for the IP blocks your driver supports. The resulting devicetree usually looks something like this:

```c
/ {
    soc {
        mydevice0: dev00 {
            compatible = "vnd,my-device";
        };
        mydevice1: dev01 {
            compatible = "vnd,my-device";
        };
    };
}
```

The driver can use the mydevice0 and mydevice1 node labels in the devicetree to operate on specific device nodes:

```c
/*
 * This is a convenience macro for creating a node identifier for
 * the relevant devices. An example use is MYDEV(0) to refer to
 * the node with label "mydevice0".
 */
#define MYDEV(idx) DT_NODELABEL(mydevice ## idx)

/*
 * Define your instantiation macro; "idx" is a number like 0 for mydevice0
 * or 1 for mydevice1. It uses MYDEV() to create the node label from the
 * index.
 */
#define CREATE_MY_DEVICE(idx) static struct my_dev_data my_data_##idx = { 
    .freq = DT_PROP(MYDEV(idx), clock_frequency),
};
static const struct my_dev_cfg my_cfg_##idx = { /* ... */ }; DEVICE_DT_DEFINE(MYDEV(idx),
    my_dev_init_function,
    NULL,
    &my_data_##idx,
    &my_cfg_##idx,
    MY_DEV_INIT_LEVEL, MY_DEV_INIT_PRIORITY,
    &my_api_funcs)
```
Notice the use of APIs like `DT_PROP()` and `DEVICE_DT_DEFINE()` to access devicetree node data.

Finally, manually detect each enabled devicetree node and use `CREATE_MY_DEVICE` to instantiate each struct device:

```c
#if DT_NODE_HAS_STATUS(DT_NODELABEL(mydevice0), okay)
CREATE_MY_DEVICE(0)
#endif

#if DT_NODE_HAS_STATUS(DT_NODELABEL(mydevice1), okay)
CREATE_MY_DEVICE(1)
#endif
```

Since this style does not use `DT_INST_FOREACH_STATUS_OKAY()`, the driver author is responsible for calling `CREATE_MY_DEVICE()` for every possible node, e.g. using knowledge about the peripherals available on supported SoCs.

**Device drivers that depend on other devices** At times, one struct device depends on another struct device and requires a pointer to it. For example, a sensor device might need a pointer to its SPI bus controller device. Some advice:

- Write your devicetree binding in a way that permits use of `Hardware specific APIs` from `devicetree.h` if possible.
- In particular, for bus devices, your driver's binding should include a file like `dts/bindings/spi/spi-device.yaml` which provides common definitions for devices addressable via a specific bus. This enables use of APIs like `DT_BUS()` to obtain a node identifier for the bus node. You can then get a struct device from a devicetree node for the bus in the usual way.

Search existing bindings and device drivers for examples.

**Applications that depend on board-specific devices** One way to allow application code to run unmodified on multiple boards is by supporting a devicetree alias to specify the hardware specific portions, as is done in the blinky-sample. The application can then be configured in `BOARD.dts` files or via device-tree overlays.

**Troubleshooting devicetree**

Here are some tips for fixing misbehaving devicetree related code.

See Devicetree HOWTOs for other “HOWTO” style information.

**Try again with a pristine build directory**

**Important:** Try this first, before doing anything else.

See Pristine Builds for examples, or just delete the build directory completely and retry.

This is general advice which is especially applicable to debugging devicetree issues, because the outputs are created during the CMake configuration phase, and are not always regenerated when one of their inputs changes.

**Make sure `<devicetree.h>` is included** Unlike Kconfig symbols, the `devicetree.h` header must be included explicitly.

Many Zephyr header files rely on information from devicetree, so including some other API may transiently include `devicetree.h`, but that's not guaranteed.
Make sure you're using the right names  

Remember that:

- In C/C++, devicetree names must be lowercased and special characters must be converted to underscores. Zephyr's generated devicetree header has DTS names converted in this way into the C tokens used by the preprocessor-based `<devicetree.h>` API.

- In overlays, use devicetree node and property names the same way they would appear in any DTS file. Zephyr overlays are just DTS fragments.

For example, if you're trying to get the `clock-frequency` property of a node with path `/soc/i2c@12340000` in a C/C++ file:

```c
/*
 * foo.c: lowercase-and-underscores names
 */

/* Don't do this: */
#define MY_CLOCK_FREQ DT_PROP(DT_PATH(soc, i2c@12340000), clock-frequency)
/*
 * @ should be _ - should be _ */

/* Do this instead: */
#define MY_CLOCK_FREQ DT_PROP(DT_PATH(soc, i2c_12340000), clock_frequency)
/*
 * ^ ^ */
```

And if you're trying to set that property in a devicetree overlay:

```c
/*
 * foo.overlay: DTS names with special characters, etc.
 */

/* Don't do this; you'll get devicetree errors. */
k{/soc/i2c_12340000/} {
    clock-frequency = <115200>;
};

/* Do this instead. Overlays are just DTS fragments. */
k{/soc/i2c@12340000/} {
    clock-frequency = <115200>;
};
```

Look at the preprocessor output  

To save preprocessor output when using GCC-based toolchains, add `-save-temps=obj` to the `EXTRA_CFLAGS` CMake variable. For example, to build hello_world with west with this option set, use:

```
west build -b BOARD samples/hello_world -- -DEXTRA_CFLAGS=-save-temps=obj
```

This will create a preprocessor output file named `foo.c.i` in the build directory for each source file `foo.c`.

You can then search for the file in the build directory to see what your devicetree macros expanded to. For example, on macOS and Linux, using `find` to find `main.c.i`:

```
$ find build -name main.c.i
build/CMakeFiles/app.dir/src/main.c.i
```

It's usually easiest to run a style formatter on the results before opening them. For example, to use `clang-format` to reformat the file in place:
You can then open the file in your favorite editor to view the final C results after preprocessing.

**Validate properties**  If you're getting a compile error reading a node property, check your node identifier and property. For example, if you get a build error on a line that looks like this:

```c
int baud_rate = DT_PROP(DT_NODELABEL(my_serial), current_speed);
```

Try checking the node by adding this to the file and recompiling:

```c
#if !DT_NODE_EXISTS(DT_NODELABEL(my_serial))
#error "whoops"
#endif
```

If you see the "whoops" error message when you rebuild, the node identifier isn't referring to a valid node. *Get your devicetree and generated header* and debug from there.

Some hints for what to check next if you don’t see the "whoops" error message:

* did you *Make sure you’re using the right names*?
* does the *property exist*?
* does the node have a *matching binding*?
* does the binding define the property?

**Check for missing bindings**  See *Devicetree bindings* for information about bindings, and *Bindings index* for information on bindings built into Zephyr.

If the build fails to *Find a devicetree binding* for a node, then either the node's compatible property is not defined, or its value has no matching binding. If the property is set, check for typos in its name. In a devicetree source file, compatible should look like "vnd,some-device" – *Make sure you're using the right names*.

If your binding file is not under zephyr/dts, you may need to set `DTS_ROOT`; see *Where bindings are located*.

**Errors with DT_INST() APIs**  If you're using an API like `DT_INST_PROP()`, you must define `DT_DRV_COMPAT` to the lowercase-and-underscores version of the compatible you are interested in. See *Option 1: create devices using instance numbers*.

**Devicetree versus Kconfig**

Along with devicetree, Zephyr also uses the Kconfig language to configure the source code. Whether to use devicetree or Kconfig for a particular purpose can sometimes be confusing. This section should help you decide which one to use.

In short:

* Use devicetree to describe *hardware* and its *boot-time configuration*. Examples include peripherals on a board, boot-time clock frequencies, interrupt lines, etc.
* Use Kconfig to configure *software support* to build into the final image. Examples include whether to add networking support, which drivers are needed by the application, etc.

In other words, devicetree mainly deals with hardware, and Kconfig with software.

For example, consider a board containing a SoC with 2 UART, or serial port, instances.
• The fact that the board has this UART hardware is described with two UART nodes in the device-tree. These provide the UART type (via the compatible property) and certain settings such as the address range of the hardware peripheral registers in memory (via the reg property).

• Additionally, the UART boot-time configuration is also described with devicetree. This could include configuration such as the RX IRQ line’s priority and the UART baud rate. These may be modifiable at runtime, but their boot-time configuration is described in devicetree.

• Whether or not to include software support for UART in the build is controlled via Kconfig. Applications which do not need to use the UARTs can remove the driver source code from the build using Kconfig, even though the board’s devicetree still includes UART nodes.

As another example, consider a device with a 2.4GHz, multi-protocol radio supporting both the Bluetooth Low Energy and 802.15.4 wireless technologies.

• Devicetree should be used to describe the presence of the radio hardware, what driver or drivers it’s compatible with, etc.

• Boot-time configuration for the radio, such as TX power in dBm, should also be specified using devicetree.

• Kconfig should determine which software features should be built for the radio, such as selecting a BLE or 802.15.4 protocol stack.

As another example, Kconfig options that formerly enabled a particular instance of a driver (that is itself enabled by Kconfig) have been removed. The devices are selected individually using devicetree’s status keyword on the corresponding hardware instance.

There are exceptions to these rules:

• Because Kconfig is unable to flexibly control some instance-specific driver configuration parameters, such as the size of an internal buffer, these options may be defined in devicetree. However, to make clear that they are specific to Zephyr drivers and not hardware description or configuration these properties should be prefixed with zephyr, e.g., zephyr,random-mac-address in the common Ethernet devicetree properties.

• Devicetree’s chosen keyword, which allows the user to select a specific instance of a hardware device to be used for a particular purpose. An example of this is selecting a particular UART for use as the system’s console.

5.2.2 Devicetree Reference

These pages contain reference material for Zephyr’s devicetree APIs and built-in bindings.

For the platform-independent details, see the Devicetree specification.

Devicetree API

This is a reference page for the <devicetree.h> API. The API is macro based. Use of these macros has no impact on scheduling. They can be used from any calling context and at file scope.

Some of these require a special macro named DT_DRV_COMPAT to be defined before they can be used; these are discussed individually below. These macros are generally meant for use within device drivers, though they can be used outside of drivers with appropriate care.

Contents

• Generic APIs
  – Node identifiers and helpers
  – Property access
- `ranges` property
- `reg` property
- `interrupts` property
- For-each macros
- Existence checks
- Inter-node dependencies
- Bus helpers

- **Instance-based APIs**

- **Hardware specific APIs**
  - CAN
  - Clocks
  - DMA
  - Fixed flash partitions
  - GPIO
  - IO channels
  - MBOX
  - Pinctrl (pin control)
  - PWM
  - Reset Controller
  - SPI

- **Chosen nodes**

- **Zephyr-specific chosen nodes**

---

**Generic APIs**  The APIs in this section can be used anywhere and do not require `DT_DRV_COMPAT` to be defined.

**Node identifiers and helpers**  A node identifier is a way to refer to a devicetree node at C preprocessor time. While node identifiers are not C values, you can use them to access devicetree data in C rvalue form using, for example, the `Property access` API.

The root node `/` has node identifier `DT_ROOT`. You can create node identifiers for other devicetree nodes using `DT_PATH()`, `DT_NODELABEL()`, `DT_ALIAS()`, and `DT_INST()`.

There are also `DT_PARENT()` and `DT_CHILD()` macros which can be used to create node identifiers for a given node's parent node or a particular child node, respectively.

The following macros create or operate on node identifiers.

```c
group devicetree-generic-id
```

**Defines**

```c
DT_INVALID_NODE
Name for an invalid node identifier.
```
This supports cases where factored macros can be invoked from paths where devicetree data may or may not be available. It is a preprocessor identifier that does not match any valid devicetree node identifier.

**DT_ROOT**

Node identifier for the root node in the devicetree.

**DT_PATH(...)**

Get a node identifier for a devicetree path.

The arguments to this macro are the names of non-root nodes in the tree required to reach the desired node, starting from the root. Non-alphanumeric characters in each name must be converted to underscores to form valid C tokens, and letters must be lowercased.

Example devicetree fragment:

```
/ {
  soc {
    serial1: serial@40001000 {
      status = "okay";
      current-speed = <115200>;
      ...
    }
  }
};
```

You can use `DT_PATH(soc, serial_40001000)` to get a node identifier for the `serial@40001000` node. Node labels like `serial1` cannot be used as `DT_PATH()` arguments; use `DT_NODELABEL()` for those instead.

Example usage with `DT_PROP()` to get the `current-speed` property:

```
DT_PROP(DT_PATH(soc, serial_40001000), current_speed) // 115200
```

(The `current-speed` property is also in lowercase-and-underscores form when used with this API.)

When determining arguments to `DT_PATH()`:

- the first argument corresponds to a child node of the root (`soc` above)
- a second argument corresponds to a child of the first argument (`serial_40001000` above, from the node name `serial@40001000` after lowercasing and changing @ to _)
- and so on for deeper nodes in the desired node's path

**Note:** This macro returns a node identifier from path components. To get a path string from a node identifier, use `DT_NODE_PATH()` instead.

**Parameters**

- `...` – lowercase-and-underscores node names along the node's path, with each name given as a separate argument
**Returns**

node identifier for the node with that path

\[ \text{DT_NODELABEL}(\text{label}) \]

Get a node identifier for a node label.

Convert non-alphanumeric characters in the node label to underscores to form valid C tokens, and lowercase all letters. Note that node labels are not the same thing as label properties.

Example devicetree fragment:

```
serial1: serial@40001000 {
    label = "UART_0";
    status = "okay";
    current-speed = <115200>;
    ...
};
```

The only node label in this example is `serial1`.

The string `UART_0` is not a node label; it's the value of a property named `label`.

You can use `DT_NODELABEL(serial1)` to get a node identifier for the `serial@40001000` node.

Example usage with `DT_PROP()` to get the current-speed property:

```
DT_PROP(DT_NODELABEL(serial1), current_speed) // 115200
```

Another example devicetree fragment:

```
cpu@0 {
    L2_0: l2-cache {
        cache-level = <2>;
        ...
    };
};
```

Example usage to get the cache-level property:

```
DT_PROP(DT_NODELABEL(12_0), cache_level) // 2
```

Notice how `L2_0` in the devicetree is lowercased to `12_0` in the `DT_NODELABEL()` argument.

**Parameters**

- `label` – lowercase-and-underscores node label name

**Returns**

node identifier for the node with that label

\[ \text{DT_ALIAS}(\text{alias}) \]

Get a node identifier from `/aliases`.

This macro's argument is a property of the `/aliases` node. It returns a node identifier for the node which is aliased. Convert non-alphanumeric characters in the alias property to underscores to form valid C tokens, and lowercase all letters.

Example devicetree fragment:
You can use `DT_ALIAS(my_serial)` to get a node identifier for the serial@40001000 node. Notice how `my-serial` in the devicetree becomes `my_serial` in the `DT_ALIAS()` argument. Example usage with `DT_PROP()` to get the current-speed property:

```
DT_PROP(DT_ALIAS(my_serial), current_speed)  // 115200
```

### Parameters

- alias – lowercase-and-underscores alias name.

### Returns

Node identifier for the node with that alias

**DT_INST(inst, compat)**

Get a node identifier for an instance of a compatible.

All nodes with a particular compatible property value are assigned instance numbers, which are zero-based indexes specific to that compatible. You can get a node identifier for these nodes by passing `DT_INST()` an instance number, `inst`, along with the lowercase-and-underscores version of the compatible, `compat`.

Instance numbers have the following properties:

- for each compatible, instance numbers start at 0 and are contiguous
- exactly one instance number is assigned for each node with a compatible, including disabled nodes
- enabled nodes (status property is `okay` or missing) are assigned the instance numbers starting from 0, and disabled nodes have instance numbers which are greater than those of any enabled node

No other guarantees are made. In particular:

- instance numbers **in no way reflect** any numbering scheme that might exist in SoC documentation, node labels or unit addresses, or properties of the /aliases node (use `DT_NODELABEL()` or `DT_ALIAS()` for those)
- there is **no general guarantee** that the same node will have the same instance number between builds, even if you are building the same application again in the same build directory
Example devicetree fragment:

```c
serial1: serial@40001000 {
    compatible = "vnd,soc-serial";
    status = "disabled";
    current-speed = <9600>;
    ...
};

serial2: serial@40002000 {
    compatible = "vnd,soc-serial";
    status = "okay";
    current-speed = <57600>;
    ...
};

serial3: serial@40003000 {
    compatible = "vnd,soc-serial";
    current-speed = <115200>;
    ...
};
```

Assuming no other nodes in the devicetree have compatible "vnd,soc-serial", that compatible has nodes with instance numbers 0, 1, and 2.

The nodes serial@40002000 and serial@40003000 are both enabled, so their instance numbers are 0 and 1, but no guarantees are made regarding which node has which instance number.

Since serial@40001000 is the only disabled node, it has instance number 2, since disabled nodes are assigned the largest instance numbers. Therefore:

```c
// Could be 57600 or 115200. There is no way to be sure:
// either serial@40002000 or serial@40003000 could
// have instance number 0, so this could be the current-speed
// property of either of those nodes.
DT_PROP(DT_INST(0, vnd_soc_serial), current_speed)

// Could be 57600 or 115200, for the same reason.
// If the above expression expands to 57600, then
// this expands to 115200, and vice-versa.
DT_PROP(DT_INST(1, vnd_soc_serial), current_speed)

// 9600, because there is only one disabled node, and
// disabled nodes are "at the end" of the instance
// number "list".
DT_PROP(DT_INST(2, vnd_soc_serial), current_speed)
```

Notice how "vnd,soc-serial" in the devicetree becomes vnd_soc_serial (without quotes) in the `DT_INST()` arguments. (As usual, current-speed in the devicetree becomes current_speed as well.)

Nodes whose compatible property has multiple values are assigned independent instance numbers for each compatible.

**Parameters**

- `inst` – instance number for compatible `compat`
• compat – lowercase-and-underscores compatible, without quotes

**Returns**

node identifier for the node with that instance number and compatible

\texttt{DT\_PARENT(node\_id)}

Get a node identifier for a parent node.

Example devicetree fragment:

```plaintext
parent: parent-node {
    child: child-node {
        ...
    };
};
```

The following are equivalent ways to get the same node identifier:

- \texttt{DT\_NODELABEL(parent)}
- \texttt{DT\_PARENT(DT\_NODELABEL(child))}

**Parameters**

- \texttt{node\_id} – node identifier

**Returns**

a node identifier for the node's parent

\texttt{DT\_GPARENT(node\_id)}

Get a node identifier for a grandparent node.

Example devicetree fragment:

```plaintext
gparent: grandparent-node {
    parent: parent-node {
        child: child-node { ... }
    };
};
```

The following are equivalent ways to get the same node identifier:

- \texttt{DT\_GPARENT(DT\_NODELABEL(child))}
- \texttt{DT\_PARENT(DT\_PARENT(DT\_NODELABEL(child))}

**Parameters**

- \texttt{node\_id} – node identifier

**Returns**

a node identifier for the node's parent's parent

\texttt{DT\_CHILD(node\_id, child)}

Get a node identifier for a child node.

Example devicetree fragment:
Example usage with `DT_PROP()` to get the status of the serial@40001000 node:

```c
#define SOC_NODE DT_NODELABEL(soc_label)
DT_PROP(DT_CHILD(SOC_NODE, serial_40001000), status) // "okay"
```

Node labels like `serial1` cannot be used as the child argument to this macro. Use `DT_NODELABEL()` for that instead.

You can also use `DT_FOREACH_CHILD()` to iterate over node identifiers for all of a node’s children.

**Parameters**

- `node_id` – node identifier
- `child` – lowercase-and-underscores child node name

**Returns**

node identifier for the node with the name referred to by ‘child’

**Example devicetree fragment:**

```
node-a {
    compatible = "vnd,device";
    status = "okay";
};

node-b {
    compatible = "vnd,device";
    status = "okay";
};

node-c {
    compatible = "vnd,device";
    status = "disabled";
};
```

**Example usage:**

```c
DT_COMPAT_GET_ANY_STATUS_OKAY(vnd_device)
```
This expands to a node identifier for either node-a or node-b. It will not expand to a node identifier for node-c, because that node does not have status okay.

**Parameters**
- compat – lowercase-and-underscores compatible, without quotes

**Returns**
node identifier for a node with that compatible, or DT_INVALID_NODE

**DT_NODE_PATH(node_id)**
Get a devicetree node's full path as a string literal.

This returns the path to a node from a node identifier. To get a node identifier from path components instead, use DT_PATH().

Example devicetree fragment:

```plaintext
/ {
  soc {
    node: my-node@12345678 { ... };
  };
};
```

Example usage:

```plaintext
DT_NODE_PATH(DT_NODELABEL(node)) // "/soc/my-node@12345678"
DT_NODE_PATH(DT_PATH(soc)) // "/soc"
DT_NODE_PATH(DT_ROOT) // "/
```

**Parameters**
- node_id – node identifier

**Returns**
the node's full path in the devicetree

**DT_NODE_FULL_NAME(node_id)**
Get a devicetree node's name with unit-address as a string literal.

This returns the node name and unit-address from a node identifier.

Example devicetree fragment:

```plaintext
/ {
  soc {
    node: my-node@12345678 { ... };
  };
};
```

Example usage:

```plaintext
DT_NODE_FULL_NAME(DT_NODELABEL(node)) // "my-node@12345678"
```

**Parameters**
- node_id – node identifier
**Returns**

the node's name with unit-address as a string in the devicetree

\[ \text{DT_NODE_NAME}(\text{node_id}) \]

Get a devicetree node's name and its unit-address as a string.

**Parameters**

- \( \text{node_id} \) – node identifier

**Returns**

the node's name with unit-address as a string in the devicetree

\[ \text{DT_NODE_ADDRESS}(\text{node_id}) \]

Get a devicetree node's address.

**Parameters**

- \( \text{node_id} \) – node identifier

**Returns**

the node's address in the devicetree

\[ \text{DT_NODE_CHILD_IDX}(\text{node_id}) \]

Get a devicetree node's index into its parent's list of children.

Indexes are zero-based.

It is an error to use this macro with the root node.

Example devicetree fragment:

```
parent {
    c1: child-1 {};
    c2: child-2 {};
};
```

Example usage:

```
DT_NODE_CHILD_IDX(DT_NODELABEL(c1))  // 0
DT_NODE_CHILD_IDX(DT_NODELABEL(c2))  // 1
```

**Parameters**

- \( \text{node_id} \) – node identifier

**Returns**

the node's index in its parent node's list of children

\[ \text{DT_SAME_NODE}(\text{node_id1}, \text{node_id2}) \]

Do \( \text{node_id1} \) and \( \text{node_id2} \) refer to the same node?

Both \( \text{node_id1} \) and \( \text{node_id2} \) must be node identifiers for nodes that exist in the devicetree (if unsure, you can check with \( \text{DT_NODE_EXISTS()} \)).

The expansion evaluates to 0 or 1, but may not be a literal integer 0 or 1.

**Parameters**

- \( \text{node_id1} \) – first node identifier
- \( \text{node_id2} \) – second node identifier

**Returns**

an expression that evaluates to 1 if the node identifiers refer to the same node, and evaluates to 0 otherwise

**Property access**

The following general-purpose macros can be used to access node properties. There are special-purpose APIs for accessing the \( \text{ranges property} \), \( \text{reg property} \) and \( \text{interrupts property} \).

Property values can be read using these macros even if the node is disabled, as long as it has a matching binding.

```
group devicetree-generic-prop
```
Defines

**DT_PROP(node_id, prop)**

Get a devicetree property value.

For properties whose bindings have the following types, this macro expands to:

- **string**: a string literal
- **boolean**: 0 if the property is false, or 1 if it is true
- **int**: the property's value as an integer literal
- **array, uint8-array, string-array**: an initializer expression in braces, whose elements are integer or string literals (like `{0, 1, 2}, {"hello", "world"}`, etc.)
- **phandle**: a node identifier for the node with that phandle

A property's type is usually defined by its binding. In some special cases, it has an assumed type defined by the devicetree specification even when no binding is available: `compatible` has type `string-array`, `status` has type `string`, and `interrupt-controller` has type `boolean`.

For other properties or properties with unknown type due to a missing binding, behavior is undefined.

For usage examples, see `DT_PATH()`, `DT_ALIAS()`, `DT_NODELABEL()`, and `DT_INST()` above.

**Parameters**

- **node_id** – node identifier
- **prop** – lowercase-and-underscores property name

**Returns**

a representation of the property's value

**DT_PROP_LEN(node_id, prop)**

Get a property's logical length.

Here, "length" is a number of elements, which may differ from the property's size in bytes.

The return value depends on the property's type:

- for types `array`, `string-array`, and `uint8-array`, this expands to the number of elements in the array
- for type phandles, this expands to the number of phandles
- for type phandle-array, this expands to the number of phandle and specifier blocks in the property

These properties are handled as special cases:

- reg property: use `DT_NUM_REGS(node_id)` instead
- interrupts property: use `DT_NUM_IRQS(node_id)` instead

It is an error to use this macro with the `ranges`, `dma-ranges`, `reg` or `interrupts` properties.

For other properties, behavior is undefined.

**Parameters**

- **node_id** – node identifier
- **prop** – a lowercase-and-underscores property with a logical length
Returns the property's length

DT_PROP_LEN_OR(node_id, prop, default_value)

Like DT_PROP_LEN(), but with a fallback to default_value.

If the property is defined (as determined by DT_NODE_HAS_PROP()), this expands to DT_PROP_LEN(node_id, prop). The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

Parameters

• node_id – node identifier
• prop – a lowercase-and-underscores property with a logical length
• default_value – a fallback value to expand to

Returns the property's length or the given default value

DT_PROP_HAS_IDX(node_id, prop, idx)

Is index idx valid for an array type property?

If this returns 1, then DT_PROP_BY_IDX(node_id, prop, idx) or DT_PHA_BY_IDX(node_id, prop, idx, ...) are valid at index idx. If it returns 0, it is an error to use those macros with that index.

These properties are handled as special cases:

• reg property: use DT_REG_HAS_IDX(node_id, idx) instead
• interrupts property: use DT_IRQ_HAS_IDX(node_id, idx) instead

It is an error to use this macro with the reg or interrupts properties.

Parameters

• node_id – node identifier
• prop – a lowercase-and-underscores property with a logical length
• idx – index to check

Returns An expression which evaluates to 1 if idx is a valid index into the given property, and 0 otherwise.

DT_PROP_HAS_NAME(node_id, prop, name)

Is name name available in a foo-names property?

This property is handled as special case:

• interrupts property: use DT_IRQ_HAS_NAME(node_id, idx) instead

It is an error to use this macro with the interrupts property.

Example devicetree fragment:

```c
nx: node-x {
    foos = <&bar xx yy>, <&baz xx zz>;
    foo-names = "event", "error";
    status = "okay";
};
```
Example usage:

```
DT_PROP_HAS_NAME(nx, foos, event)  // 1
DT_PROP_HAS_NAME(nx, foos, failure)  // 0
```

**Parameters**
- `node_id` – node identifier
- `prop` – a lowercase-and-underscores `prop-names` type property
- `name` – a lowercase-and-underscores name to check

**Returns**
An expression which evaluates to 1 if “name” is an available name into the given property, and 0 otherwise.

```
DT_PROP_BYIDX(node_id, prop, idx)
```

Get the value at index `idx` in an array type property.

It might help to read the argument order as being similar to `node->property[index]`.

When the property’s binding has type array, string-array, uint8-array, or phandles, this expands to the `idx`-th array element as an integer, string literal, or node identifier respectively.

These properties are handled as special cases:

- `reg` property: use `DT_REG_ADDR_BY_IDX()` or `DT_REG_SIZE_BY_IDX()` instead
- `interrupts` property: use `DT_IRQ_BY_IDX()` instead

For non-array properties, behavior is undefined.

**Parameters**
- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – the index to get

**Returns**
a representation of the `idx`-th element of the property

```
DT_PROP_OR(node_id, prop, default_value)
```

Like `DT_PROP()`, but with a fallback to `default_value`.

If the value exists, this expands to `DT_PROP(node_id, prop)`. The `default_value` parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**
- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `default_value` – a fallback value to expand to

**Returns**
the property's value or `default_value`
DT_LABEL(node_id)

Equivalent to \( \text{DT_PROP}(\text{node_id, label}) \)

{
\textit{Deprecated:}

Use \( \text{DT_PROP}(\text{node_id, label}) \)

This is a convenience for the Zephyr device API, which uses label properties as \( \text{device_get_binding()} \) arguments.

\textbf{Parameters}

- node_id – node identifier

\textbf{Returns}

node's label property value

\textbf{DT_ENUM_IDX}(node_id, prop)

Get a property value's index into its enumeration values.

The return values start at zero.

Example devicetree fragment:

```plaintext
usb1: usb@12340000 {
   maximum-speed = "full-speed";
};
usb2: usb@12341000 {
   maximum-speed = "super-speed";
};
```

Example bindings fragment:

```plaintext
properties:
   maximum-speed:
      type: string
      enum:
         - "low-speed"
         - "full-speed"
         - "high-speed"
         - "super-speed"
```

Example usage:

```plaintext
\text{DT_ENUM_IDX(DT_NODELABEL(usb1), maximum_speed)} // 1
\text{DT_ENUM_IDX(DT_NODELABEL(usb2), maximum_speed)} // 3
```

\textbf{Parameters}

- node_id – node identifier

- prop – lowercase-and-underscores property name

\textbf{Returns}

zero-based index of the property's value in its enum: list
DT_ENUM_IDX_OR(node_id, prop, default_idx_value)

Like DT_ENUM_IDX(), but with a fallback to a default enum index.

If the value exists, this expands to its zero based index value thanks to DT_ENUM_IDX(node_id, prop).

Otherwise, this expands to provided default index enum value.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
- default_idx_value – a fallback index value to expand to

**Returns**

zero-based index of the property's value in its enum if present, default_idx_value otherwise

DT_STRING_TOKEN(node_id, prop)

Get a string property's value as a token.

This removes “the quotes” from a string property's value, converting any non-alphanumeric characters to underscores. This can be useful, for example, when programmatically using the value to form a C variable or code.

**DT_STRING_TOKEN()** can only be used for properties with string type.

It is an error to use **DT_STRING_TOKEN()** in other circumstances.

Example devicetree fragment:

```plaintext
n1: node-1 {
    prop = "foo";
};
n2: node-2 {
    prop = "FOO";
}
n3: node-3 {
    prop = "123 foo";
};
```

Example bindings fragment:

```plaintext
properties:
    prop:
        type: string
```

Example usage:

```c
DT_STRING_TOKEN(DT_NODELABEL(n1), prop) // foo
DT_STRING_TOKEN(DT_NODELABEL(n2), prop) // FOO
DT_STRING_TOKEN(DT_NODELABEL(n3), prop) // 123_foo
```

Notice how:

- Unlike C identifiers, the property values may begin with a number. It's the user's responsibility not to use such values as the name of a C identifier.
• The uppercased "F00" in the DTS remains F00 as a token. It is not converted to foo.
• The whitespace in the DTS "123 foo" string is converted to 123_foo as a token.

Parameters
  • node_id – node identifier
  • prop – lowercase-and-underscores property name

Returns
  the value of prop as a token, i.e. without any quotes and with special characters
  converted to underscores

 DT_STRING_TOKEN_OR(node_id, prop, default_value)
  Like DT_STRING_TOKEN(), but with a fallback to default_value.
  If the value exists, this expands to DT_STRING_TOKEN(node_id, prop). The default_value
  parameter is not expanded in this case.
  Otherwise, this expands to default_value.

Parameters
  • node_id – node identifier
  • prop – lowercase-and-underscores property name
  • default_value – a fallback value to expand to

Returns
  the property's value as a token, or default_value

 DT_STRING_UPPER_TOKEN(node_id, prop)
  Like DT_STRING_TOKEN(), but uppercased.
  This removes “the quotes” from a string property's value, converting any non-alphanumeric
  characters to underscores, and capitalizing the result. This can be useful, for example, when
  programmatically using the value to form a C variable or code.
  DT_STRING_UPPER_TOKEN() can only be used for properties with string type.
  It is an error to use DT_STRING_UPPER_TOKEN() in other circumstances.

Example devicetree fragment:

```
n1: node-1 {
    prop = "foo";
};
n2: node-2 {
    prop = "123 foo";
};
```

Example bindings fragment:

```
properties:
    prop:
        type: string
```

Example usage:
Notice how:

- Unlike C identifiers, the property values may begin with a number. It's the user's responsibility not to use such values as the name of a C identifier.
- The lowercased "foo" in the DTS becomes FOO as a token, i.e. it is uppercased.
- The whitespace in the DTS "123 foo" string is converted to 123_FOO as a token, i.e. it is uppercased and whitespace becomes an underscore.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name

**Returns**

the value of prop as an uppercased token, i.e. without any quotes and with special characters converted to underscores

DT_STRING_UPPER_TOKEN_OR(node_id, prop, default_value)

Like DT_STRING_UPPER_TOKEN(), but with a fallback to default_value.

If the value exists, this expands to DT_STRING_UPPER_TOKEN(node_id, prop). The default_value parameter is not expanded in this case. Otherwise, this expands to default_value.

**Parameters**

- node_id – node identifier
- prop – lowercase-and-underscores property name
- default_value – a fallback value to expand to

**Returns**

the property's value as an uppercased token, or default_value

DT_STRING_TOKEN_BY_IDX(node_id, prop, idx)

Get an element out of a string-array property as a token.

This removes “the quotes” from an element in the array, and converts non-alphanumeric characters to underscores. That can be useful, for example, when programmatically using the value to form a C variable or code.

DT_STRING_TOKEN_BY_IDX() can only be used for properties with string-array type.

It is an error to use DT_STRING_TOKEN_BY_IDX() in other circumstances.

Example devicetree fragment:

```plaintext
n1: node-1 {
    prop = "f1", "F2";
};
n2: node-2 {
    prop = "123 foo", "456 FOO";
};
```
Example bindings fragment:

```c
properties:
  prop:
    type: string-array
```

Example usage:

```c
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 0) // f1
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n1), prop, 1) // F2
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 0) // 123_foo
DT_STRING_TOKEN_BY_IDX(DT_NODELABEL(n2), prop, 1) // 456_FOO
```

For more information, see `DT_STRING_TOKEN`.

**Parameters**

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – the index to get

**Returns**

the element in `prop` at index `idx` as a token

```c
DT_STRING_UPPER_TOKEN_BY_IDX(node_id, prop, idx)
```

Like `DT_STRING_TOKEN_BY_IDX()`, but uppercased.

This removes “the quotes” and capitalizes an element in the array, and converts non-alphanumeric characters to underscores. That can be useful, for example, when programmatically using the value to form a C variable or code.

`DT_STRING_UPPER_TOKEN_BY_IDX()` can only be used for properties with string-array type.

It is an error to use `DT_STRING_UPPER_TOKEN_BY_IDX()` in other circumstances.

Example devicetree fragment:

```c
n1: node-1 {
  prop = "f1", "F2";
};
n2: node-2 {
  prop = "123 foo", "456 F00";
};
```

Example bindings fragment:

```c
properties:
  prop:
    type: string-array
```

Example usage:
For more information, see `DT_STRING_UPPER_TOKEN`.

Parameters

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – the index to get

Returns
the element in `prop` at index `idx` as an uppercased token

```
DT_PROP_BY_PHANDLE_IDX(node_id, phs, idx, prop)
```

Get a property value from a phandle in a property.

This is a shorthand for:

```
DT_PROP(DT_PHANDLE_BY_IDX(node_id, phs, idx), prop)
```

That is, `prop` is a property of the phandle's node, not a property of `node_id`.

Example devicetree fragment:

```
n1: node-1 {
    foo = <&n2 &n3>;
};
n2: node-2 {
    bar = <42>;
};
n3: node-3 {
    baz = <43>;
};
```

Example usage:

```
#define N1 DT_NODELABEL(n1)
DT_PROP_BY_PHANDLE_IDX(N1, foo, 0, bar) // 42
DT_PROP_BY_PHANDLE_IDX(N1, foo, 1, baz) // 43
```

Parameters

- `node_id` – node identifier
- `phs` – lowercase-and-underscores property with type `phandle`, `phandles`, or `phandle-array`
- `idx` – logical index into `phs`, which must be zero if `phs` has type `phandle`
- `prop` – lowercase-and-underscores property of the phandle's node
**Returns**

the property's value

DT_PROP_BY_PHANDLE_IDX_OR(node_id, phs, idx, prop, default_value)

Like DT_PROP_BY_PHANDLE_IDX(), but with a fallback to default_value.

If the value exists, this expands to DT_PROP_BY_PHANDLE_IDX(node_id, phs, idx, prop). The default_value parameter is not expanded in this case.

Otherwise, this expands to default_value.

**Parameters**

- node_id – node identifier
- phs – lowercase-and-underscores property with type phandle, phandles, or phandle-array
- idx – logical index into phs, which must be zero if phs has type phandle
- prop – lowercase-and-underscores property of the phandle's node
- default_value – a fallback value to expand to

**Returns**

the property's value

DT_PROP_BY_PHANDLE(node_id, ph, prop)

Get a property value from a phandle's node.

This is equivalent to DT_PROP_BY_PHANDLE_IDX(node_id, ph, 0, prop).

**Parameters**

- node_id – node identifier
- ph – lowercase-and-underscores property of node_id with type phandle
- prop – lowercase-and-underscores property of the phandle's node

**Returns**

the property's value

DT_PHA_BY_IDX(node_id, pha, idx, cell)

Get a phandle-array specifier cell value at an index.

It might help to read the argument order as being similar to node->phandle_array[index].cell. That is, the cell value is in the pha property of node_id, inside the specifier at index idx.

Example devicetree fragment:

```plaintext
gpio0: gpio@abcd1234 {
    #gpio-cells = <2>;
};

gpio1: gpio@1234abcd {
    #gpio-cells = <2>;
};

led: led_0 {
    gpios = <&gpio0 17 0x1>, <&gpio1 5 0x3>;
};
```
Bindings fragment for the gpio0 and gpio1 nodes:

```plaintext
gpio-cells:
- pin
- flags
```

Above, gpios has two elements:

- index 0 has specifier `<17 0x1>`, so its pin cell is 17, and its flags cell is 0x1
- index 1 has specifier `<5 0x3>`, so pin is 5 and flags is 0x3

Example usage:

```c
#define LED DT_NODELABEL(led)

DT_PHA_BY_IDX(LED, gpios, 0, pin) // 17
DT_PHA_BY_IDX(LED, gpios, 1, flags) // 0x3
```

**Parameters**
- `node_id` – node identifier
- `pha` – lowercase-and-underscores property with type phandle-array
- `idx` – logical index into pha
- `cell` – lowercase-and-underscores cell name within the specifier at pha index `idx`

**Returns**
- the cell's value

```c
DT_PHA_BY_IDX_OR(node_id, pha, idx, cell, default_value)
```
Like `DT_PHA_BY_IDX()`, but with a fallback to `default_value`.
If the value exists, this expands to `DT_PHA_BY_IDX(node_id, pha,idx, cell)`. The `default_value` parameter is not expanded in this case.
Otherwise, this expands to `default_value`.

**Parameters**
- `node_id` – node identifier
- `pha` – lowercase-and-underscores property with type phandle-array
- `idx` – logical index into pha
- `cell` – lowercase-and-underscores cell name within the specifier at pha index `idx`
- `default_value` – a fallback value to expand to

**Returns**
- the cell's value or `default_value`

```c
DT_PHA(node_id, pha, cell)
```
Equivalent to `DT_PHA_BY_IDX(node_id, pha, 0, cell)`

**Parameters**
- `node_id` – node identifier
• pha – lowercase-and-underscores property with type phandle-array
• cell – lowercase-and-underscores cell name

**Returns**
the cell's value

```
DT_PHA.OR(node_id, pha, cell, default_value)
```

Like `DT_PHA()`, but with a fallback to `default_value`. If the value exists, this expands to `DT_PHA(node_id, pha, cell)`. The `default_value` parameter is not expanded in this case. Otherwise, this expands to `default_value`.

**Parameters**

• `node_id` – node identifier
• `pha` – lowercase-and-underscores property with type phandle-array
• `cell` – lowercase-and-underscores cell name
• `default_value` – a fallback value to expand to

**Returns**
the cell's value or `default_value`

```
DT_PHA_BY_NAME(node_id, pha, name, cell)
```

Get a value within a phandle-array specifier by name. This is like `DT_PHA_BY_IDX()`, except it treats `pha` as a structure where each array element has a name. It might help to read the argument order as being similar to `node->phandle_struct.name.cell`. That is, the cell value is in the `pha` property of `node_id`, treated as a data structure where each array element has a name.

Example devicetree fragment:

```
n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
}
```

Bindings fragment for the “adc1” and “adc2” nodes:

```
io-channel-cells:
    - input
```

Example usage:

```
DT_PHA_BY_NAME(DT_NODELABEL(n), io_channels, sensor, input)  // 10
DT_PHA_BY_NAME(DT_NODELABEL(n), io_channels, bandgap, input)  // 20
```

**Parameters**

• `node_id` – node identifier
• `pha` – lowercase-and-underscores property with type phandle-array
• `name` – lowercase-and-underscores name of a specifier in `pha`
cell – lowercase-and-underscores cell name in the named specifier

Returns
the cell's value

DT_PHA_BY_NAME_OR(node_id, pha, name, cell, default_value)
Like DT_PHA_BY_NAME(), but with a fallback to default_value.
If the value exists, this expands to DT_PHA_BY_NAME(node_id, pha, name, cell). The default_value parameter is not expanded in this case.
Otherwise, this expands to default_value.

Parameters
• node_id – node identifier
• pha – lowercase-and-underscores property with type phandle-array
• name – lowercase-and-underscores name of a specifier in pha
• cell – lowercase-and-underscores cell name in the named specifier
• default_value – a fallback value to expand to

Returns
the cell's value or default_value

DT_PHANDLE_BY_NAME(node_id, pha, name)
Get a phandle's node identifier from a phandle array by name.
It might help to read the argument order as being similar to node->phandle_struct.name. phandle. That is, the phandle array is treated as a structure with named elements. The return value is the node identifier for a phandle inside the structure.

Example devicetree fragment:

```plaintext
adc1: adc@abcd1234 {
   foobar = "ADC_1";
};
adc2: adc@1234abcd {
   foobar = "ADC_2";
};
n: node {
   io-channels = &adc1 10, &adc2 20;
   io-channel-names = "SENSOR", "BANDGAP";
};
```

Above, “io-channels” has two elements:

• the element named “SENSOR” has phandle &adc1
• the element named “BANDGAP” has phandle &adc2

Example usage:

```plaintext
#define NODE DT_NODELABEL(n)
```
DT_PROP(DT_PHANDLE_BY_NAME(NODE, io_channels, sensor), foobar)  // “ADC_1”
DT_PROP(DT_PHANDLE_BY_NAME(NODE, io_channels, bandgap), foobar)  // “ADC_2”

Notice how devicetree properties and names are lowercased, and non-alphanumeric characters are converted to underscores.

**Parameters**
- `node_id` – node identifier
- `pha` – lowercase-and-underscores property with type phandle-array
- `name` – lowercase-and-underscores name of an element in `pha`

**Returns**
a node identifier for the node with that phandle

`DT_PHANDLE_BY_IDX(node_id, prop, idx)`
Get a node identifier for a phandle in a property.
When a node’s value at a logical index contains a phandle, this macro returns a node identifier for the node with that phandle.
Therefore, if `prop` has type phandle, `idx` must be zero. (A phandle type is treated as a phandles with a fixed length of 1).

Example devicetree fragment:

```plaintext
n1: node-1 {
    foo = <&n2 &n3>;
};
n2: node-2 { ... };
n3: node-3 { ... };
```

Above, `foo` has type phandles and has two elements:

- index 0 has phandle `&n2`, which is `node-2`’s phandle
- index 1 has phandle `&n3`, which is `node-3`’s phandle

Example usage:

```plaintext
#define N1 DT_NODELABEL(n1)
DT_PHANDLE_BY_IDX(N1, foo, 0)  // node identifier for node-2
DT_PHANDLE_BY_IDX(N1, foo, 1)  // node identifier for node-3
```

Behavior is analogous for phandle-arrays.

**Parameters**
- `node_id` – node identifier
- `prop` – lowercase-and-underscores property name in `node_id` with type phandle, phandles or phandle-array
- `idx` – index into `prop`

**Returns**
node identifier for the node with the phandle at that index
DT_PHANDLE(node_id, prop)

Get a node identifier for a phandle property's value.

This is equivalent to `DT_PHANDLE_BY_IDX(node_id, prop, 0)`. Its primary benefit is readability when `prop` has type `phandle`.

**Parameters**

- `node_id` – node identifier
- `prop` – lowercase-and-underscores property of `node_id` with type `phandle`

**Returns**

a node identifier for the node pointed to by “ph”

**ranges property**  Use these APIs instead of `Property access` to access the `ranges` property. Because this property’s semantics are defined by the devicetree specification, these macros can be used even for nodes without matching bindings. However, they take on special semantics when the node’s binding indicates it is a PCIe bus node, as defined in the PCI Bus Binding to: IEEE Std 1275-1994 Standard for Boot (Initialization Configuration) Firmware

**Definition**

```
DT_NUM_RANGES(node_id)

Get the number of range blocks in the `ranges` property.

Use this instead of `DT_PROP_LEN(node_id, ranges)`.

Example devicetree fragment:
```

cmie0: pcie@0 {
    compatible = "intel,pcie";
    reg = <0 1>;
    #address-cells = <3>;
    #size-cells = <2>;

    ranges = <0x1000000 0 0 0 0x3eff0000 0 0x1000>,
             <0x2000000 0 0x10000000 0 0x10000000 0 0x2eff0000>,
             <0x3000000 0x80 0 0x80 0 0x80 0>;
};

other: other@1 {
    reg = <1 1>;

    ranges = <0x0 0x0 0x0 0x3eff0000 0x1000>,
             <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
};
```

Example usage:

```
DT_NUM_RANGES(DT_NODELABEL(pcie0)) // 3
DT_NUM_RANGES(DT_NODELABEL(other)) // 2
```

**Parameters**
• node_id – node identifier

DT_RANGES_HAS_IDX(node_id, idx)

Is idx a valid range block index?

If this returns 1, then DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(node_id, idx), DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(node_id, idx) or DT_RANGES_LENGTH_BY_IDX(node_id, idx) are valid. For DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx) the return value of DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(node_id, idx) will indicate validity. If it returns 0, it is an error to use those macros with index idx, including DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx).

Example devicetree fragment:

```plaintext
cicie0: pcie@0 {
  compatible = "intel,pcie";
  reg = <0 1>;
  #address-cells = <3>;
  #size-cells = <2>;

  ranges = <0x1000000 0 0 0 0x3eff0000 0 0x10000>,
           <0x2000000 0x10000000 0 0x10000000 0 0x2eff0000>,
           <0x3000000 0x80 0 0x80 0 0x80 0>;
};
other: other@1 {
  reg = <1 1>;

  ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,
           <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
};
```

Example usage:

```plaintext
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 0) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 1) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 2) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(pcie0), 3) // 0
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 0) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 1) // 1
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 2) // 0
DT_RANGES_HAS_IDX(DT_NODELABEL(other), 3) // 0
```

Parameters

• node_id – node identifier
• idx – index to check

Returns

1 if idx is a valid register block index, 0 otherwise.

DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(node_id, idx)

Does a ranges property have child bus flags at index?
If this returns 1, then `DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx)` is valid. If it returns 0, it is an error to use this macro with index `idx`. This macro only returns 1 for PCIe buses (i.e. nodes whose bindings specify they are “pcie” bus nodes.)

Example devicetree fragment:

```
parent {
    #address-cells = <2>;

    pcie0: pcie00 {
        compatible = "intel,pcie";
        reg = <0 0 1>;
        #address-cells = <3>;
        #size-cells = <2>;

        ranges = <0x1000000 0 0x3eff0000 0x1000000>,
                <0x2000000 0 0x10000000 0x10000000 0x2eff0000>,
                <0x3000000 0x80 0 0x80 0 0x80 0>;
    };

    other: other01 {
        reg = <0 1 1>;

        ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,
                 <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    };
};
```

Example usage:

```
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 0) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 1) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 2) // 1
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(pcie0), 3) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 0) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 1) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 2) // 0
DT_RANGES_HAS_CHILD_BUS_FLAGS_AT_IDX(DT_NODELABEL(other), 3) // 0
```

**Parameters**

- `node_id` – node identifier
- `idx` – logical index into the ranges array

**Returns**

1 if `idx` is a valid child bus flags index, 0 otherwise.

`DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(node_id, idx)`

Get the ranges property child bus flags at index.

When the node is a PCIe bus, the Child Bus Address has an extra cell used to store some flags, thus this cell is extracted from the Child Bus Address as Child Bus Flags field.

Example devicetree fragments:
Example usage:

```
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0x1000000
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x2000000
DT_RANGES_CHILD_BUS_FLAGS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x3000000
```

**Parameters**

- `node_id` – node identifier
- `idx` – logical index into the ranges array

**Returns**

range child bus flags field at `idx`

**Example devicetree fragments:**

```
parent {
    #address-cells = <2>;

    pcie0: pcie@0 {
        compatible = "intel,pcie";
        reg = <0 0 1>;
        #address-cells = <3>;
        #size-cells = <2>;

        ranges = <0x1000000 0 0 0x3eff0000 0 0x10000>,
                 <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                 <0x3000000 0x80 0x80 0x80 0x80 0>
    }
};

other: other@1 {
    reg = <0 1 1>;

    ranges = <0x0 0x0 0x3eff0000 0x10000>,
} (continues on next page)
```
Example usage:

```c
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x10000000
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x8000000000
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 0) // 0
DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 1) // 0x10000000
```

**Parameters**
- `node_id` – node identifier
- `idx` – logical index into the ranges array

**Returns**
- range child bus address field at `idx`

**DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(node_id, idx)**

Get the ranges property parent bus address at index.

Similarly to **DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX()**, this properly accounts for child bus flags cells when the node is a PCIe bus.

Example devicetree fragment:

```devicetree
parent {
    #address-cells = <2>;

    pcie0: pcie@0 {
        compatible = "intel,pcie";
        reg = <0 0 1>;
        #address-cells = <3>;
        #size-cells = <2>;
        ranges = <0x1000000 0 0 0 0x3eff0000 0x10000>,
                  <0x2000000 0x10000000 0x10000000 0x2eff0000>,
                  <0x3000000 0x80 0 0x80 0x80 0x80>;
    }

    other: other@1 {
        reg = <0 1 1>;
        ranges = <0x0 0x0 0x3eff0000 0x10000>,
                  <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
    }
}
```

Example usage:
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 0) // 0x3eff0000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x10000000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x8000000000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 0) // 0x3eff0000
DT_RANGES_PARENT_BUS_ADDRESS_BY_IDX(DT_NODELABEL(other), 1) // 0x10000000

Parameters

- node_id – node identifier
- idx – logical index into the ranges array

Returns

range parent bus address field at idx

DT_RANGES_LENGTH_BY_IDX(node_id, idx)

Get the ranges property length at index.

Similarly to DT_RANGES_CHILD_BUS_ADDRESS_BY_IDX(), this properly accounts for child bus flags cells when the node is a PCIe bus.

Example devicetree fragment:

```
parent {
  #address-cells = <2>;

  pcie0: pcie00 {
    compatible = "intel,pcie";
    reg = <0 0 1>;
    #address-cells = <3>;
    #size-cells = <2>;

    ranges = <0x10000000 0 0 0x3eff0000 0 0x10000000 0 0x3eff0000>,
             <0x20000000 0x10000000 0x10000000 0x2eff0000>,
             <0x30000000 0x80 0x80 0x80 0x80>;
  }

  other: other0 {  
    reg = <0 1 1>;

    ranges = <0x0 0x0 0x3eff0000 0x10000>,
             <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
  }
};
```

Example usage:

```
DT_RANGES_LENGTH_BY_IDX(DT_NODELABEL(pcie0), 0) // 0x10000
DT_RANGES_LENGTH_BY_IDX(DT_NODELABEL(pcie0), 1) // 0x2eff0000
DT_RANGES_LENGTH_BY_IDX(DT_NODELABEL(pcie0), 2) // 0x8000000000
DT_RANGES_LENGTH_BY_IDX(DT_NODELABEL(other), 0) // 0x10000
DT_RANGES_LENGTH_BY_IDX(DT_NODELABEL(other), 1) // 0x2eff0000
```

Parameters

- node_id – node identifier
• idx – logical index into the ranges array

**Returns**

range length field at idx

`DT_FOREACH_RANGE(node_id, fn)`

Invokes fn for each entry of node_id ranges property.

The macro fn must take two parameters, node_id which will be the node identifier of the node with the ranges property and idx the index of the ranges block.

Example devicetree fragment:

```c
n: node@0 {
    reg = <0 0 1>;
    ranges = <0x0 0x0 0x0 0x3eff0000 0x10000>,
           <0x0 0x10000000 0x0 0x10000000 0x2eff0000>;
};
```

Example usage:

```c
#define RANGE_LENGTH(node_id, idx) DT_RANGES_LENGTH_BY_IDX(node_id, idx),
const uint64_t *ranges_length[] = {
    DT_FOREACH_RANGE(DT_NODELABEL(n), RANGE_LENGTH)
};
```

This expands to:

```c
const char *ranges_length[] = {
    0x10000, 0x2eff0000,
};
```

**Parameters**

- node_id – node identifier
- fn – macro to invoke

**reg property** Use these APIs instead of *Property access* to access the reg property. Because this property’s semantics are defined by the devicetree specification, these macros can be used even for nodes without matching bindings.

**group devicetree-reg-prop**

**Defines**

`DT_NUM_REGS(node_id)`

Get the number of register blocks in the reg property.

Use this instead of `DT_PROP_LEN(node_id, reg)`.

**Parameters**
• node_id – node identifier

**Returns**
Number of register blocks in the node’s “reg” property.

**DT_REG_HAS_IDX(node_id, idx)**
Is idx a valid register block index?
If this returns 1, then **DT_REG_ADDR_BY_IDX(node_id, idx)** or **DT_REG_SIZE_BY_IDX(node_id, idx)** are valid. If it returns 0, it is an error to use those macros with index idx.

**Parameters**
• node_id – node identifier
• idx – index to check

**Returns**
1 if idx is a valid register block index, 0 otherwise.

**DT_REG_ADDR_BY_IDX(node_id, idx)**
Get the base address of the register block at index idx.

**Parameters**
• node_id – node identifier
• idx – index of the register whose address to return

**Returns**
address of the idx-th register block

**DT_REG_SIZE_BY_IDX(node_id, idx)**
Get the size of the register block at index idx.
This is the size of an individual register block, not the total number of register blocks in the property; use **DT_NUM_REGS()** for that.

**Parameters**
• node_id – node identifier
• idx – index of the register whose size to return

**Returns**
size of the idx-th register block

**DT_REG_ADDR(node_id)**
Get a node’s (only) register block address.
Equivalent to **DT_REG_ADDR_BY_IDX(node_id, 0)**.

**Parameters**
• node_id – node identifier

**Returns**
node’s register block address

**DT_REG_SIZE(node_id)**
Get a node’s (only) register block size.
Equivalent to **DT_REG_SIZE_BY_IDX(node_id, 0)**.

**Parameters**
• node_id – node identifier

**Returns**
node’s only register block’s size
DT_REG_ADDR_BY_NAME(node_id, name)
Get a register block’s base address by name.

**Parameters**
- `node_id` – node identifier
- `name` – lowercase-and-underscores register specifier name

**Returns**
address of the register block specified by name

DT_REG_SIZE_BY_NAME(node_id, name)
Get a register block’s size by name.

**Parameters**
- `node_id` – node identifier
- `name` – lowercase-and-underscores register specifier name

**Returns**
size of the register block specified by name

**interrupts property**  Use these APIs instead of *Property access* to access the `interrupts` property.
Because this property’s semantics are defined by the devicetree specification, some of these macros can
be used even for nodes without matching bindings. This does not apply to macros which take cell names
as arguments.

**group devicetree-interrupts-prop**

**Defines**

DT_NUM_IRQS(node_id)
Get the number of interrupt sources for the node.
Use this instead of `DT_PROP_LEN(node_id, interrupts)`.

**Parameters**
- `node_id` – node identifier

**Returns**
Number of interrupt specifiers in the node’s “interrupts” property.

DT_IRQ_HAS_IDX(node_id, idx)
Is `idx` a valid interrupt index?
If this returns 1, then `DT_IRQ_BY_IDX(node_id, idx)` is valid. If it returns 0, it is an error to
use that macro with this index.

**Parameters**
- `node_id` – node identifier
- `idx` – index to check

**Returns**
1 if the idx is valid for the interrupt property 0 otherwise.

DT_IRQ_HAS_CELL_AT_IDX(node_id, idx, cell)
Does an interrupts property have a named cell specifier at an index? If this returns 1, then
`DT_IRQ_BY_IDX(node_id, idx, cell)` is valid. If it returns 0, it is an error to use that macro.

**Parameters**
• node_id – node identifier
• idx – index to check
• cell – named cell value whose existence to check

**Returns**
1 if the named cell exists in the interrupt specifier at index idx 0 otherwise.

`DT_IRQ_HAS_CELL(node_id, cell)`

Equivalent to `DT_IRQ_HAS_CELL_AT_IDX(node_id, 0, cell)`

**Parameters**
• node_id – node identifier
• cell – named cell value whose existence to check

**Returns**
1 if the named cell exists in the interrupt specifier at index 0 0 otherwise.

`DT_IRQ_HAS_NAME(node_id, name)`

Does an interrupts property have a named specifier value at an index? If this returns 1, then `DT_IRQ_BY_NAME(node_id, name, cell)` is valid. If it returns 0, it is an error to use that macro.

**Parameters**
• node_id – node identifier
• name – lowercase-and-underscores interrupt specifier name

**Returns**
1 if “name” is a valid named specifier 0 otherwise.

`DT_IRQ_BY_IDX(node_id, idx, cell)`

Get a value within an interrupt specifier at an index.

It might help to read the argument order as being similar to “node->interrupts[index].cell”.

This can be used to get information about an individual interrupt when a device generates more than one.

Example devicetree fragment:

```
my-serial: serial@abcd1234 {
    interrupts = < 33 0 >, < 34 1 >;
};
```

Assuming the node’s interrupt domain has “#interrupt-cells = <2>;” and the individual cells in each interrupt specifier are named “irq” and “priority” by the node’s binding, here are some examples:

```
#define SERIAL DT_NODELABEL(my_serial)
```

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</thead>
<tbody>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 0, irq)</td>
<td>33</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 0, priority)</td>
<td>0</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 1, irq)</td>
<td>34</td>
</tr>
<tr>
<td>DT_IRQ_BY_IDX(SERIAL, 1, priority)</td>
<td>1</td>
</tr>
</tbody>
</table>

**Parameters**
• node_id – node identifier
• idx – logical index into the interrupt specifier array
• cell – cell name specifier

**Returns**
the named value at the specifier given by the index

`DT_IRQ_BY_NAME(node_id, name, cell)`
Get a value within an interrupt specifier by name.
It might help to read the argument order as being similar to `node->interrupts.name.cell`.
This can be used to get information about an individual interrupt when a device generates
more than one, if the bindings give each interrupt specifier a name.

**Parameters**
• node_id – node identifier  
• name – lowercase-and-underscores interrupt specifier name  
• cell – cell name specifier

**Returns**
the named value at the specifier given by the index

`DT_IRQ(node_id, cell)`
Get an interrupt specifier's value Equivalent to `DT_IRQ_BY_IDX(node_id, 0, cell)`.

**Parameters**
• node_id – node identifier  
• cell – cell name specifier

**Returns**
the named value at that index

`DT_IRQN(node_id)`
Get a node's (only) irq number.
Equivalent to `DT_IRQ(node_id, irq)`.
This is provided as a convenience for the common case where a node generates exactly one interrupt, and the IRQ number is in a cell named irq.

**Parameters**
• node_id – node identifier

**Returns**
the interrupt number for the node's only interrupt

**For-each macros**
There is currently only one “generic” for-each macro, `DT_FOREACH_CHILD()`, which allows iterating over the children of a devicetree node.

There are special-purpose for-each macros, like `DT_INST_FOREACH_STATUS_OKAY()`, but these require `DT_DRV_COMPAT` to be defined before use.

`group devicetree-generic-foreach`

**Defines**

`DT_FOREACH_NODE(fn)`
Invokes fn for every node in the tree.
The macro fn must take one parameter, which will be a node identifier. The macro is expanded once for each node in the tree. The order that nodes are visited in is not specified.
Parameters

- fn - macro to invoke

**DT_FOREACH_STATUS_OKAY_NODE(fn)**

Invokes fn for every status okay node in the tree.

The macro fn must take one parameter, which will be a node identifier. The macro is expanded once for each node in the tree with status okay (as usual, a missing status property is treated as status okay). The order that nodes are visited in is not specified.

Parameters

- fn - macro to invoke

**DT_FOREACH_CHILD(node_id, fn)**

Invokes fn for each child of node_id.

The macro fn must take one parameter, which will be the node identifier of a child node of node_id.

The children will be iterated over in the same order as they appear in the final devicetree.

Example devicetree fragment:

```
n: node {
  child-1 {
    foobar = "foo";
  };
  child-2 {
    foobar = "bar";
  };
}
```

Example usage:

```c
#define FOOBAR_AND_COMMA(node_id) DT_PROP(node_id, foobar),
const char *child_foobars[] = {
    DT_FOREACH_CHILD(DT_NODELABEL(n), FOOBAR_AND_COMMA)
};
```

This expands to:

```c
const char *child_foobars[] = {
    "foo", "bar",
};
```

Parameters

- node_id - node identifier
- fn - macro to invoke

**DT_FOREACH_CHILD_SEP(node_id, fn, sep)**

Invokes fn for each child of node_id with a separator.

The macro fn must take one parameter, which will be the node identifier of a child node of node_id.
Example devicetree fragment:

```c
n: node {
    child-1 {
        ...
    };
    child-2 {
        ...
    };
};
```

Example usage:

```c
const char *child_names[] = {
    DT_FOREACH_CHILD_SEP(DT_NODELABEL(n), DT_NODE_FULL_NAME, (,))
};
```

This expands to:

```c
const char *child_names[] = {
    "child-1", "child-2"
};
```

Parameters

- `node_id` – node identifier
- `fn` – macro to invoke
- `sep` – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

```c
DT_FOREACH_CHILD_VARGS(node_id, fn, ...)
```

Invokes `fn` for each child of `node_id` with multiple arguments.

The macro `fn` takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

The children will be iterated over in the same order as they appear in the final devicetree.

See also:

`DT_FOREACH_CHILD`

Parameters

- `node_id` – node identifier
- `fn` – macro to invoke
- `...` – variable number of arguments to pass to `fn`

```c
DT_FOREACH_CHILD_SEP_VARGS(node_id, fn, sep, ...)
```

Invokes `fn` for each child of `node_id` with separator and multiple arguments.

The macro `fn` takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.
See also:

**DT_FOREACH_CHILD_VARGS**

Parameters

- node_id – node identifier
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- ... – variable number of arguments to pass to fn

DT_FOREACH_CHILD_STATUS_OKAY(node_id, fn)

Call fn on the child nodes with status okay

The macro fn should take one argument, which is the node identifier for the child node.

As usual, both a missing status and an ok status are treated as okay.

The children will be iterated over in the same order as they appear in the final devicetree.

Parameters

- node_id – node identifier
- fn – macro to invoke

DT_FOREACH_CHILD_STATUS_OKAY_SEP(node_id, fn, sep)

Call fn on the child nodes with status okay with separator.

The macro fn should take one argument, which is the node identifier for the child node.

As usual, both a missing status and an ok status are treated as okay.

See also:

**DT_FOREACH_CHILD_STATUS_OKAY**

Parameters

- node_id – node identifier
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

DT_FOREACH_CHILD_STATUS_OKAY_VARGS(node_id, fn, ...)

Call fn on the child nodes with status okay with multiple arguments.

The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

As usual, both a missing status and an ok status are treated as okay.

The children will be iterated over in the same order as they appear in the final devicetree.

See also:

**DT_FOREACH_CHILD_STATUS_OKAY**

Parameters
DT_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS(node_id, fn, sep, ...)
Call fn on the child nodes with status okay with separator and multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.
As usual, both a missing status and an ok status are treated as okay.

See also:
DT_FOREACH_CHILD_SEP_STATUS_OKAY

Parameters

- node_id – node identifier
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- ... – variable number of arguments to pass to fn

DT_FOREACH_PROP_ELEM(node_id, prop, fn)
Invokes fn for each element in the value of property prop.
The macro fn must take three parameters: fn(node_id, prop, idx). node_id and prop are the same as what is passed to DT_FOREACH_PROP_ELEM(), and idx is the current index into the array. The idx values are integer literals starting from 0.
Example devicetree fragment:

```plaintext
n: node {
    my-ints = <1 2 3>;
};
```
Example usage:

```plaintext
#define TIMES_TWO(node_id, prop, idz) \
    (2 * DT_PROP_BY_IDX(node_id, prop, idz)),

int array[] = {
    DT_FOREACH_PROP_ELEM(DT_NODELABEL(n), my_ints, TIMES_TWO)
};
```
This expands to:

```plaintext
int array[] = {
    (2 * 1), (2 * 2), (2 * 3),
};
```
In general, this macro expands to:
fn(node_id, prop, 0) fn(node_id, prop, 1) [...] fn(node_id, prop, n-1)

where \( n \) is the number of elements in \( prop \), as it would be returned by \( DT\_PROP\_LEN(node_id, prop) \).

The \( prop \) argument must refer to a property with type string, array, uint8-array, string-array, phandles, or phandle-array. It is an error to use this macro with properties of other types.

**Parameters**

- \( node\_id \) – node identifier
- \( prop \) – lowercase-and-underscores property name
- \( fn \) – macro to invoke

\( DT\_FOREACH\_PROP\_ELEM\_SEP(node\_id, prop, fn, sep) \)

Invokes \( fn \) for each element in the value of property \( prop \) with separator.

Example devicetree fragment:

```markdown
n: node {
    my-gpios = <&gpioa 0 GPIO\_ACTICE\_HIGH>,
              <&gpiob 1 GPIO\_ACTIVE\_HIGH>;
}
```

Example usage:

```c
struct gpio_dt_spec specs[] = {
    DT_FOREACH_PROP_ELEM_SEP(DT\_NODELABEL(n), my\_gpios,
                                GPIO\_DT\_SPEC\_BY\_IDX, (,)),
};
```

This expands as a first step to:

```c
struct gpio_dt_spec specs[] = {
    struct gpio_dt_spec specs[] = {
        GPIO\_DT\_SPEC\_BY\_IDX(DT\_NODELABEL(n), my\_gpios, 0),
        GPIO\_DT\_SPEC\_BY\_IDX(DT\_NODELABEL(n), my\_gpios, 1)
    }
};
```

The “prop” argument must refer to a property with type string, array, uint8-array, string-array, phandles, or phandle-array. It is an error to use this macro with properties of other types.

**See also:**

\( DT\_FOREACH\_PROP\_ELEM \)

**Parameters**

- \( node\_id \) – node identifier
- \( prop \) – lowercase-and-underscores property name
- \( fn \) – macro to invoke
- \( sep \) – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
DT_FOREACH_PROP_ELEM_VARS(node_id, prop, fn, ...)
Invokes fn for each element in the value of property prop with multiple arguments.

The macro fn must take multiple parameters: fn(node_id, prop, idx, ...). node_id and prop are the same as what is passed to DT_FOREACH_PROP_ELEM(), and idx is the current index into the array. The idx values are integer literals starting from 0. The remaining arguments are passed-in by the caller.

See also:
DT_FOREACH_PROP_ELEM

Parameters
• node_id – node identifier
• prop – lowercase-and-underscores property name
• fn – macro to invoke
• ... – variable number of arguments to pass to fn

DT_FOREACH_PROP_ELEM_SEP_VARS(node_id, prop, fn, sep, ...)
Invokes fn for each element in the value of property prop with multiple arguments and a separator.

See also:
DT_FOREACH_PROP_ELEM_VARS

Parameters
• node_id – node identifier
• prop – lowercase-and-underscores property name
• fn – macro to invoke
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• ... – variable number of arguments to pass to fn

DT_FOREACH_STATUS_OKAY(compat, fn)
Invokes fn for each status okay node of a compatible.

This macro expands to:

fn(node_id_1) fn(node_id_2) ... fn(node_id_n)

where each node_id_<i> is a node identifier for some node with compatible compat and status okay. Whitespace is added between expansions as shown above.

Example devicetree fragment:

/ {
  a {
    compatible = "foo";
    status = "okay";
  };
  b {
    (continues on next page)
Example usage:

\[ \text{DT_FOREACH_STATUS_OKAY}(\text{foo}, \text{DT_NODE_PATH}) \]

This expands to one of the following:

\[ /a \quad /c \]
\[ /c \quad /a \]

“One of the following” is because no guarantees are made about the order that node identifiers are passed to \textit{fn} in the expansion.

(The /c string literal is present because a missing status property is always treated as if the status were set to \textit{okay}.)

Note also that \textit{fn} is responsible for adding commas, semicolons, or other terminators as needed.

**Parameters**

- \textit{compat} – lowercase-and-underscores devicetree compatible
- \textit{fn} – Macro to call for each enabled node. Must accept a node\_id as its only parameter.

\[ \text{DT_FOREACH_STATUS_OKAY_VARGS}(\text{compat}, \text{fn}, ...) \]

Invokes \textit{fn} for each status \textit{okay} node of a \textit{compatible} with multiple arguments.

This is like \textit{DT_FOREACH_STATUS_OKAY()} except you can also pass additional arguments to \textit{fn}.

Example devicetree fragment:

\[
/ \{
  a \{
    \text{compatible} = "foo";
    \text{val} = <3>;
  \};
  b \{
    \text{compatible} = "foo";
    \text{val} = <4>;
  \};
\};
\]

Example usage:

\[ \text{\#define MY\_FN}(\text{node\_id, operator}) \text{DT\_PROP}(\text{node\_id, val}) \text{operator} \]
\[ x = \text{DT\_FOREACH\_STATUS\_OKAY\_VARGS}(\text{foo, MY\_FN, +}) \ 0; \]
This expands to one of the following:

\[
x = 3 + 4 + 0;
x = 4 + 3 + 0;
\]

i.e. it sets x to 7. As with `DT_FOREACH_STATUS_OKAY()`, there are no guarantees about the order nodes appear in the expansion.

**Parameters**

- `compat` – lowercase-and-underscores devicetree compatible
- `fn` – Macro to call for each enabled node. Must accept a node_id as its only parameter.
- `...` – Additional arguments to pass to `fn`

**Existence checks**

This section documents miscellaneous macros that can be used to test if a node exists, how many nodes of a certain type exist, whether a node has certain properties, etc. Some macros used for special purposes (such as `DT_IRQ_HAS_IDX()` and all macros which require `DT_DRV_COMPAT`) are documented elsewhere on this page.

`group devicetree-generic-exist`

**Defines**

`DT_NODE_EXISTS(node_id)`

Does a node identifier refer to a node?

Tests whether a node identifier refers to a node which exists, i.e. is defined in the devicetree. It doesn’t matter whether or not the node has a matching binding, or what the node’s status value is. This is purely a check of whether the node exists at all.

**Parameters**

- `node_id` – a node identifier

**Returns**

1 if the node identifier refers to a node, 0 otherwise.

`DT_NODE_HAS_STATUS(node_id, status)`

Does a node identifier refer to a node with a status?

Example uses:

\[
\begin{align*}
&DT\_NODE\_HAS\_STATUS(DT\_PATH(soc, i2c_12340000), \text{okay}) \\
&DT\_NODE\_HAS\_STATUS(DT\_PATH(soc, i2c_12340000), \text{disabled})
\end{align*}
\]

Tests whether a node identifier refers to a node which:

- exists in the devicetree, and
- has a status property matching the second argument (except that either a missing status or an ok status in the devicetree is treated as if it were okay instead)

**Parameters**
• node_id – a node identifier
• status – a status as one of the tokens okay or disabled, not a string

Returns
1 if the node has the given status, 0 otherwise.

\texttt{DT\_HAS\_COMPAT\_STATUS\_OKAY(compat)}

Does the devicetree have a status okay node with a compatible?

Test for whether the devicetree has any nodes with status okay and the given compatible. That is, this returns 1 if and only if there is at least one \texttt{node_id} for which both of these expressions return 1:

\texttt{DT\_NODE\_HAS\_STATUS(node_id, okay)}
\texttt{DT\_NODE\_HAS\_COMPAT(node_id, compat)}

As usual, both a missing status and an \texttt{ok} status are treated as \texttt{okay}.

Parameters
• compat – lowercase-and-underscores compatible, without quotes

Returns
1 if both of the above conditions are met, 0 otherwise

\texttt{DT\_NUM\_INST\_STATUS\_OKAY(compat)}

Get the number of instances of a given compatible with status okay

Parameters
• compat – lowercase-and-underscores compatible, without quotes

Returns
Number of instances with status okay

\texttt{DT\_NODE\_HAS\_COMPAT(node_id, compat)}

Does a devicetree node match a compatible?

Example devicetree fragment:

```
\texttt{n: node {}
    \texttt{compatible = "vnd,specific-device", "generic-device";}
\texttt{}}
```

Example usages which evaluate to 1:

```
\texttt{DT\_NODE\_HAS\_COMPAT(DT\_NODELABEL(n), vnd_specific_device)}
\texttt{DT\_NODE\_HAS\_COMPAT(DT\_NODELABEL(n), generic_device)}
```

This macro only uses the value of the compatible property. Whether or not a particular compatible has a matching binding has no effect on its value, nor does the node's status.

Parameters
• node_id – node identifier
• compat – lowercase-and-underscores compatible, without quotes

Returns
1 if the node's compatible property contains \texttt{compat}, 0 otherwise.
DT_NODE_HAS_COMPAT_STATUS(node_id, compat, status)
   Does a devicetree node have a compatible and status?
   This is equivalent to:
   
   (DT_NODE_HAS_COMPAT(node_id, compat) &&
    DT_NODE_HAS_STATUS(node_id, status))

Parameters
   • node_id – node identifier
   • compat – lowercase-and-underscores compatible, without quotes
   • status – okay or disabled as a token, not a string

DT_NODE_HAS_PROP(node_id, prop)
   Does a devicetree node have a property?
   Tests whether a devicetree node has a property defined.
   This tests whether the property is defined at all, not whether a boolean property is true or false. To get a boolean property's truth value, use DT_PROP(node_id, prop) instead.

Parameters
   • node_id – node identifier
   • prop – lowercase-and-underscores property name

Returns
   1 if the node has the property, 0 otherwise.

DT_PHA_HAS_CELL_AT_IDX(node_id, pha, idx, cell)
   Does a phandle array have a named cell specifier at an index?
   If this returns 1, then the phandle-array property pha has a cell named cell at index idx, and therefore DT_PHA_BY_IDX(node_id,pha, idx, cell) is valid. If it returns 0, it's an error to use DT_PHA_BY_IDX() with the same arguments.

Parameters
   • node_id – node identifier
   • pha – lowercase-and-underscores property with type phandle-array
   • idx – index to check within pha
   • cell – lowercase-and-underscores cell name whose existence to check at index idx

Returns
   1 if the named cell exists in the specifier at index idx, 0 otherwise.

DT_PHA_HAS_CELL(node_id, pha, cell)
   Equivalent to DT_PHA_HAS_CELL_AT_IDX(node_id, pha, 0, cell)

Parameters
   • node_id – node identifier
   • pha – lowercase-and-underscores property with type phandle-array
   • cell – lowercase-and-underscores cell name whose existence to check at index idx

Returns
   1 if the named cell exists in the specifier at index 0, 0 otherwise.
Inter-node dependencies  The devicetree.h API has some support for tracking dependencies between nodes. Dependency tracking relies on a binary “depends on” relation between devicetree nodes, which is defined as the transitive closure of the following “directly depends on” relation:

- every non-root node directly depends on its parent node
- a node directly depends on any nodes its properties refer to by phandle
- a node directly depends on its interrupt-parent if it has an interrupts property

A dependency ordering of a devicetree is a list of its nodes, where each node n appears earlier in the list than any nodes that depend on n. A node's dependency ordinal is then its zero-based index in that list. Thus, for two distinct devicetree nodes n1 and n2 with dependency ordinals d1 and d2, we have:

- d1 != d2
- if n1 depends on n2, then d1 > d2
- d1 > d2 does not necessarily imply that n1 depends on n2

The Zephyr build system chooses a dependency ordering of the final devicetree and assigns a dependency ordinal to each node. Dependency related information can be accessed using the following macros. The exact dependency ordering chosen is an implementation detail, but cyclic dependencies are detected and cause errors, so it's safe to assume there are none when using these macros.

There are instance number-based conveniences as well; see DT_INST_DEP_ORD() and subsequent documentation.

### group devicetree-dep-ord

#### Defines

- **DT_DEP_ORD(node_id)**
  Get a node's dependency ordinal.
  
  **Parameters**
  - node_id – Node identifier
  
  **Returns**
  the node's dependency ordinal as an integer literal

- **DT_REQUIRES_DEP_ORDS(node_id)**
  Get a list of dependency ordinals of a node's direct dependencies.
  
  There is a comma after each ordinal in the expansion, including the last one:

  ```
  DT_REQUIRES_DEP_ORDS(my_node) // required_ord_1, ..., required_ord_n,
  ```

  The one case **DT_REQUIRES_DEP_ORDS()** expands to nothing is when given the root node identifier DT_ROOT as argument. The root has no direct dependencies; every other node at least depends on its parent.

  **Parameters**
  - node_id – Node identifier
  
  **Returns**
  a list of dependency ordinals, with each ordinal followed by a comma (,), or an empty expansion

- **DT_SUPPORTS_DEP_ORDS(node_id)**
  Get a list of dependency ordinals of what depends directly on a node.
  
  There is a comma after each ordinal in the expansion, including the last one:
DT_SUPPORTS_DEP_ORDS() may expand to nothing. This happens when node_id refers to a leaf node that nothing else depends on.

**Parameters**
- node_id – Node identifier

**Returns**
- a list of dependency ordinals, with each ordinal followed by a comma (,), or an empty expansion

**DT_INST_DEP_ORD(inst)**
Get a DT_DRV_COMPAT instance’s dependency ordinal.
Equivalent to DT_DEP_ORD(DT_DRV_INST(inst)).

**Parameters**
- inst – instance number

**Returns**
- The instance’s dependency ordinal

**DT_INSTQUIRES_DEP_ORDS(inst)**
Get a list of dependency ordinals of a DT_DRV_COMPAT instance’s direct dependencies.
Equivalent to DT_REQUIRES_DEP_ORDS(DT_DRV_INST(inst)).

**Parameters**
- inst – instance number

**Returns**
- a list of dependency ordinals for the nodes the instance depends on directly

**DT_INST_SUPPORTS_DEP_ORDS(inst)**
Get a list of dependency ordinals of what depends directly on a DT_DRV_COMPAT instance.
Equivalent to DT_SUPPORTS_DEP_ORDS(DT_DRV_INST(inst)).

**Parameters**
- inst – instance number

**Returns**
- a list of node identifiers for the nodes that depend directly on the instance

**Bus helpers** Zephyr’s devicetree bindings language supports a bus: key which allows bindings to declare that nodes with a given compatible describe system buses. In this case, child nodes are considered to be on a bus of the given type, and the following APIs may be used.

**group devicetree-generic-bus**

**Defines**

**DT_BUS(node_id)**
Node’s bus controller.
Get the node identifier of the node’s bus controller. This can be used with DT_PROP() to get properties of the bus controller.
It is an error to use this with nodes which do not have bus controllers.
Example devicetree fragment:

```
i2c@deadbeef {
    status = "okay";
    clock-frequency = <100000>;

    i2c_device: accelerometer@12 {
        ...
    };
};
```

Example usage:

```
DT_PROP(DT_BUS(DT_NODELABEL(i2c_device)), clock_frequency) // 100000
```

**Parameters**

- `node_id` – node identifier

**Returns**

a node identifier for the node's bus controller

```
DT_BUS_LABEL(node_id)
```

Node's bus controller's `label` property.

**Deprecated:**

If used to obtain a device instance with `device_get_binding`, consider using `DEVICE_DT_GET(DT_BUS(node))`.

**Parameters**

- `node_id` – node identifier

**Returns**

the label property of the node's bus controller `DT_BUS(node)`

```
DT_ON_BUS(node_id, bus)
```

Is a node on a bus of a given type?

Example devicetree overlay:

```
&i2c0 {
    temp: temperature-sensor@76 {
        compatible = "vnd,some-sensor";
        reg = <0x76>;
    };
};
```

Example usage, assuming `i2c0` is an I2C bus controller node, and therefore `temp` is on an I2C bus:

```
DT_ON_BUS(DT_NODELABEL(temp), i2c) // 1
DT_ON_BUS(DT_NODELABEL(temp), spi) // 0
```
Parameters
- node_id – node identifier
- bus – lowercase-and-underscores bus type as a C token (i.e. without quotes)

Returns
1 if the node is on a bus of the given type, 0 otherwise

Instance-based APIs
These are recommended for use within device drivers. To use them, define DT_DRV_COMPAT to the lowercase-and-underscores compatible the device driver implements support for. Here is an example devicetree fragment:

```c
serial@40001000 {
    compatible = "vnd,serial";
    status = "okay";
    current-speed = <115200>;
};
```

Example usage, assuming serial@40001000 is the only enabled node with compatible vnd,serial:

```c
#define DT_DRV_COMPAT vnd_serial
DT_DRV_INST(0)  // node identifier for serial@40001000
DT_INST_PROP(0, current_speed) // 115200
```

Warning: Be careful making assumptions about instance numbers. See `DT_INST()` for the API guarantees.

As shown above, the DT_INST_* APIs are conveniences for addressing nodes by instance number. They are almost all defined in terms of one of the Generic APIs. The equivalent generic API can be found by removing INST_ from the macro name. For example, DT_INST_PROP(inst, prop) is equivalent to DT_PROP(DT_DRV_INST(inst), prop). Similarly, DT_INST_REG_ADDR(inst) is equivalent to DT_REG_ADDR(DT_DRV_INST(inst)), and so on. There are some exceptions: DT_ANY_INST_ON_BUS_STATUS_OKAY() and DT_INST_FOREACH_STATUS_OKAY() are special-purpose helpers without straightforward generic equivalents.

Since DT_DRV_INST() requires DT_DRV_COMPAT to be defined, it’s an error to use any of these without that macro defined.

Note that there are also helpers available for specific hardware; these are documented in Hardware specific APIs.

```c
group devicetree-inst

Defines

DT_DRV_INST(inst)
Node identifier for an instance of a DT_DRV_COMPAT compatible.

Parameters
- inst – instance number

Returns
a node identifier for the node with DT_DRV_COMPAT compatible and instance number inst
```
DT_INST_PARENT(inst)
Get a DT_DRV_COMPAT parent's node identifier.

See also:
DT_PARENT

Parameters
• inst – instance number

Returns
a node identifier for the instance's parent

DT_INST_GPARENT(inst)
Get a DT_DRV_COMPAT grandparent's node identifier.

See also:
DT_GPARENT

Parameters
• inst – instance number

Returns
a node identifier for the instance's grandparent

DT_INST_CHILD(inst, child)
Get a node identifier for a child node of DT_DRV_INST(inst)

See also:
DT_CHILD

Parameters
• inst – instance number
• child – lowercase-and-underscores child node name

Returns
node identifier for the node with the name referred to by ‘child’

DT_INST_FOREACH_CHILD(inst, fn)
Call fn on all child nodes of DT_DRV_INST(inst).
The macro fn should take one argument, which is the node identifier for the child node.
The children will be iterated over in the same order as they appear in the final devicetree.

See also:
DT_FOREACH_CHILD

Parameters
• inst – instance number
• fn – macro to invoke on each child node identifier
DT_INST_FOREACH_CHILD_SEP (inst, fn, sep)

Call fn on all child nodes of DT_DRV_INST(inst) with a separator.

The macro fn should take one argument, which is the node identifier for the child node.

See also:

DT_FOREACH_CHILD_SEP

Parameters

• inst – instance number
• fn – macro to invoke on each child node identifier
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

DT_INST_FOREACH_CHILD_VARGS (inst, fn, ...)

Call fn on all child nodes of DT_DRV_INST(inst).

The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

The children will be iterated over in the same order as they appear in the final devicetree.

See also:

DT_FOREACH_CHILD

Parameters

• inst – instance number
• fn – macro to invoke on each child node identifier
• ... – variable number of arguments to pass to fn

DT_INST_FOREACH_CHILD_SEP_VARGS (inst, fn, sep, ...)

Call fn on all child nodes of DT_DRV_INST(inst) with separator.

The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

See also:

DT_FOREACH_CHILD_SEP_VARGS

Parameters

• inst – instance number
• fn – macro to invoke on each child node identifier
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
• ... – variable number of arguments to pass to fn

5.2. Devicetree
DT_INST_FOREACH_CHILD_STATUS_OKAY(inst, fn)
Call fn on all child nodes of DT_DRV_INST(inst) with status okay.
The macro fn should take one argument, which is the node identifier for the child node.

See also:
DT_FOREACH_CHILD_STATUS_OKAY

Parameters
• inst – instance number
• fn – macro to invoke on each child node identifier

DT_INST_FOREACH_CHILD_STATUS_OKAY_SEP(inst, fn, sep)
Call fn on all child nodes of DT_DRV_INST(inst) with status okay and with separator.
The macro fn should take one argument, which is the node identifier for the child node.

See also:
DT_FOREACH_CHILD_STATUS_OKAY_SEP

Parameters
• inst – instance number
• fn – macro to invoke on each child node identifier
• sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.

DT_INST_FOREACH_CHILD_STATUS_OKAY_VARGS(inst, fn, ...)
Call fn on all child nodes of DT_DRV_INST(inst) with status okay and multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

See also:
DT_FOREACH_CHILD_STATUS_OKAY_VARGS

Parameters
• inst – instance number
• fn – macro to invoke on each child node identifier
• ... – variable number of arguments to pass to fn

DT_INST_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS(inst, fn, sep, ...)
Call fn on all child nodes of DT_DRV_INST(inst) with status okay and with separator and multiple arguments.
The macro fn takes multiple arguments. The first should be the node identifier for the child node. The remaining are passed-in by the caller.

See also:
DT_FOREACH_CHILD_STATUS_OKAY_SEP_VARGS
Parameters

- **inst** – instance number
- **fn** – macro to invoke on each child node identifier
- **sep** – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- **...** – variable number of arguments to pass to **fn**

**DT_INST_ENUM_IDX**(inst, prop)

Get a `DT_DRV_COMPAT` value's index into its enumeration values.

**Parameters**

- **inst** – instance number
- **prop** – lowercase-and-underscores property name

**Returns**

zero-based index of the property's value in its enum: list

**DT_INST_ENUM_IDX_OR**(inst, prop, default_idx_value)

Like `DT_INST_ENUM_IDX()`, but with a fallback to a default enum index.

**Parameters**

- **inst** – instance number
- **prop** – lowercase-and-underscores property name
- **default_idx_value** – a fallback index value to expand to

**Returns**

zero-based index of the property's value in its enum if present, default_idx_value otherwise

**DT_INST_PROP**(inst, prop)

Get a `DT_DRV_COMPAT` instance property.

**Parameters**

- **inst** – instance number
- **prop** – lowercase-and-underscores property name

**Returns**

a representation of the property's value

**DT_INST_PROP_LEN**(inst, prop)

Get a `DT_DRV_COMPAT` property length.

**Parameters**

- **inst** – instance number
- **prop** – lowercase-and-underscores property name

**Returns**

logical length of the property

**DT_INST_PROP_HAS_IDX**(inst, prop, idx)

Is index idx valid for an array type property on a `DT_DRV_COMPAT` instance?

**Parameters**

- **inst** – instance number
- **prop** – lowercase-and-underscores property name
• idx – index to check

**Returns**
1 if idx is a valid index into the given property, 0 otherwise.

`DT_INST_PROP_HAS_NAME(inst, prop, name)`
Is name name available in a foo-names property?

**Parameters**
• inst – instance number
• prop – a lowercase-and-underscores prop-names type property
• name – a lowercase-and-underscores name to check

**Returns**
An expression which evaluates to 1 if name is an available name into the given property, and 0 otherwise.

`DT_INST_PROP_BY_IDX(inst, prop, idx)`
Get a DT_DRV_COMPAT element value in an array property.

**Parameters**
• inst – instance number
• prop – lowercase-and-underscores property name
• idx – the index to get

**Returns**
a representation of the idx-th element of the property

`DT_INST_PROP_OR(inst, prop, default_value)`
Like `DT_INST_PROP()`, but with a fallback to default_value.

**Parameters**
• inst – instance number
• prop – lowercase-and-underscores property name
• default_value – a fallback value to expand to

**Returns**
`DT_INST_PROP(inst, prop)` or default_value

`DT_INST_LABEL(inst)`
Get a DT_DRV_COMPAT instance’s label property.

*Deprecated:*
Use `DT_INST_PROP(inst, label)`

**Parameters**
• inst – instance number

**Returns**
instance’s label property value

`DT_INST_STRING_TOKEN(inst, prop)`
Get a DT_DRV_COMPAT instance’s string property’s value as a token.

**Parameters**
• inst – instance number
• prop – lowercase-and-underscores property string name

**Returns**
the value of prop as a token, i.e. without any quotes and with special characters converted to underscores

`DT_INST_STRING_UPPER_TOKEN(inst, prop)`
Like `DT_INST_STRING_TOKEN()`, but uppercased.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property string name

**Returns**
the value of prop as an uppercased token, i.e. without any quotes and with special characters converted to underscores

`DT_INST_STRING_TOKEN_BY_IDX(inst, prop, idx)`
Get an element out of string-array property as a token.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property string name
- idx – the index to get

**Returns**
the element in prop at index idx as a token

`DT_INST_STRING_UPPER_TOKEN_BY_IDX(inst, prop, idx)`
Like `DT_INST_STRING_TOKEN_BY_IDX()`, but uppercased.

**Parameters**
- inst – instance number
- prop – lowercase-and-underscores property string name
- idx – the index to get

**Returns**
the element in prop at index idx as an uppercased token

`DT_INST_PROP_BY_PHANDLE(inst, ph, prop)`
Get a DT_DRV_COMPAT instance's property value from a phandle's node.

**Parameters**
- inst – instance number
- ph – lowercase-and-underscores property of inst with type phandle
- prop – lowercase-and-underscores property of the phandle's node

**Returns**
the value of prop as described in the DT_PROP() documentation

`DT_INST_PROP_BY_PHANDLE_IDX(inst, phs, idx, prop)`
Get a DT_DRV_COMPAT instance's property value from a phandle in a property.

**Parameters**
- inst – instance number
- phs – lowercase-and-underscores property with type phandle, phandles, or phandle-array

5.2. Devicetree
- idx – logical index into “phs”, which must be zero if “phs” has type phandle
- prop – lowercase-and-underscores property of the phandle’s node

**Returns**
the value of prop as described in the `DT_PROP()` documentation.

`DT_INST_PHA_BY_IDX(inst, pha, idx, cell)`
Get a `DT_DRV_COMPAT` instance’s phandle-array specifier value at an index.

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- idx – logical index into the property pha
- cell – binding’s cell name within the specifier at index idx

**Returns**
the value of the cell inside the specifier at index idx

`DT_INST_PHA_BY_IDX_OR(inst, pha, idx, cell, default_value)`
Like `DT_INST_PHA_BY_IDX()`, but with a fallback to default_value.

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- idx – logical index into the property pha
- cell – binding’s cell name within the specifier at index idx
- default_value – a fallback value to expand to

**Returns**
`DT_INST_PHA(inst, pha, cell)`
Get a `DT_DRV_COMPAT` instance’s phandle-array specifier value
Equivalent to `DT_INST_PHA_BY_IDX(inst, pha, 0, cell)`

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- cell – binding’s cell name for the specifier at pha index 0

**Returns**
the cell value

`DT_INST_PHA_OR(inst, pha, cell, default_value)`
Like `DT_INST_PHA()`, but with a fallback to default_value.

**Parameters**
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- cell – binding’s cell name for the specifier at pha index 0
- default_value – a fallback value to expand to

**Returns**
`DT_INST_PHA(inst, pha, cell)` or `default_value`
DT_INST_PHA_BY_NAME(inst, pha, name, cell)
Get a DT_DRV_COMPAT instance's value within a phandle-array specifier by name.

Parameters
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of a specifier in pha
- cell – binding's cell name for the named specifier

Returns
the cell value

DT_INST_PHA_BY_NAME_OR(inst, pha, name, cell, default_value)
Like DT_INST_PHA_BY_NAME(), but with a fallback to default_value.

Parameters
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of a specifier in pha
- cell – binding's cell name for the named specifier
- default_value – a fallback value to expand to

Returns
DT_INST_PHA_BY_NAME(inst, pha, name, cell) or default_value

DT_INST_PHANDLE_BY_NAME(inst, pha, name)
Get a DT_DRV_COMPAT instance's phandle node identifier from a phandle array by name.

Parameters
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- name – lowercase-and-underscores name of an element in pha

Returns
node identifier for the phandle at the element named “name”

DT_INST_PHANDLE_BY_IDX(inst, prop, idx)
Get a DT_DRV_COMPAT instance's node identifier for a phandle in a property.

Parameters
- inst – instance number
- prop – lowercase-and-underscores property name in inst with type phandle, phandles or phandle-array
- idx – index into prop

Returns
a node identifier for the phandle at index idx in prop

DT_INST_PHANDLE(inst, prop)
Get a DT_DRV_COMPAT instance's node identifier for a phandle property's value.

Parameters
- inst – instance number
- prop – lowercase-and-underscores property of inst with type phandle
Returns a node identifier for the node pointed to by “ph”

\texttt{DT\_INST\_REG\_HAS\_IDX}(\texttt{inst, idx})

is \texttt{idx} a valid register block index on a \texttt{DT\_DRV\_COMPAT} instance?

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{idx} – index to check
\end{itemize}

\textbf{Returns}

1 if \texttt{idx} is a valid register block index, 0 otherwise.

\texttt{DT\_INST\_REG\_ADDR\_BY\_IDX}(\texttt{inst, idx})

Get a \texttt{DT\_DRV\_COMPAT} instance's \texttt{idx}-th register block's address.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{idx} – index of the register whose address to return
\end{itemize}

\textbf{Returns}

address of the instance's \texttt{idx}-th register block

\texttt{DT\_INST\_REG\_SIZE\_BY\_IDX}(\texttt{inst, idx})

Get a \texttt{DT\_DRV\_COMPAT} instance's \texttt{idx}-th register block's size.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{idx} – index of the register whose size to return
\end{itemize}

\textbf{Returns}

size of the instance's \texttt{idx}-th register block

\texttt{DT\_INST\_REG\_ADDR\_BY\_NAME}(\texttt{inst, name})

Get a \texttt{DT\_DRV\_COMPAT}'s register block address by name.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{name} – lowercase-and-underscores register specifier name
\end{itemize}

\textbf{Returns}

address of the register block with the given \texttt{name}

\texttt{DT\_INST\_REG\_SIZE\_BY\_NAME}(\texttt{inst, name})

Get a \texttt{DT\_DRV\_COMPAT}'s register block size by name.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{name} – lowercase-and-underscores register specifier name
\end{itemize}

\textbf{Returns}

size of the register block with the given \texttt{name}

\texttt{DT\_INST\_REG\_ADDR}(\texttt{inst})

Get a \texttt{DT\_DRV\_COMPAT}'s (only) register block address.

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – instance number
\end{itemize}
Returns
    instance's register block address

DT_INST_REG_SIZE(inst)
    Get a DT_DRV_COMPAT's (only) register block size.

Parameters
    • inst – instance number

Returns
    instance's register block size

DT_INST_IRQ_BY_IDX(inst, idx, cell)
    Get a DT_DRV_COMPAT interrupt specifier value at an index.

Parameters
    • inst – instance number
    • idx – logical index into the interrupt specifier array
    • cell – cell name specifier

Returns
    the named value at the specifier given by the index

DT_INST_IRQ_BY_NAME(inst, name, cell)
    Get a DT_DRV_COMPAT interrupt specifier value by name.

Parameters
    • inst – instance number
    • name – lowercase-and-underscores interrupt specifier name
    • cell – cell name specifier

Returns
    the named value at the specifier given by the index

DT_INST_IRQ(inst, cell)
    Get a DT_DRV_COMPAT interrupt specifier's value.

Parameters
    • inst – instance number
    • cell – cell name specifier

Returns
    the named value at that index

DT_INST_IRQN(inst)
    Get a DT_DRV_COMPAT's (only) irq number.

Parameters
    • inst – instance number

Returns
    the interrupt number for the node's only interrupt

DT_INST_BUS(inst)
    Get a DT_DRV_COMPAT's bus node identifier.

Parameters
    • inst – instance number
Returns
node identifier for the instance's bus node

DT_INST_BUS_LABEL(inst)
Get a DT_DRV_COMPAT's bus node's label property.

Deprecated:
If used to obtain a device instance with device_get_binding, consider using DEVICE_DT_GET(DT_INST_BUS(inst)).

Parameters
• inst – instance number

Returns
the label property of the instance’s bus controller

DT_INST_ON_BUS(inst, bus)
Test if a DT_DRV_COMPAT's bus type is a given type.

Parameters
• inst – instance number
• bus – a binding’s bus type as a C token, lowercased and without quotes

Returns
1 if the given instance is on a bus of the given type, 0 otherwise

DT_INST_STRING_TOKEN_OR(inst, name, default_value)
Like DT_INST_STRING_TOKEN(), but with a fallback to default_value.

Parameters
• inst – instance number
• name – lowercase-and-underscores property name
• default_value – a fallback value to expand to

Returns
if prop exists, its value as a token, i.e. without any quotes and with special characters converted to underscores. Otherwise default_value

DT_INST_STRING_UPPER_TOKEN_OR(inst, name, default_value)
Like DT_INST_STRING_UPPER_TOKEN(), but with a fallback to default_value.

Parameters
• inst – instance number
• name – lowercase-and-underscores property name
• default_value – a fallback value to expand to

Returns
the property's value as an uppercased token, or default_value

DT_ANY_INST_ON_BUS_STATUS_OKAY(bus)
Test if any DT_DRV_COMPAT node is on a bus of a given type and has status okay.

This is a special-purpose macro which can be useful when writing drivers for devices which can appear on multiple buses. One example is a sensor device which may be wired on an I2C or SPI bus.

Example devicetree overlay:
Example usage, assuming i2c0 is an I2C bus controller node, and therefore temp is on an I2C bus:

```c
#define DT_DRV_COMPAT vnd_some_sensor
DT_ANY_INST_ON_BUS_STATUS_OKAY(i2c) // 1
```

**Parameters**

- bus – a binding’s bus type as a C token, lowercased and without quotes

**Returns**

1 if any enabled node with that compatible is on that bus type, 0 otherwise

```c
DT_INST_FOREACH_STATUS_OKAY(fn)
```

Call fn on all nodes with compatible DT_DRV_COMPAT and status okay

This macro calls fn(inst) on each inst number that refers to a node with status okay. Whitespace is added between invocations.

Example devicetree fragment:

```c
a {
    compatible = "vnd.device";
    status = "okay";
    foobar = "DEV_A";
}

b {
    compatible = "vnd.device";
    status = "okay";
    foobar = "DEV_B";
}

c {
    compatible = "vnd.device";
    status = "disabled";
    foobar = "DEV_C";
}
```

Example usage:

```c
#define DT_DRV_COMPAT vnd_device
#define MY_FN(inst) DT_INST_PROP(inst, foobar),
DT_INST_FOREACH_STATUS_OKAY(MY_FN)
```
This expands to:

```
MY_FN(0) MY_FN(1)
```

and from there, to either this:

```
"DEV_A", "DEV_B",
```

or this:

```
"DEV_B", "DEV_A",
```

No guarantees are made about the order that a and b appear in the expansion.

Note that fn is responsible for adding commas, semicolons, or other separators or terminators.

Device drivers should use this macro whenever possible to instantiate a struct device for each enabled node in the devicetree of the driver’s compatible DT_DRV_COMPAT.

**Parameters**

- fn – Macro to call for each enabled node. Must accept an instance number as its only parameter.

```
DT_INST_FOREACH_STATUS_OKAY_VARGS(fn, ...)
```

Call fn on all nodes with compatible DT_DRV_COMPAT and status okay with multiple arguments.

**See also:**

`DT_INST_FOREACH_STATUS_OKAY`

**Parameters**

- fn – Macro to call for each enabled node. Must accept an instance number as its only parameter.
- ... – variable number of arguments to pass to fn

```
DT_INST_FOREACH_PROP_ELEM(inst, prop, fn)
```

Invokes fn for each element of property prop for a DT_DRV_COMPAT instance.

Equivalent to `DT_FOREACH_PROP_ELEM(DT_DRV_INST(inst), prop, fn)`.

**Parameters**

- inst – instance number
- prop – lowercase-and-underscores property name
- fn – macro to invoke

```
DT_INST_FOREACH_PROP_ELEM_SEP(inst, prop, fn, sep)
```

Invokes fn for each element of property prop for a DT_DRV_COMPAT instance with a separator.

Equivalent to `DT_FOREACH_PROP_ELEM_SEP(DT_DRV_INST(inst), prop, fn, sep)`.

**Parameters**

- inst – instance number
- prop – lowercase-and-underscores property name
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
DT_INST_FOREACH_PROP_ELEM_VARGS(inst, prop, fn, ...)  
Invokes fn for each element of property prop for a DT_DRV_COMPAT instance with multiple arguments.  
Equivalent to DT_FOREACH_PROP_ELEM_VARGS(DT_DRV_INST(inst), prop, fn, VA_ARGS)

See also:  
DT_INST_FOREACH_PROP_ELEM

Parameters
- inst – instance number
- prop – lowercase-and-underscores property name
- fn – macro to invoke
- ... – variable number of arguments to pass to fn

DT_INST_FOREACH_PROP_ELEM_SEP_VARGS(inst, prop, fn, sep, ...)  
Invokes fn for each element of property prop for a DT_DRV_COMPAT instance with multiple arguments and a separator.  
Equivalent to DT_FOREACH_PROP_ELEM_SEP_VARGS(DT_DRV_INST(inst), prop, fn, sep, VA_ARGS)

See also:  
DT_INST_FOREACH_PROP_ELEM

Parameters
- inst – instance number
- prop – lowercase-and-underscores property name
- fn – macro to invoke
- sep – Separator (e.g. comma or semicolon). Must be in parentheses; this is required to enable providing a comma as separator.
- ... – variable number of arguments to pass to fn

DT_INST_NODE_HAS_PROP(inst, prop)  
Does a DT_DRV_COMPAT instance have a property?  

Parameters
- inst – instance number
- prop – lowercase-and-underscores property name

Returns
1 if the instance has the property, 0 otherwise.

DT_INST_PHA_HAS_CELL_AT_IDX(inst, pha, idx, cell)  
Does a phandle array have a named cell specifier at an index for a DT_DRV_COMPAT instance?  

Parameters
- inst – instance number
- pha – lowercase-and-underscores property with type phandle-array
- idx – index to check
• cell – named cell value whose existence to check

Returns
1 if the named cell exists in the specifier at index idx, 0 otherwise.

DT_INST_PHA_HAS_CELL(inst, pha, cell)
Does a phandle array have a named cell specifier at index 0 for a DT_DRV_COMPAT instance?

Parameters
• inst – instance number
• pha – lowercase-and-underscores property with type phandle-array
• cell – named cell value whose existence to check

Returns
1 if the named cell exists in the specifier at index 0, 0 otherwise.

DT_INST_IRQ_HAS_IDX(inst, idx)
is index valid for interrupt property on a DT_DRV_COMPAT instance?

Parameters
• inst – instance number
• idx – logical index into the interrupt specifier array

Returns
1 if the idx is valid for the interrupt property 0 otherwise.

DT_INST_IRQ_HAS_CELL_AT_IDX(inst, idx, cell)
Does a DT_DRV_COMPAT instance have an interrupt named cell specifier?

Parameters
• inst – instance number
• idx – index to check
• cell – named cell value whose existence to check

Returns
1 if the named cell exists in the interrupt specifier at index idx 0 otherwise.

DT_INST_IRQ_HAS_CELL(inst, cell)
Does a DT_DRV_COMPAT instance have an interrupt value?

Parameters
• inst – instance number
• cell – named cell value whose existence to check

Returns
1 if the named cell exists in the interrupt specifier at index 0 0 otherwise.

DT_INST_IRQ_HAS_NAME(inst, name)
Does a DT_DRV_COMPAT instance have an interrupt value?

Parameters
• inst – instance number
• name – lowercase-and-underscores interrupt specifier name

Returns
1 if name is a valid named specifier
Hardware specific APIs  The following APIs can also be used by including `<devicetree.h>`; no additional include is needed.

CAN  These conveniences may be used for nodes which describe CAN controllers/transceivers, and properties related to them.

group devicetree-can

Defines

```
DT_CAN_TRANSCEIVER_MAX_BITRATE(node_id, max)
```

Get the maximum transceiver bitrate for a CAN controller.

The bitrate will be limited to the maximum bitrate supported by the CAN controller. If no CAN transceiver is present in the devicetree, the maximum bitrate will be that of the CAN controller.

Example devicetree fragment:

```
transceiver0: can-phy0 {
    compatible = "vnd,can-transceiver";
    max-bitrate = <1000000>;
    #phy-cells = <0>;
};

can0: can@... {
    compatible = "vnd,can-controller";
    phys = <&transceiver0>;
};

can1: can@... {
    compatible = "vnd,can-controller";

    can-transceiver {
        max-bitrate = <2000000>;
    };
};
```

Example usage:

```
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can0), 5000000) // 1000000
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can1), 5000000) // 2000000
DT_CAN_TRANSCEIVER_MAX_BITRATE(DT_NODELABEL(can1), 1000000) // 1000000
```

Parameters

- node_id – node identifier
- max – maximum bitrate supported by the CAN controller

Returns

the maximum bitrate supported by the CAN controller/transceiver combination

```
DT_INST_CAN_TRANSCEIVER_MAX_BITRATE(inst, max)
```

Get the maximum transceiver bitrate for a DT_DRV_COMPAT CAN controller.
See also:  

\texttt{DT\_CAN\_TRANSCEIVER\_MAX\_BITRATE()}

\textbf{Parameters}

\begin{itemize}
  \item \texttt{inst} – DT\_DRV\_COMPAT instance number
  \item \texttt{max} – maximum bitrate supported by the CAN controller
\end{itemize}

\textbf{Returns}

the maximum bitrate supported by the CAN controller/transceiver combination

\textbf{Clocks}  

These conveniences may be used for nodes which describe clock sources, and properties related to them.

\textit{group devicetree-clocks}

\textbf{Defines}

\texttt{DT\_CLOCKS\_HAS\_IDX(node\_id, idx)}

Test if a node has a clocks phandle-array property at a given index.

This expands to \texttt{1} if the given index is valid clocks property phandle-array index. Otherwise, it expands to \texttt{0}.

Example devicetree fragment:

\begin{verbatim}
n1: node-1 {
    clocks = <...>, <...>;
};
n2: node-2 {
    clocks = <...>;
};
\end{verbatim}

Example usage:

\begin{verbatim}
DT\_CLOCKS\_HAS\_IDX(DT\_NODELABEL(n1), 0) // 1
DT\_CLOCKS\_HAS\_IDX(DT\_NODELABEL(n1), 1) // 1
DT\_CLOCKS\_HAS\_IDX(DT\_NODELABEL(n1), 2) // 0
DT\_CLOCKS\_HAS\_IDX(DT\_NODELABEL(n2), 1) // 0
\end{verbatim}

\textbf{Parameters}

\begin{itemize}
  \item \texttt{node\_id} – node identifier; may or may not have any clocks property
  \item \texttt{idx} – index of a clocks property phandle-array whose existence to check
\end{itemize}

\textbf{Returns}

1 if the index exists, 0 otherwise

\texttt{DT\_CLOCKS\_HAS\_NAME(node\_id, name)}

Test if a node has a clock-names array property holds a given name.

This expands to \texttt{1} if the name is available as clocks-name array property cell. Otherwise, it expands to \texttt{0}.

Example devicetree fragment:
n1: node-1 {
    clocks = <...>, <...>;
    clock-names = "alpha", "beta";
};

n2: node-2 {
    clocks = <...>;
    clock-names = "alpha";
};

Example usage:

DT_CLOCKS_HAS_NAME(DT_NODELABEL(n1), alpha) // 1
DT_CLOCKS_HAS_NAME(DT_NODELABEL(n1), beta) // 1
DT_CLOCKS_HAS_NAME(DT_NODELABEL(n2), beta) // 0

Parameters

- node_id – node identifier; may or may not have any clock-names property.
- name – lowercase-and-underscores clock-names cell value name to check

Returns

1 if the clock name exists, 0 otherwise

DT_NUM_CLOCKS(node_id)

Get the number of elements in a clocks property.

Example devicetree fragment:

n1: node-1 {
    clocks = <&foo>, <&bar>;
};
n2: node-2 {
    clocks = <&foo>;
};

Example usage:

DT_NUM_CLOCKS(DT_NODELABEL(n1)) // 2
DT_NUM_CLOCKS(DT_NODELABEL(n2)) // 1

Parameters

- node_id – node identifier with a clocks property

Returns

number of elements in the property

DT_CLOCKS_CTLR_BY_IDX(node_id, idx)

Get the node identifier for the controller phandle from a “clocks” phandle-array property at an index.

Example devicetree fragment:

clk1: clock-controller@... { ... };
clk2: clock-controller@... { ... };

(continues on next page)
...continued from previous page...

n: node {
    clocks = <&clk1 10 20>, <&clk2 30 40>;
};

Example usage:

DT_CLOCKS_CTLR_BY_IDX(DT_NODELABEL(n), 0)) // DT_NODELABEL(clk1)
DT_CLOCKS_CTLR_BY_IDX(DT_NODELABEL(n), 1)) // DT_NODELABEL(clk2)

See also:

DT_PHANDLE_BY_IDX()

Parameters

• node_id – node identifier
• idx – logical index into “clocks”

Returns

the node identifier for the clock controller referenced at index “idx”

DT_CLOCKS_CTLR(node_id)

Equivalent to DT_CLOCKS_CTLR_BY_IDX(node_id, 0)

See also:

DT_CLOCKS_CTLR_BY_IDX()

Parameters

• node_id – node identifier

Returns

a node identifier for the clocks controller at index 0 in “clocks”

DT_CLOCKS_CTLR_BY_NAME(node_id, name)

Get the node identifier for the controller phandle from a clocks phandle-array property by
name.

Example devicetree fragment:

clk1: clock-controller@... { ... };
clk2: clock-controller@... { ... };
n: node {
    clocks = <&clk1 10 20>, <&clk2 30 40>;
    clock-names = "alpha", "beta";
};

Example usage:

DT_CLOCKS_CTLR_BY_NAME(DT_NODELABEL(n), beta) // DT_NODELABEL(clk2)

See also:

DT_PHANDLE_BY_NAME()

Parameters
• node_id – node identifier
• name – lowercase-and-underscores name of a clocks element as defined by the
  node's clock-names property

Returns
the node identifier for the clock controller referenced by name

DT_CLOCKS_CELL_BY_IDX(node_id, idx, cell)
Get a clock specifier's cell value at an index.

Example devicetree fragment:

```devicetree
clk1: clock-controller@... {
  compatible = "vnd,clock";
  #clock-cells = < 2 >;
};

n: node {
  clocks = < &clk1 10 20 >, < &clk1 30 40 >;
};
```

Bindings fragment for the vnd,clock compatible:

```devicetree
clock-cells:
- bus
- bits
```

Example usage:

```c
DT_CLOCKS_CELL_BY_IDX(DT_NODELABEL(n), 0, bus) // 10
DT_CLOCKS_CELL_BY_IDX(DT_NODELABEL(n), 1, bits) // 40
```

See also:

* DT_PHA_BY_IDX()

Parameters

• node_id – node identifier for a node with a clocks property
• idx – logical index into clocks property
• cell – lowercase-and-underscores cell name

Returns

the cell value at index "idx"

DT_CLOCKS_CELL_BY_NAME(node_id, name, cell)
Get a clock specifier's cell value by name.

Example devicetree fragment:

```devicetree
clk1: clock-controller@... {
  compatible = "vnd,clock";
  #clock-cells = < 2 >;
};

n: node {
  clocks = < &clk1 10 20 >, < &clk1 30 40 >;
  clock-names = "alpha", "beta";
};
```
Bindings fragment for the vnd,clock compatible:

```plaintext
clock-cells:
- bus
- bits
```

Example usage:

<table>
<thead>
<tr>
<th>Code</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>DT_CLOCKS_CELL_BY_NAME(DT_NODELABEL(n), alpha, bus)</code> // 10</td>
<td>DT_CLOCKS_CELL_BY_NAME(DT_NODELABEL(n), beta, bits) // 40</td>
</tr>
</tbody>
</table>

See also:

`DT_PHA_BY_NAME()`

Parameters

- `node_id` – node identifier for a node with a clocks property
- `name` – lowercase-and-underscores name of a clocks element as defined by the node's clock-names property
- `cell` – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element

```plaintext
DT_CLOCKS_CELL(node_id, cell)
```
Equivalent to `DT_CLOCKS_CELL_BY_IDX(node_id, 0, cell)`

See also:

`DT_CLOCKS_CELL_BY_IDX()`

Parameters

- `node_id` – node identifier for a node with a clocks property
- `cell` – lowercase-and-underscores cell name

Returns

the cell value at index 0

```plaintext
DT_INST_CLOCKS_HAS_IDX(inst, idx)
```
Equivalent to `DT_CLOCKS_HAS_IDX(DT_DRV_INST(inst), idx)`

Parameters

- `inst` – DT_DRV_COMPAT instance number; may or may not have any clocks property
- `idx` – index of a clocks property phandle-array whose existence to check

Returns

1 if the index exists, 0 otherwise

```plaintext
DT_INST_CLOCKS_HAS_NAME(inst, name)
```
Equivalent to `DT_CLOCK_HAS_NAME(DT_DRV_INST(inst), name)`

Parameters

- `inst` – DT_DRV_COMPAT instance number; may or may not have any clock-names property.
- `name` – lowercase-and-underscores clock-names cell value name to check
Returns
1 if the clock name exists, 0 otherwise

\texttt{DT\_INST\_NUM\_CLOCKS(inst)}

Equivalent to \texttt{DT\_NUM\_CLOCKS(DT\_DRV\_INST(inst))}

Parameters
\begin{itemize}
  \item \texttt{inst} – instance number
\end{itemize}

Returns
number of elements in the clocks property

\texttt{DT\_INST\_CLOCKS\_CTRL\_BY\_IDX(inst, idx)}

Get the node identifier for the controller phandle from a “clocks” phandle-array property at an index.

See also:
\texttt{DT\_CLOCKS\_CTRL\_BY\_IDX()}

Parameters
\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{idx} – logical index into “clocks”
\end{itemize}

Returns
the node identifier for the clock controller referenced at index “idx”

\texttt{DT\_INST\_CLOCKS\_CTRL(inst)}

Equivalent to \texttt{DT\_INST\_CLOCKS\_CTRL\_BY\_IDX(inst, 0)}

See also:
\texttt{DT\_CLOCKS\_CTRL()}

Parameters
\begin{itemize}
  \item \texttt{inst} – instance number
\end{itemize}

Returns
a node identifier for the clocks controller at index 0 in “clocks”

\texttt{DT\_INST\_CLOCKS\_CTRL\_BY\_NAME(inst, name)}

Get the node identifier for the controller phandle from a clocks phandle-array property by name.

See also:
\texttt{DT\_CLOCKS\_CTRL\_BY\_NAME()}

Parameters
\begin{itemize}
  \item \texttt{inst} – instance number
  \item \texttt{name} – lowercase-and-underscores name of a clocks element as defined by the node’s clock-names property
\end{itemize}

Returns
the node identifier for the clock controller referenced by the named element
DT_INST_CLOCKS_CELL_BY_IDX(inst, idx, cell)

Get a DT_DRV_COMPAT instance's clock specifier's cell value at an index.

See also:

DT_CLOCKS_CELL_BY_IDX()

Parameters

• inst – DT_DRV_COMPAT instance number
• idx – logical index into clocks property
• cell – lowercase-and-underscores cell name

Returns

the cell value at index “idx”

DT_INST_CLOCKS_CELL_BY_NAME(inst, name, cell)

Get a DT_DRV_COMPAT instance's clock specifier's cell value by name.

See also:

DT_CLOCKS_CELL_BY_NAME()

Parameters

• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a clocks element as defined by the node's clock-names property
• cell – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element

DT_INST_CLOCKS_CELL(inst, cell)

Equivalent to DT_INST_CLOCKS_CELL_BY_IDX(inst, 0, cell)

Parameters

• inst – DT_DRV_COMPAT instance number
• cell – lowercase-and-underscores cell name

Returns

the value of the cell inside the specifier at index 0

DMA These conveniences may be used for nodes which describe direct memory access controllers or channels, and properties related to them.

group devicetree-dmas

Defines
DT_DMAS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the DMA controller from a dmas property at an index.

Example devicetree fragment:

dma1: dma@... { ... };
dma2: dma@... { ... };
n: node {
  dmas = <&dma1 1 2 0x400 0x3>,
    <&dma2 6 3 0x404 0x5>;
};

Example usage:

DT_DMAS_CTLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(dma1)
DT_DMAS_CTLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(dma2)

See also:
DT_PROP_BY_PHANDLE_IDX()

Parameters
• node_id – node identifier for a node with a dmas property
• idx – logical index into dmas property

Returns
the node identifier for the DMA controller referenced at index “idx”

DT_DMAS_CTLR_BY_NAME(node_id, name)
Get the node identifier for the DMA controller from a dmas property by name.

Example devicetree fragment:

dma1: dma@... { ... };
dma2: dma@... { ... };
n: node {
  dmas = <&dma1 1 2 0x400 0x3>,
    <&dma2 6 3 0x404 0x5>;
  dma-names = "tx", "rx";
};

Example usage:

DT_DMAS_CTLR_BY_NAME(DT_NODELABEL(n), tx) // DT_NODELABEL(dma1)
DT_DMAS_CTLR_BY_NAME(DT_NODELABEL(n), rx) // DT_NODELABEL(dma2)

See also:
DT_PHANDLE_BY_NAME()

Parameters
• node_id – node identifier for a node with a dmas property
• name – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property

5.2. Devicetree
Returns
the node identifier for the DMA controller in the named element

`DT_DMAS_CTLR(node_id)`
Equivalent to `DT_DMAS_CTLR_BY_IDX(node_id, 0)`

See also:
`DT_DMAS_CTLR_BY_IDX()`

Parameters
- `node_id` – node identifier for a node with a dmas property

Returns
the node identifier for the DMA controller at index 0 in the node’s “dmas” property

`DT_INST_DMAS_CTLR_BY_IDX(inst, idx)`
Get the node identifier for the DMA controller from a DT_DRV_COMPAT instance’s dmas property at an index.

See also:
`DT_DMAS_CTLR_BY_IDX()`

Parameters
- `inst` – DT_DRV_COMPAT instance number
- `idx` – logical index into dmas property

Returns
the node identifier for the DMA controller referenced at index “idx”

`DT_INST_DMAS_CTLR_BY_NAME(inst, name)`
Get the node identifier for the DMA controller from a DT_DRV_COMPAT instance’s dmas property by name.

See also:
`DT_DMAS_CTLR_BY_NAME()`

Parameters
- `inst` – DT_DRV_COMPAT instance number
- `name` – lowercase-and-underscores name of a dmas element as defined by the node’s dma-names property

Returns
the node identifier for the DMA controller in the named element

`DT_INST_DMAS_CTLR(inst)`
Equivalent to `DT_INST_DMAS_CTLR_BY_IDX(inst, 0)`

See also:
`DT_DMAS_CTLR_BY_IDX()`
Parameters

- inst – DT_DRV_COMPAT instance number

Returns

the node identifier for the DMA controller at index 0 in the instance’s “dmas” property

`DT_DMAS_CELL_BY_IDX(node_id, idx, cell)`

Get a DMA specifier’s cell value at an index.

Example devicetree fragment:

```markdown
dma1: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
}

dma2: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
}

n: node {
    dmas = <&dma1 1 0x400>,
      <&dma2 6 0x404>;
}
```

Bindings fragment for the vnd,dma compatible:

```markdown
dma-cells:
  - channel
  - config
```

Example usage:

```markdown
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 0, channel) // 1
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 1, channel) // 6
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 0, config) // 0x400
DT_DMAS_CELL_BY_IDX(DT_NODELABEL(n), 1, config) // 0x404
```

See also:

`DT_PHA_BY_IDX()`

Parameters

- node_id – node identifier for a node with a dmas property
- idx – logical index into dmas property
- cell – lowercase-and-underscores cell name

Returns

the cell value at index “idx”

`DT_INST_DMAS_CELL_BY_IDX(inst, idx, cell)`

Get a DT_DRV_COMPAT instance’s DMA specifier’s cell value at an index.

See also:

`DT_DMAS_CELL_BY_IDX()`

5.2. Devicetree
Parameters

- inst – DT_DRV_COMPAT instance number
- idx – logical index into dmas property
- cell – lowercase-and-underscores cell name

Returns

the cell value at index “idx”

\texttt{DT_DMAS_CELL_BY_NAME(node\_id, name, cell)}

Get a DMA specifier's cell value by name.

Example devicetree fragment:

```markdown
dma1: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
}

dma2: dma@... {
    compatible = "vnd,dma";
    #dma-cells = <2>;
}

n: node {
    dmas = <&dma1 1 0x400>,
    <&dma2 6 0x404>;
    dma-names = "tx", "rx";
}
```

Bindings fragment for the vnd,dma compatible:

```markdown
dma-cells:
- channel
- config
```

Example usage:

```markdown
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), tx, channel) // 1
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), rx, channel) // 6
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), tx, config) // 0x400
DT_DMAS_CELL_BY_NAME(DT_NODELABEL(n), rx, config) // 0x404
```

See also:

\textit{DT_PHA_BY_NAME()}

Parameters

- node\_id – node identifier for a node with a dmas property
- name – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property
- cell – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element
DT_INST_DMAS_CELL_BY_NAME(inst, name, cell)

Get a DT_DRV_COMPAT instance’s DMA specifier’s cell value by name.

See also:

DT_DMAS_CELL_BY_NAME()

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `name` – lowercase-and-underscores name of a dmas element as defined by the node's dma-names property
- `cell` – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element

DT_DMAS_HAS_IDX(node_id, idx)

Is index “idx” valid for a dmas property?

Parameters

- `node_id` – node identifier for a node with a dmas property
- `idx` – logical index into dmas property

Returns

1 if the “dmas” property has index “idx”, 0 otherwise

DT_INST_DMAS_HAS_IDX(inst, idx)

Is index “idx” valid for a DT_DRV_COMPAT instance’s dmas property?

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `idx` – logical index into dmas property

Returns

1 if the “dmas” property has a specifier at index “idx”, 0 otherwise

DT_DMAS_HAS_NAME(node_id, name)

Does a dmas property have a named element?

Parameters

- `node_id` – node identifier for a node with a dmas property
- `name` – lowercase-and-underscores name of a dmas element as defined by the node’s dma-names property

Returns

1 if the dmas property has the named element, 0 otherwise

DT_INST_DMAS_HAS_NAME(inst, name)

Does a DT_DRV_COMPAT instance’s dmas property have a named element?

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `name` – lowercase-and-underscores name of a dmas element as defined by the node’s dma-names property

Returns

1 if the dmas property has the named element, 0 otherwise
Fixed flash partitions  These conveniences may be used for the special-purpose fixed-partitions compatible used to encode information about flash memory partitions in the device tree. See See fixed-partition for more details.

group devicetree-fixed-partition

Defines

**DT_NODE_BY_FIXED_PARTITION_LABEL(label)**

Get a node identifier for a fixed partition with a given label property.

Example devicetree fragment:

```c
flash@... {
    partitions {
        compatible = "fixed-partitions";
        boot_partition: partition@0 {
            label = "mcuboot";
        }
        slot0_partition: partition@c000 {
            label = "image-0";
        }
    }
}
```

Example usage:

```c
DT_NODE_BY_FIXED_PARTITION_LABEL(mcuboot) // node identifier for boot_partition
DT_NODE_BY_FIXED_PARTITION_LABEL(image_0) // node identifier for slot0_partition
```

**Parameters**

- `label` – lowercase-and-underscores label property value

**Returns**

a node identifier for the partition with that label property

**DT_HAS_FIXED_PARTITION_LABEL(label)**

Test if a fixed partition with a given label property exists.

**Parameters**

- `label` – lowercase-and-underscores label property value

**Returns**

1 if any “fixed-partitions” child node has the given label, 0 otherwise.

**DT_FIXED_PARTITION_EXISTS(node_id)**

Test if fixed-partition compatible node exists.

**Parameters**

- `node_id` – DTS node to test

**Returns**

1 if node exists and is fixed-partition compatible, 0 otherwise.
DT_FIXED_PARTITION_ID(node_id)
Get a numeric identifier for a fixed partition.

Parameters
- node_id – node identifier for a fixed-partitions child node

Returns
the partition’s ID, a unique zero-based index number

DT_MTD_FROM_FIXED_PARTITION(node_id)
Get the node identifier of the flash device for a partition.

Parameters
- node_id – node identifier for a fixed-partitions child node

Returns
the node identifier of the memory technology device that contains the fixed-partitions node.

GPIO
These conveniences may be used for nodes which describe GPIO controllers/pins, and properties related to them.

group devicetree-gpio

Defines

DT_GPIO_CTLR_BY_IDX(node_id, gpio_pha, idx)
Get the node identifier for the controller phandle from a gpio phandle-array property at an index.

Example devicetree fragment:
```
gpio1: gpio@... { };  
gpio2: gpio@... { };  
n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
            <&gpio2 30 GPIO_ACTIVE_HIGH>;
};
```

Example usage:
```
DT_GPIO_CTLR_BY_IDX(DT_NODELABEL(n), gpios, 1) // DT_NODELABEL(gpio2)
```

See also:

DT_PHANDLE_BY_IDX()

Parameters
- node_id – node identifier
- gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”
- idx – logical index into “gpio_pha”

Returns
the node identifier for the gpio controller referenced at index “idx”
DT_GPIO_CTLR(node_id, gpio_pha)
   Equivalent to DT_GPIO_CTLR_BY_IDX(node_id, gpio_pha, 0)

See also:
DT_GPIO_CTLR_BY_IDX()

Parameters
• node_id – node identifier
• gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”

Returns
a node identifier for the gpio controller at index 0 in “gpio_pha”

DT_GPIO_LABEL_BY_IDX(node_id, gpio_pha, idx)
   Get a label property from a gpio phandle-array property at an index.

Deprecated:
   If used to obtain a device instance with device_get_binding, consider using
   DEVICE_DT_GET(DT_GPIO_CTLR_BY_IDX(node, gpio_pha, idx)).
   It's an error if the GPIO controller node referenced by the phandle in node_id's “gpio_pha”
   property at index “idx” has no label property.

Example devicetree fragment:

```plaintext
gpio1: gpio@... {
    label = "GPIO_1";
};

gpio2: gpio@... {
    label = "GPIO_2";
};

n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
           <&gpio2 30 GPIO_ACTIVE_HIGH>;
};
```

Example usage:

```plaintext
DT_GPIO_LABEL_BY_IDX(DT_NODELABEL(n), gpios, 1) // "GPIO_2"
```

See also:
DT_PHANDLE_BY_IDX()

Parameters
• node_id – node identifier
• gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”
• idx – logical index into “gpio_pha”

Returns
the label property of the node referenced at index “idx”
DT_GPIO_LABEL(node_id, gpio_pha)

Equivalent to `DT_GPIO_LABEL_BY_IDX(node_id, gpio_pha, 0)`

**Deprecated:**
If used to obtain a device instance with `device_get_binding`, consider using `DEVICE_DT_GET(DT_GPIO_CTLR(node, gpio_pha))`.

**See also:**
`DT_GPIO_LABEL_BY_IDX()`

**Parameters**
- `node_id` - node identifier
- `gpio_pha` - lowercase-and-underscores GPIO property with type “phandle-array”

**Returns**
the label property of the node referenced at index 0

DT_GPIO_PIN_BY_IDX(node_id, gpio_pha, idx)

Get a GPIO specifier’s pin cell at an index.

This macro only works for GPIO specifiers with cells named “pin”. Refer to the node’s binding to check if necessary.

Example devicetree fragment:

```plaintext
gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};

gpio2: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};

n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
        <&gpio2 30 GPIO_ACTIVE_HIGH>;
};
```

Bindings fragment for the vnd,gpio compatible:

```plaintext
gpio-cells:
- pin
- flags
```

Example usage:

```plaintext
DT_GPIO_PIN_BY_IDX(DT_NODELABEL(n), gpios, 0) // 10
DT_GPIO_PIN_BY_IDX(DT_NODELABEL(n), gpios, 1) // 30
```

**See also:**
`DT_PHA_BY_IDX()`

**Parameters**
• node_id – node identifier
• gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”
• idx – logical index into “gpio_pha”

**Returns**
the pin cell value at index “idx”

\[ \text{DT\_GPIO\_PIN} \text{(node\_id, gpio\_pha)} \]
Equivalent to \[ \text{DT\_GPIO\_PIN\_BY\_IDX} \text{(node\_id, gpio\_pha, 0)} \]

**See also:**
\[ \text{DT\_GPIO\_PIN\_BY\_IDX}() \]

**Parameters**
• node_id – node identifier
• gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”

**Returns**
the pin cell value at index 0

\[ \text{DT\_GPIO\_FLAGS\_BY\_IDX} \text{(node\_id, gpio\_pha, idx)} \]
Get a GPIO specifier’s flags cell at an index.

This macro expects GPIO specifiers with cells named “flags”. If there is no “flags” cell in the GPIO specifier, zero is returned. Refer to the node’s binding to check specifier cell names if necessary.

Example devicetree fragment:

```dts
gpio1: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};
gpio2: gpio@... {
    compatible = "vnd,gpio";
    #gpio-cells = <2>;
};
n: node {
    gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
             <&gpio2 30 GPIO_ACTIVE_HIGH>;
};
```

**Example usage:**

\[ \text{DT\_GPIO\_FLAGS\_BY\_IDX} \text{(DT\_NODELABEL(n), gpios, 0)} \] // GPIO_ACTIVE_LOW
\[ \text{DT\_GPIO\_FLAGS\_BY\_IDX} \text{(DT\_NODELABEL(n), gpios, 1)} \] // GPIO_ACTIVE_HIGH
See also:

\texttt{DT\_PH\_BY\_IDX()}

Parameters

\begin{itemize}
\item node\_id – node identifier
\item gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-
array”
\item idx – logical index into “gpio\_pha”
\end{itemize}

Returns

the flags cell value at index “idx”, or zero if there is none

\texttt{DT\_GPIO\_FLAGS(node\_id, gpio\_pha)}

Equivalent to \texttt{DT\_GPIO\_FLAGS\_BY\_IDX(node\_id, gpio\_pha, 0)}

See also:

\texttt{DT\_GPIO\_FLAGS\_BY\_IDX()}

Parameters

\begin{itemize}
\item node\_id – node identifier
\item gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-
array”
\end{itemize}

Returns

the flags cell value at index 0, or zero if there is none

\texttt{DT\_INST\_GPIO\_LABEL\_BY\_IDX(inst, gpio\_pha, idx)}

Get a label property from a DT\_DRV\_COMPAT instance's GPIO property at an index.

\textit{Deprecated:}

If used to obtain a device instance with device\_get\_binding, consider using \texttt{DEVICE\_DT\_GET(DT\_INST\_GPIO\_CTRL\_BY\_IDX(node, gpio\_pha, idx))}.

Parameters

\begin{itemize}
\item inst – DT\_DRV\_COMPAT instance number
\item gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-
array”
\item idx – logical index into “gpio\_pha”
\end{itemize}

Returns

the label property of the node referenced at index “idx”

\texttt{DT\_INST\_GPIO\_LABEL(inst, gpio\_pha)}

Equivalent to \texttt{DT\_INST\_GPIO\_LABEL\_BY\_IDX(inst, gpio\_pha, 0)}

\textit{Deprecated:}

If used to obtain a device instance with device\_get\_binding, consider using \texttt{DEVICE\_DT\_GET(DT\_INST\_GPIO\_CTRL(node, gpio\_pha))}.

Parameters
• inst – DT_DRV_COMPAT instance number
• gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”

Returns
the label property of the node referenced at index 0

\texttt{DT_INST_GPIO_PIN\_BY\_IDX(inst, gpio\_pha, idx)}
Get a DT\_DRV\_COMPAT instance’s GPIO specifier’s pin cell value at an index.

\textbf{See also:}
\textit{DT\_GPIO\_PIN\_BY\_IDX()}

\textbf{Parameters}
• inst – DT\_DRV\_COMPAT instance number
• gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-array”
• idx – logical index into “gpio\_pha”

Returns
the pin cell value at index “idx”

\texttt{DT\_INST\_GPIO\_PIN(inst, gpio\_pha)}
Equivalent to \texttt{DT\_INST\_GPIO\_PIN\_BY\_IDX(inst, gpio\_pha, 0)}

\textbf{See also:}
\textit{DT\_INST\_GPIO\_PIN\_BY\_IDX()}

\textbf{Parameters}
• inst – DT\_DRV\_COMPAT instance number
• gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-array”

Returns
the pin cell value at index 0

\texttt{DT\_INST\_GPIO\_FLAGS\_BY\_IDX(inst, gpio\_pha, idx)}
Get a DT\_DRV\_COMPAT instance’s GPIO specifier’s flags cell at an index.

\textbf{See also:}
\textit{DT\_GPIO\_FLAGS\_BY\_IDX()}

\textbf{Parameters}
• inst – DT\_DRV\_COMPAT instance number
• gpio\_pha – lowercase-and-underscores GPIO property with type “phandle-array”
• idx – logical index into “gpio\_pha”

Returns
the flags cell value at index “idx”, or zero if there is none
DT_INST_GPIO_FLAGS(inst, gpio_pha)
Equivalent to DT_INST_GPIO_FLAGS_BY_IDX(inst, gpio_pha, 0)

See also:
DT_INST_GPIO_FLAGS_BY_IDX()

Parameters
- inst – DT_DRV_COMPAT instance number
- gpio_pha – lowercase-and-underscores GPIO property with type “phandle-array”

Returns
the flags cell value at index 0, or zero if there is none

IO channels These are commonly used by device drivers which need to use IO channels (e.g. ADC or DAC channels) for conversion.

group devicetree-io-channels

Defines

DT_IO_CHANNELS_CTLR_BY_IDX(node_id, idx)
Get the node identifier for the node referenced by an io-channels property at an index.

Example devicetree fragment:

```
adc1: adc@... { ... };
adc2: adc@... { ... };
n: node {
  io-channels = <&adc1 10>, <&adc2 20>;
};
```

Example usage:

```
DT_IO_CHANNELS_CTLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(adc1)
DT_IO_CHANNELS_CTLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(adc2)
```

See also:
DT_PROP_BY_PHANDLE_IDX()

Parameters
- node_id – node identifier for a node with an io-channels property
- idx – logical index into io-channels property

Returns
the node identifier for the node referenced at index “idx”

DT_IO_CHANNELS_CTLR_BY_NAME(node_id, name)
Get the node identifier for the node referenced by an io-channels property by name.

Example devicetree fragment:
adc1: adc@... { ... };
adc2: adc@... { ... };

n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
};

Example usage:

DT_IO_CHANNELS_CTLR_BY_NAME(DT_NODELABEL(n), sensor) // DT_NODELABEL(adc1)
DT_IO_CHANNELS_CTLR_BY_NAME(DT_NODELABEL(n), bandgap) // DT_NODELABEL(adc2)

See also:

DT_PHANDLE_BY_NAME()

Parameters

• node_id – node identifier for a node with an io-channels property
• name – lowercase-and-underscores name of an io-channels element as defined by the node's io-channel-names property

Returns

the node identifier for the node referenced at the named element

DT_IO_CHANNELS_CTLR(node_id)

Equivalent to DT_IO_CHANNELS_CTLR_BY_IDX(node_id, 0)

See also:

DT_IO_CHANNELS_CTLR_BY_IDX()

Parameters

• node_id – node identifier for a node with an io-channels property

Returns

the node identifier for the node referenced at index 0 in the node's “io-channels” property

DT_INST_IO_CHANNELS_CTLR_BY_IDX(inst, idx)

Get the node identifier from a DT_DRV_COMPAT instance's io-channels property at an index.

See also:

DT_IO_CHANNELS_CTLR_BY_IDX()

Parameters

• inst – DT_DRV_COMPAT instance number
• idx – logical index into io-channels property

Returns

the node identifier for the node referenced at index “idx”
DT_INST_IO_CHANNELS_CTLR_BY_NAME(inst, name)

Get the node identifier from a DT_DRV_COMPAT instance's io-channels property by name.

See also:

* DT_IO_CHANNELS_CTLR_BY_NAME()

Parameters

- inst – DT_DRV_COMPAT instance number
- name – lowercase-and-underscores name of an io-channels element as defined by the node's io-channel-names property

Returns

the node identifier for the node referenced at the named element

DT_INST_IO_CHANNELS_CTLR(inst)

Equivalent to DT_INST_IO_CHANNELS_CTLR_BY_IDX(inst, 0)

See also:

* DT_IO_CHANNELS_CTLR_BY_IDX()

Parameters

- inst – DT_DRV_COMPAT instance number

Returns

the node identifier for the node referenced at index 0 in the node's “io-channels” property

DT_IO_CHANNELS_INPUT_BY_IDX(node_id, idx)

Get an io-channels specifier input cell at an index.

This macro only works for io-channels specifiers with cells named “input”. Refer to the node’s binding to check if necessary.

Example devicetree fragment:

```
adci: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
adc2: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};
n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
};
```

Bindings fragment for the vnd,adc compatible:

io-channel-cells:

- input

Example usage:
DT_IO_CHANNELS_INPUT_BY_IDX(DT_NODELABEL(n), 0) // 10
DT_IO_CHANNELS_INPUT_BY_IDX(DT_NODELABEL(n), 1) // 20

See also:

DT_PHA_BY_IDX()

Parameters

• node_id – node identifier for a node with an io-channels property
• idx – logical index into io-channels property

Returns

the input cell in the specifier at index “idx”

DT_IO_CHANNELS_INPUT_BY_NAME(node_id, name)

Get an io-channels specifier input cell by name.

This macro only works for io-channels specifiers with cells named “input”. Refer to the node’s binding to check if necessary.

Example devicetree fragment:

adc1: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};

adc2: adc@... {
    compatible = "vnd,adc";
    #io-channel-cells = <1>;
};

n: node {
    io-channels = <&adc1 10>, <&adc2 20>;
    io-channel-names = "SENSOR", "BANDGAP";
};

Bindings fragment for the vnd,adc compatible:

io-channel-cells:
• input

Example usage:

DT_IO_CHANNELS_INPUT_BY_NAME(DT_NODELABEL(n), sensor) // 10
DT_IO_CHANNELS_INPUT_BY_NAME(DT_NODELABEL(n), bandgap) // 20

See also:

DT_PHA_BY_NAME()

Parameters

• node_id – node identifier for a node with an io-channels property
• name – lowercase-and-underscores name of an io-channels element as defined by the node’s io-channel-names property

Returns

the input cell in the specifier at the named element
DT_IO_CHANNELS_INPUT(node_id)
   Equivalent to DT_IO_CHANNELS_INPUT_BY_IDX(node_id, 0)

See also:
   DT_IO_CHANNELS_INPUT_BY_IDX()

Parameters
   • node_id – node identifier for a node with an io-channels property

Returns
   the input cell in the specifier at index 0

DT_INST_IO_CHANNELS_INPUT_BY_IDX(inst, idx)
   Get an input cell from the “DT_DRV_INST(inst)” io-channels property at an index.

See also:
   DT_IO_CHANNELS_INPUT_BY_IDX()

Parameters
   • inst – DT_DRV_COMPAT instance number
   • idx – logical index into io-channels property

Returns
   the input cell in the specifier at index “idx”

DT_INST_IO_CHANNELS_INPUT_BY_NAME(inst, name)
   Get an input cell from the “DT_DRV_INST(inst)” io-channels property by name.

See also:
   DT_IO_CHANNELS_INPUT_BY_NAME()

Parameters
   • inst – DT_DRV_COMPAT instance number
   • name – lowercase-and-underscores name of an io-channels element as defined
            by the instance’s io-channel-names property

Returns
   the input cell in the specifier at the named element

DT_INST_IO_CHANNELS_INPUT(inst)
   Equivalent to DT_INST_IO_CHANNELS_INPUT_BY_IDX(inst, 0)

Parameters
   • inst – DT_DRV_COMPAT instance number

Returns
   the input cell in the specifier at index 0
These conveniences may be used for nodes which describe MBOX controllers/users, and properties related to them.

**group devicetree-mbox**

**Defines**

`DT_MBOX_CTLR_BY_NAME(node_id, name)`

Get the node identifier for the MBOX controller from a mboxes property by name.

Example devicetree fragment:

```markdown
mbox1: mbox-controller@... { ... };

n: node {
    mboxes = <&mbox1 8>,
             <&mbox1 9>;
    mbox-names = "tx", "rx";
}
```

Example usage:

```markdown
DT_MBOX_CTLR_BY_NAME(DT_NODELABEL(n), tx) // DT_NODELABEL(mbox1)
DT_MBOX_CTLR_BY_NAME(DT_NODELABEL(n), rx) // DT_NODELABEL(mbox1)
```

**See also:**

`DT_PHANDLE_BY_NAME()`

**Parameters**

- `node_id` – node identifier for a node with a mboxes property
- `name` – lowercase-and-underscores name of a mboxes element as defined by the node's mbox-names property

**Returns**

the node identifier for the MBOX controller in the named element

`DT_MBOX_CHANNEL_BY_NAME(node_id, name)`

Get a MBOX channel value by name.

Example devicetree fragment:

```markdown
mbox1: mbox@... {
    #mbox-cells = <1>;
}

n: node {
    mboxes = <&mbox1 1>,
             <&mbox1 6>;
    mbox-names = "tx", "rx";
}
```

Bindings fragment for the mbox compatible:

```markdown
mbox-cells:
    - channel
```
Parameters

- node_id – node identifier for a node with a mboxes property
- name – lowercase-and-underscores name of a mboxes element as defined by the
  node's mbox-names property

Returns

the channel value in the specifier at the named element or 0 if no channels are
supported

Pinctrl (pin control) These are used to access pin control properties by name or index.

Devicetree nodes may have properties which specify pin control (sometimes known as pin mux) settings.
These are expressed using pinctrl-<index> properties within the node, where the <index> values are
contiguous integers starting from 0. These may also be named using the pinctrl-names property.

Here is an example:

```plaintext
node {

  ...  
  pinctrl-0 = <&foo &bar ...>; 
  pinctrl-1 = <&baz ...>;  
  pinctrl-names = "default", "sleep"; 
}
```

Above, pinctrl-0 has name "default", and pinctrl-1 has name "sleep". The pinctrl-<index>
property values contain phandles. The &foo, &bar, etc. phandles within the properties point to nodes
whose contents vary by platform, and which describe a pin configuration for the node.

```
group devicetree-pinctrl
```

Defines

DT_PINCTRL_BY_IDX(node_id, pc_idx, idx)
Get a node identifier for a phandle in a pinctrl property by index.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <&foo &bar>;  
    pinctrl-1 = <&baz &blub>; 
}
```

Example usage:

```plaintext
DT_PINCTRL_BY_IDX(DT_NODELABEL(n), 0, 1) // DT_NODELABEL(bar)
DT_PINCTRL_BY_IDX(DT_NODELABEL(n), 1, 0) // DT_NODELABEL(baz)
```

Parameters

- node_id – node with a pinctrl-'pc_idx' property

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• `pc_idx` – index of the pinctrl property itself
• `idx` – index into the value of the pinctrl property

**Returns**
node identifier for the phandle at index ‘idx’ in ‘pinctrl-‘pc_idx’

`DT_PINCTRL_0(node_id, idx)`
Get a node identifier from a pinctrl-0 property.
This is equivalent to:

`DT_PINCTRL_BY_IDX(node_id, 0, idx)`

It is provided for convenience since pinctrl-0 is commonly used.

**Parameters**
• `node_id` – node with a pinctrl-0 property
• `idx` – index into the pinctrl-0 property

**Returns**
node identifier for the phandle at index idx in the pinctrl-0 property of that node

`DT_PINCTRL_BY_NAME(node_id, name, idx)`
Get a node identifier for a phandle inside a pinctrl node by name.

Example devicetree fragment:
```plaintext
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz &blub>;
    pinctrl-names = "default", "sleep";
};
```

Example usage:

`DT_PINCTRL_BY_NAME(DT_NODELABEL(n), default, 1) // DT_NODELABEL(bar)`
`DT_PINCTRL_BY_NAME(DT_NODELABEL(n), sleep, 0) // DT_NODELABEL(baz)`

**Parameters**
• `node_id` – node with a named pinctrl property
• `name` – lowercase-and-underscores pinctrl property name
• `idx` – index into the value of the named pinctrl property

**Returns**
node identifier for the phandle at that index in the pinctrl property

`DT_PINCTRL_NAME_TO_IDX(node_id, name)`
Convert a pinctrl name to its corresponding index.

Example devicetree fragment:
```plaintext
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz &blub>;
    pinctrl-names = "default", "sleep";
};
```

Example usage:
DT_PINCTRL_NAME_TO_IDX(DT_NODELABEL(n), default) // 0
DT_PINCTRL_NAME_TO_IDX(DT_NODELABEL(n), sleep) // 1

Parameters
- node_id – node identifier with a named pinctrl property
- name – lowercase-and-underscores name name of the pinctrl whose index to get

Returns
integer literal for the index of the pinctrl property with that name

DT_PINCTRL_IDX_TO_NAME_TOKEN(node_id, pc_idx)
Convert a pinctrl property index to its name as a token.

This allows you to get a pinctrl property's name, and “remove the quotes” from it.

DT_PINCTRL_IDX_TO_NAME_TOKEN() can only be used if the node has a pinctrl-'pc_idx' property and a pinctrl-names property element for that index. It is an error to use it in other circumstances.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
    pinctrl-names = "default", "f.o.o2";
};
```

Example usage:

```
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 0) // default
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 1) // f_o_o2
```

The same caveats and restrictions that apply to DT_STRING_TOKEN()'s return value also apply here.

Parameters
- node_id – node identifier
- pc_idx – index of a pinctrl property in that node

Returns
name of the pinctrl property, as a token, without any quotes and with non-alphanumeric characters converted to underscores

DT_PINCTRL_IDX_TO_NAME_UPPER_TOKEN(node_id, pc_idx)
Like DT_PINCTRL_IDX_TO_NAME_TOKEN(), but with an uppercased result.

This does the a similar conversion as DT_PINCTRL_IDX_TO_NAME_TOKEN(node_id, pc_idx). The only difference is that alphabetical characters in the result are uppercased.

Example devicetree fragment:

```plaintext
n: node {
    pinctrl-0 = <...>;
    pinctrl-1 = <...>;
    pinctrl-names = "default", "f.o.o2";
};
```
Example usage:

```c
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 0) // DEFAULT
DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_NODELABEL(n), 1) // F_O_O2
```

The same caveats and restrictions that apply to `DT_STRING_UPPER_TOKEN()`'s return value also apply here.

`DT_NUM_PINCTRLS_BY_IDX(node_id, pc_idx)`

Get the number of phandles in a pinctrl property.

Example devicetree fragment:

```devicetree
n1: node-1 {
    pinctrl-0 = <&foo &bar>;
};
n2: node-2 {
    pinctrl-0 = <&baz>;
};
```

Example usage:

```c
DT_NUM_PINCTRLS_BY_IDX(DT_NODELABEL(n1), 0) // 2
DT_NUM_PINCTRLS_BY_IDX(DT_NODELABEL(n2), 0) // 1
```

**Parameters**

- `node_id` – node identifier with a pinctrl property
- `pc_idx` – index of the pinctrl property itself

**Returns**

number of phandles in the property with that index

`DT_NUM_PINCTRLS_BY_NAME(node_id, name)`

Like `DT_NUM_PINCTRLS_BY_IDX()`, but by name instead.

Example devicetree fragment:

```devicetree
n: node {
    pinctrl-0 = <&foo &bar>;
    pinctrl-1 = <&baz>
    pinctrl-names = "default", "sleep";
};
```

Example usage:

```c
DT_NUM_PINCTRLS_BY_NAME(DT_NODELABEL(n), default) // 2
DT_NUM_PINCTRLS_BY_NAME(DT_NODELABEL(n), sleep) // 1
```

**Parameters**

- `node_id` – node identifier with a pinctrl property
- `name` – lowercase-and-underscores name name of the pinctrl property

**Returns**

number of phandles in the property with that name
DT_NUM_PINCTRL_STATES(node_id)

Get the number of pinctrl properties in a node.
This expands to 0 if there are no pinctrl-i properties. Otherwise, it expands to the number of such properties.

Example devicetree fragment:

n1: node-1 {
  pinctrl-0 = <...>;
  pinctrl-1 = <...>;
};

n2: node-2 {
};

Example usage:

DT_NUM_PINCTRL_STATES(DT_NODELABEL(n1)) // 2
DT_NUM_PINCTRL_STATES(DT_NODELABEL(n2)) // 0

Parameters

- node_id – node identifier; may or may not have any pinctrl properties

Returns

number of pinctrl properties in the node

DT_PINCTRL_HAS_IDX(node_id, pc_idx)

Test if a node has a pinctrl property with an index.
This expands to 1 if the pinctrl-'idx' property exists. Otherwise, it expands to 0.

Example devicetree fragment:

n1: node-1 {
  pinctrl-0 = <...>;
  pinctrl-1 = <...>;
};

n2: node-2 {
};

Example usage:

DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 0) // 1
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 1) // 1
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n1), 2) // 0
DT_PINCTRL_HAS_IDX(DT_NODELABEL(n2), 0) // 0

Parameters

- node_id – node identifier; may or may not have any pinctrl properties
- pc_idx – index of a pinctrl property whose existence to check

Returns

1 if the property exists, 0 otherwise
DT_PINCTRL_HAS_NAME(node_id, name)
Test if a node has a pinctrl property with a name.
This expands to 1 if the named pinctrl property exists. Otherwise, it expands to 0.
Example devicetree fragment:

```
n1: node-1 {
   pinctrl-0 = <...>;
   pinctrl-names = "default";
};
n2: node-2 {
};
```

Example usage:

```
DT_PINCTRL_HAS_NAME(DT_NODELABEL(n1), default) // 1
DT_PINCTRL_HAS_NAME(DT_NODELABEL(n1), sleep)  // 0
DT_PINCTRL_HAS_NAME(DT_NODELABEL(n2), default) // 0
```

Parameters
- **node_id** – node identifier; may or may not have any pinctrl properties
- **name** – lowercase-and-underscores pinctrl property name to check

Returns
1 if the property exists, 0 otherwise

DT_INST_PINCTRL_BY_IDX(inst, pc_idx, idx)
Get a node identifier for a phandle in a pinctrl property by index for a DT_DRV_COMPAT instance.
This is equivalent to `DT_PINCTRL_BY_IDX(DT_DRV_INST(inst), pc_idx, idx)`.

Parameters
- **inst** – instance number
- **pc_idx** – index of the pinctrl property itself
- **idx** – index into the value of the pinctrl property

Returns
node identifier for the phandle at index ‘idx’ in ‘pinctrl-‘pc_idx”

DT_INST_PINCTRL_0(inst, idx)
Get a node identifier from a pinctrl-0 property for a DT_DRV_COMPAT instance.
This is equivalent to:

```
DT_PINCTRL_BY_IDX(DT_DRV_INST(inst), 0, idx)
```

It is provided for convenience since pinctrl-0 is commonly used.

Parameters
- **inst** – instance number
- **idx** – index into the pinctrl-0 property

Returns
node identifier for the phandle at index idx in the pinctrl-0 property of that instance
DT_INST_PINCTRL_BY_NAME(inst, name, idx)
Get a node identifier for a phandle inside a pinctrl node for a DT_DRV_COMPAT instance.
This is equivalent to DT_PINCTRL_BY_NAME(DT_DRV_INST(inst), name, idx).

Parameters
• inst – instance number
• name – lowercase-and-underscores pinctrl property name
• idx – index into the value of the named pinctrl property

Returns
node identifier for the phandle at that index in the pinctrl property

DT_INST_PINCTRL_NAME_TO_IDX(inst, name)
Convert a pinctrl name to its corresponding index for a DT_DRV_COMPAT instance.
This is equivalent to DT_PINCTRL_NAME_TO_IDX(DT_DRV_INST(inst), name).

Parameters
• inst – instance number
• name – lowercase-and-underscores name of the pinctrl whose index to get

Returns
integer literal for the index of the pinctrl property with that name

DT_INST_PINCTRL_IDX_TO_NAME_TOKEN(inst, pc_idx)
Convert a pinctrl index to its name as an uppercased token.
This is equivalent to DT_PINCTRL_IDX_TO_NAME_TOKEN(DT_DRV_INST(inst), pc_idx).

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
name of the pin control property as a token

DT_INST_PINCTRL_IDX_TO_NAME_UPPER_TOKEN(inst, pc_idx)
Convert a pinctrl index to its name as an uppercase token.
This is equivalent to DT_PINCTRL_IDX_TO_NAME_UPPER_TOKEN(DT_DRV_INST(inst), pc_idx).

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
name of the pin control property as an uppercase token

DT_INST_NUM_PINCTRLS_BY_IDX(inst, pc_idx)
Get the number of phandles in a pinctrl property for a DT_DRV_COMPAT instance.
This is equivalent to DT_NUM_PINCTRLS_BY_IDX(DT_DRV_INST(inst), pc_idx).

Parameters
• inst – instance number
• pc_idx – index of the pinctrl property itself

Returns
number of phandles in the property with that index

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DT_INST_NUM_PINCTRLS_BY_NAME(inst, name)

Like DT_INST_NUM_PINCTRLS_BY_IDX(), but by name instead.
This is equivalent to DT_NUM_PINCTRLS_BY_NAME(DT_DRV_INST(inst), name).

Parameters

• inst – instance number
• name – lowercase-and-underscores name of the pinctrl property

Returns

number of phandles in the property with that name

DT_INST_NUM_PINCTRL_STATES(inst)

Get the number of pinctrl properties in a DT_DRV_COMPAT instance.
This is equivalent to DT_NUM_PINCTRL_STATES(DT_DRV_INST(inst)).

Parameters

• inst – instance number

Returns

number of pinctrl properties in the instance

DT_INST_PINCTRL_HAS_IDX(inst, pc_idx)

Test if a DT_DRV_COMPAT instance has a pinctrl property with an index.
This is equivalent to DT_PINCTRL_HAS_IDX(DT_DRV_INST(inst), pc_idx).

Parameters

• inst – instance number
• pc_idx – index of a pinctrl property whose existence to check

Returns

1 if the property exists, 0 otherwise

DT_INST_PINCTRL_HAS_NAME(inst, name)

Test if a DT_DRV_COMPAT instance has a pinctrl property with a name.
This is equivalent to DT_PINCTRL_HAS_NAME(DT_DRV_INST(inst), name).

Parameters

• inst – instance number
• name – lowercase-and-underscores pinctrl property name to check

Returns

1 if the property exists, 0 otherwise

PWM These conveniences may be used for nodes which describe PWM controllers and properties related to them.

group devicetree-pwms

Defines

DT_PWMS_CTRLR_BY_IDX(node_id, idx)

Get the node identifier for the PWM controller from a pwms property at an index.
Example devicetree fragment:
pwm1: pwm-controller@... { ... };
pwm2: pwm-controller@... { ... };
n: node {
    pwms = <&pwm1 1 PWM_POLARITY_NORMAL>,
           <&pwm2 3 PWM_POLARITY_INVERTED>;
};

Example usage:
DT_PWMS_CTLR_BY_IDX(DT_NODELABEL(n), 0) // DT_NODELABEL(pwm1)
DT_PWMS_CTLR_BY_IDX(DT_NODELABEL(n), 1) // DT_NODELABEL(pwm2)

See also:
DT_PROP_BY_PHANDLE_IDX()

Parameters

• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property

Returns

the node identifier for the PWM controller referenced at index “idx”

DT_PWMS_CTLR_BY_NAME(node_id, name)

Get the node identifier for the PWM controller from a pwms property by name.

Example devicetree fragment:
pwm1: pwm-controller@... { ... };
pwm2: pwm-controller@... { ... };
n: node { pwms = <&pwm1 1 PWM_POLARITY_NORMAL>,
           <&pwm2 3 PWM_POLARITY_INVERTED>; pwm-names = “alpha”, “beta”; }

Example usage:
DT_PWMS_CTLR_BY_NAME(DT_NODELABEL(n), alpha) // DT_NODELABEL(pwm1)
DT_PWMS_CTLR_BY_NAME(DT_NODELABEL(n), beta) // DT_NODELABEL(pwm2)

See also:
DT_PHANDLE_BY_NAME()

Parameters

• node_id – node identifier for a node with a pwms property
• name – lowercase-and-underscores name of a pwms element as defined by the
  node’s pwm-names property

Returns

the node identifier for the PWM controller in the named element

DT_PWMS_CTLR(node_id)
Equivalent to DT_PWMS_CTLR_BY_IDX(node_id, 0)
DT_PWMS_CTLR_BY_IDX()

Parameters

• node_id – node identifier for a node with a pwms property

Returns

the node identifier for the PWM controller at index 0 in the node's "pwms" property

DT_PWMS_CELL_BY_IDX(node_id, idx, cell)

Get PWM specifier's cell value at an index.

Example devicetree fragment:

```plaintext
pwm1: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

pwm2: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

n: node {
    pwms = <&pwm1 1 200000 PWM_POLARITY_NORMAL>,
          <&pwm2 3 100000 PWM_POLARITY_INVERTED>;
};
```

Bindings fragment for the “vnd,pwm” compatible:

```plaintext
pwm-cells:
    - channel
    - period
    - flags
```

Example usage:

```plaintext
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, channel) // 1
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, channel) // 3
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, period) // 200000
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, period) // 100000
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 0, flags) // PWM_POLARITY_NORMAL
DT_PWMS_CELL_BY_IDX(DT_NODELABEL(n), 1, flags) // PWM_POLARITY_INVERTED
```

See also:

DT_PHA_BY_IDX()

Parameters

• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property
• cell – lowercase-and-underscores cell name

Returns

the cell value at index “idx”
DT_PWMS_CELL_BY_NAME(node_id, name, cell)
Get a PWM specifier's cell value by name.

Example devicetree fragment:

```
pwm1: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

pwm2: pwm-controller@... {
    compatible = "vnd,pwm";
    #pwm-cells = <2>;
};

n: node {
    pwms = <&pwm1 1 200000 PWM_POLARITY_NORMAL>,
           <&pwm2 3 100000 PWM_POLARITY_INVERTED>;
    pwm-names = "alpha", "beta";
};
```

Bindings fragment for the “vnd,pwm” compatible:

```
pwm-cells:
- channel
- period
- flags
```

Example usage:

```
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, channel) // 1
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), beta, channel) // 3
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, period) // 200000
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), beta, period) // 100000
DT_PWMS_CELL_BY_NAME(DT_NODELABEL(n), alpha, flags) // PWM_POLARITY_NORMAL
DT_PWMSgetCellByIndex(DT_NODELABEL(n), beta, flags) // PWM_POLARITY_INVERTED
```

See also:

`DT_PHA_BY_NAME()`

**Parameters**

- node_id – node identifier for a node with a pwms property
- name – lowercase-and-underscores name of a pwms element as defined by the node's pwm-names property
- cell – lowercase-and-underscores cell name

**Returns**
the cell value in the specifier at the named element

DT_PWMSCELL(node_id, cell)
Equivalent to `DT_PWMS_CELL_BY_IDX(node_id, 0, cell)`

See also:

`DT_PWMS_CELL_BY_IDX()`

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Parameters
• node_id – node identifier for a node with a pwms property
• cell – lowercase-and-underscores cell name

Returns
the cell value at index 0

DT_PWMS_CHANNEL_BY_IDX(node_id, idx)
Get a PWM specifier's channel cell value at an index.
This macro only works for PWM specifiers with cells named “channel”. Refer to the node’s binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_IDX(node_id, idx, channel).

See also:
DT_PWMS_CELL_BY_IDX()

Parameters
• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property

Returns
the channel cell value at index “idx”

DT_PWMS_CHANNEL_BY_NAME(node_id, name)
Get a PWM specifier's channel cell value by name.
This macro only works for PWM specifiers with cells named “channel”. Refer to the node’s binding to check if necessary.
This is equivalent to DT_PWMS_CELL_BY_NAME(node_id, name, channel).

See also:
DT_PWMS_CELL_BY_NAME()

Parameters
• node_id – node identifier for a node with a pwms property
• name – lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

Returns
the channel cell value in the specifier at the named element

DT_PWMS_CHANNEL(node_id)
Equivalent to DT_PWMS_CHANNEL_BY_IDX(node_id, 0)

See also:
DT_PWMS_CHANNEL_BY_IDX()
**DT_PWMS_PERIOD_BY_IDX(node_id, idx)**

Get PWM specifier's period cell value at an index.

This macro only works for PWM specifiers with cells named “period”. Refer to the node's binding to check if necessary.

This is equivalent to `DT_PWMS_CELL_BY_IDX(node_id, idx, period)`.

**See also:**

`DT_PWMS_CELL_BY_IDX()`

**Parameters**

- `node_id` – node identifier for a node with a pwms property
- `idx` – logical index into pwms property

**Returns**

the channel cell value at index 0

**Returns**

the period cell value at index “idx”

**DT_PWMS_PERIOD_BY_NAME(node_id, name)**

Get a PWM specifier's period cell value by name.

This macro only works for PWM specifiers with cells named “period”. Refer to the node's binding to check if necessary.

This is equivalent to `DT_PWMS_CELL_BY_NAME(node_id, name, period)`.

**See also:**

`DT_PWMS_CELL_BY_NAME()`

**Parameters**

- `node_id` – node identifier for a node with a pwms property
- `name` – lowercase-and-underscores name of a pwms element as defined by the node's pwm-names property

**Returns**

the period cell value in the specifier at the named element

**DT_PWMS_PERIOD(node_id)**

Equivalent to `DT_PWMS_PERIOD_BY_IDX(node_id, 0)`

**See also:**

`DT_PWMS_PERIOD_BY_IDX()`

**Parameters**

- `node_id` – node identifier for a node with a pwms property

**Returns**

the period cell value at index 0
DT_PWMS_FLAGS_BY_IDX(node_id, idx)
Get a PWM specifier's flags cell value at an index.
This macro expects PWM specifiers with cells named “flags”. If there is no “flags” cell in the
PWM specifier, zero is returned. Refer to the node's binding to check specifier cell names if
necessary.
This is equivalent to DT_PWMS_CELL_BY_IDX(node_id, idx, flags).

See also:

DT_PWMS_CELL_BY_IDX()

Parameters
• node_id – node identifier for a node with a pwms property
• idx – logical index into pwms property

Returns
the flags cell value at index “idx”, or zero if there is none

DT_PWMS_FLAGS_BY_NAME(node_id, name)
Get a PWM specifier's flags cell value by name.
This macro expects PWM specifiers with cells named “flags”. If there is no “flags” cell in the
PWM specifier, zero is returned. Refer to the node's binding to check specifier cell names if
necessary.
This is equivalent to DT_PWMS.Cell_BY_NAME(node_id, name, flags) if there is a flags cell,
but expands to zero if there is none.

See also:

DT_PWMS_CELL_BY_NAME()

Parameters
• node_id – node identifier for a node with a pwms property
• name – lowercase-and-underscores name of a pwms element as defined by the
node's pwm-names property

Returns
the flags cell value in the specifier at the named element, or zero if there is none

DT_PWMS_FLAGS(node_id)
Equivalent to DT_PWMS_FLAGS_BY_IDX(node_id, 0)

See also:

DT_PWMS_FLAGS_BY_IDX()
DT_INST_PWMS_CTLR_BY_IDX(inst, idx)
Get the node identifier for the PWM controller from a DT_DRV_COMPAT instance's pwms property at an index.

See also:
DT_PWMS_CTLR_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property

Returns
the node identifier for the PWM controller referenced at index “idx”

DT_INST_PWMS_CTLR_BY_NAME(inst, name)
Get the node identifier for the PWM controller from a DT_DRV_COMPAT instance’s pwms property by name.

See also:
DT_PWMS_CTLR_BY_NAME()

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property

Returns
the node identifier for the PWM controller in the named element

DT_INST_PWMS_CTLR(inst)
Equivalent to DT_INST_PWMS_CTLR_BY_IDX(inst, 0)

See also:
DT_PWMS_CTLR_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
the node identifier for the PWM controller at index 0 in the instance’s “pwms” property

DT_INST_PWMS_CELL_BY_IDX(inst, idx, cell)
Get a DT_DRV_COMPAT instance’s PWM specifier’s cell value at an index.

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property
• cell – lowercase-and-underscores cell name
Returns
the cell value at index “idx”

\[
\text{DT_INST_PWMS_CELL\_BY\_NAME}(\text{inst, name, cell})
\]
Get a DT\_DRV\_COMPAT instance’s PWM specifier’s cell value by name.

See also:

\[
\text{DT\_PWMS\_CELL\_BY\_NAME()}
\]

Parameters

- \text{inst} – DT\_DRV\_COMPAT instance number
- \text{name} – lowercase-and-underscores name of a pwms element as defined by the
  node’s pwm-names property
- \text{cell} – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

\[
\text{DT\_INST\_PWMS\_CELL}(\text{inst, cell})
\]
Equivalent to \[
\text{DT\_INST\_PWMS\_CELL\_BY\_IDX}(\text{inst, 0, cell})
\]

Parameters

- \text{inst} – DT\_DRV\_COMPAT instance number
- \text{cell} – lowercase-and-underscores cell name

Returns
the cell value at index 0

\[
\text{DT\_INST\_PWMS\_CHANNEL\_BY\_IDX}(\text{inst, idx})
\]
Equivalent to \[
\text{DT\_INST\_PWMS\_CELL\_BY\_IDX}(\text{inst, idx, channel})
\]

See also:

\[
\text{DT\_INST\_PWMS\_CELL\_BY\_IDX()}
\]

Parameters

- \text{inst} – DT\_DRV\_COMPAT instance number
- \text{idx} – logical index into pwms property

Returns
the channel cell value at index “idx”

\[
\text{DT\_INST\_PWMS\_CHANNEL\_BY\_NAME}(\text{inst, name})
\]
Equivalent to \[
\text{DT\_INST\_PWMS\_CELL\_BY\_NAME}(\text{inst, name, channel})
\]

See also:

\[
\text{DT\_INST\_PWMS\_CELL\_BY\_NAME()}
\]

Parameters

- \text{inst} – DT\_DRV\_COMPAT instance number
- \text{name} – lowercase-and-underscores name of a pwms element as defined by the
  node’s pwm-names property
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Returns
the channel cell value in the specifier at the named element

DT_INST_PWMS_CHANNEL(inst)
Equivalent to DT_INST_PWMS_CHANNEL_BY_IDX(inst, 0)

See also:
DT_INST_PWMS_CHANNEL_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
the channel cell value at index 0

DT_INST_PWMS_PERIOD_BY_IDX(inst, idx)
Equivalent to DT_INST_PWMS_CELL_BY_IDX(inst, idx, period)

See also:
DT_INST_PWMS_CELL_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – logical index into pwms property

Returns
the period cell value at index “idx”

DT_INST_PWMS_PERIOD_BY_NAME(inst, name)
Equivalent to DT_INST_PWMS_CELL_BY_NAME(inst, name, period)

See also:
DT_INST_PWMS_CELL_BY_NAME()

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a pwms element as defined by the
  node’s pwm-names property

Returns
the period cell value in the specifier at the named element

DT_INST_PWMS_PERIOD(inst)
Equivalent to DT_INST_PWMS_PERIOD_BY_IDX(inst, 0)

See also:
DT_INST_PWMS_PERIOD_BY_IDX()
Returns
the period cell value at index 0

\texttt{DT\_INST\_PWMS\_FLAGS\_BY\_IDX}(\textit{inst}, \textit{idx})
Equivalent to \texttt{DT\_INST\_PWMS\_CELL\_BY\_IDX}(\textit{inst}, \textit{idx}, \textit{flags})

See also:
\texttt{DT\_INST\_PWMS\_CELL\_BY\_IDX()}

Parameters
\begin{itemize}
\item \textit{inst} – DT\_DRV\_COMPAT instance number
\item \textit{idx} – logical index into pwms property
\end{itemize}

Returns
the flags cell value at index “\textit{idx}”, or zero if there is none

\texttt{DT\_INST\_PWMS\_FLAGS\_BY\_NAME}(\textit{inst}, \textit{name})
Equivalent to \texttt{DT\_INST\_PWMS\_CELL\_BY\_NAME}(\textit{inst}, \textit{name}, \textit{flags})

See also:
\texttt{DT\_INST\_PWMS\_CELL\_BY\_NAME()}

Parameters
\begin{itemize}
\item \textit{inst} – DT\_DRV\_COMPAT instance number
\item \textit{name} – lowercase-and-underscores name of a pwms element as defined by the
node’s pwm-names property
\end{itemize}

Returns
the flags cell value in the specifier at the named element, or zero if there is none

\texttt{DT\_INST\_PWMS\_FLAGS(\textit{inst})}
Equivalent to \texttt{DT\_INST\_PWMS\_FLAGS\_BY\_IDX}(\textit{inst}, 0)

See also:
\texttt{DT\_INST\_PWMS\_FLAGS\_BY\_IDX()}

Parameters
\begin{itemize}
\item \textit{inst} – DT\_DRV\_COMPAT instance number
\end{itemize}

Returns
the flags cell value at index 0, or zero if there is none

\textbf{Reset Controller}  These conveniences may be used for nodes which describe reset controllers and properties related to them.

\texttt{group devicetree-reset-controller}
Defines

**DT_RESET_CTLR_BY_IDX(node_id, idx)**

Get the node identifier for the controller phandle from a “resets” phandle-array property at an index.

Example devicetree fragment:

```plaintext
reset1: reset-controller@... { ... ;
reset2: reset-controller@... { ... ;
n: node {
    resets = <&reset1 10>, <&reset2 20>;
};
```

Example usage:

```
DT_RESET_CTLR_BY_IDX(DT_NODELABEL(n), 0)) // DT_NODELABEL(reset1)
DT_RESET_CTLR_BY_IDX(DT_NODELABEL(n), 1)) // DT_NODELABEL(reset2)
```

See also:

**DT_PHANDLE_BY_IDX()**

Parameters

- node_id – node identifier
- idx – logical index into “resets”

Returns

the node identifier for the reset controller referenced at index “idx”

**DT_RESET_CTLR(node_id)**

Equivalent to **DT_RESET_CTLR_BY_IDX(node_id, 0)**

See also:

**DT_RESET_CTLR_BY_IDX()**

Parameters

- node_id – node identifier

Returns

a node identifier for the reset controller at index 0 in “resets”

**DT_RESET_CTLR_BY_NAME(node_id, name)**

Get the node identifier for the controller phandle from a resets phandle-array property by name.

Example devicetree fragment:

```plaintext
reset1: reset-controller@... { ... ;
reset2: reset-controller@... { ... ;
n: node {
    resets = <&reset1 10>, <&reset2 20>;
};
```
reset-names = "alpha", "beta";

Example usage:

\[
\begin{align*}
\text{DT}_\text{RESET}_\text{CTRLR}_\text{BY}_\text{NAME}(\text{DT}_\text{NODELABEL}(n), \text{alpha}) & \text{ // DT}_\text{NODELABEL}(\text{reset1}) \\
\text{DT}_\text{RESET}_\text{CTRLR}_\text{BY}_\text{NAME}(\text{DT}_\text{NODELABEL}(n), \text{beta}) & \text{ // DT}_\text{NODELABEL}(\text{reset2}) \\
\end{align*}
\]

See also:

\textit{DT\_PHANDLE\_BY\_NAME()}

\textbf{Parameters}

- \textit{node\_id} – node identifier
- \textit{name} – lowercase-and-underscores name of a resets element as defined by the node's resets-names property

\textbf{Returns}

the node identifier for the reset controller referenced by name

\textbf{DT\_RESET\_CELL\_BY\_IDX(node\_id, idx, cell)}

Get a reset specifier's cell value at an index.

Example devicetree fragment:

\[
\begin{align*}
\text{reset: reset-controller@... } & \{ \\
\;&\text{ compatible = "vnd,reset";} \\
\;&\text{ #reset-cells = <1>;} \\
\};
\end{align*}
\]

\[
\begin{align*}
\text{n: node } & \{ \\
\;&\text{ resets = <&reset 10>;} \\
\};
\end{align*}
\]

Bindings fragment for the vnd,reset compatible:

\textbf{reset-cells:}

- \textit{id}

Example usage:

\[
\begin{align*}
\text{DT}_\text{RESET}_\text{CELL}_\text{BY}_\text{IDX}(\text{DT}_\text{NODELABEL}(n), 0, \text{id}) & \text{ // 10}
\end{align*}
\]

See also:

\textit{DT\_PHA\_BY\_IDX()}

\textbf{Parameters}

- \textit{node\_id} – node identifier for a node with a resets property
- \textit{idx} – logical index into resets property
- \textit{cell} – lowercase-and-underscores cell name

\textbf{Returns}

the cell value at index “idx”
DT_RESET_CELL_BY_NAME(node_id, name, cell)
Get a reset specifier's cell value by name.

Example devicetree fragment:

```dtb
reset: reset-controller@... {
    compatible = "vnd,reset";
    #reset-cells = <1>;
};

n: node {
    resets = <&reset 10>;
    reset-names = "alpha";
};
```

Bindings fragment for the vnd,reset compatible:

```dtb
reset-cells:
- id
```

Example usage:

```c
DT_RESET_CELL_BY_NAME(DT_NODELABEL(n), alpha, id) // 10
```

See also:

DT_PHA_BY_NAME()

Parameters

- node_id – node identifier for a node with a resets property
- name – lowercase-and-underscores name of a resets element as defined by the node's reset-names property
- cell – lowercase-and-underscores cell name

Returns

the cell value in the specifier at the named element

DT_RESET_CELL(node_id, cell)
Equivalent to DT_RESET_CELL_BY_IDX(node_id, 0, cell)

See also:

DT_RESET_CELL_BY_IDX()

Parameters

- node_id – node identifier for a node with a resets property
- cell – lowercase-and-underscores cell name

Returns

the cell value at index 0

DT_INST_RESET_CTLR_BY_IDX(inst, idx)
Get the node identifier for the controller phandle from a “resets” phandle-array property at an index.
See also:

`DT_RESET_CTLR_BY_IDX()`

**Parameters**
- inst – instance number
- idx – logical index into “resets”

**Returns**
the node identifier for the reset controller referenced at index “idx”

`DT_INST_RESET_CTLR(inst)`
Equivalent to `DT_INST_RESET_CTLR_BY_IDX(inst, 0)`

See also:

`DT_RESET_CTLR()`

**Parameters**
- inst – instance number

**Returns**
a node identifier for the reset controller at index 0 in “resets”

`DT_INST_RESET_CTLR_BY_NAME(inst, name)`
Get the node identifier for the controller phandle from a resets phandle-array property by name.

See also:

`DT_RESET_CTLR_BY_NAME()`

**Parameters**
- inst – instance number
- name – lowercase-and-underscores name of a resets element as defined by the node’s reset-names property

**Returns**
the node identifier for the reset controller referenced by the named element

`DT_INST_RESET_CELL_BY_IDX(inst, idx, cell)`
Get a DT_DRV_COMPAT instance’s reset specifier’s cell value at an index.

See also:

`DT_RESET_CELL_BY_IDX()`

**Parameters**
- inst – DT_DRV_COMPAT instance number
- idx – logical index into resets property
- cell – lowercase-and-underscores cell name

**Returns**
the cell value at index “idx”
DT_INST_RESET_CELL_BY_NAME(inst, name, cell)
Get a DT_DRV_COMPAT instance's reset specifier's cell value by name.

See also:
DT_RESET_CELL_BY_NAME()

Parameters
• inst – DT_DRV_COMPAT instance number
• name – lowercase-and-underscores name of a resets element as defined by the node's reset-names property
• cell – lowercase-and-underscores cell name

Returns
the cell value in the specifier at the named element

DT_INST_RESET_CELL(inst, cell)
Equivalent to DT_INST_RESET_CELL_BY_IDX(inst, 0, cell)

Parameters
• inst – DT_DRV_COMPAT instance number
• cell – lowercase-and-underscores cell name

Returns
the value of the cell inside the specifier at index 0

DT_RESET_ID_BY_IDX(node_id, idx)
Get a Reset Controller specifier's id cell at an index.

This macro only works for Reset Controller specifiers with cells named "id". Refer to the node's binding to check if necessary.

Example devicetree fragment:

```plaintext
reset: reset-controller@... {
  compatible = "vnd,reset";
  #reset-cells = <1>;
};

n: node {
  resets = <&reset 10>;
};
```

Bindings fragment for the vnd,reset compatible:

```plaintext
reset-cells:
- id
```

Example usage:

```plaintext
DT_RESET_ID_BY_IDX(DT_NODELABEL(n), 0) // 10
```

See also:
DT_PHA_BY_IDX()

Parameters
• node_id – node identifier
• idx – logical index into “resets”

Returns
the id cell value at index “idx”

DT_RESET_ID(node_id)
Equivalent to DT_RESET_ID_BY_IDX(node_id, 0)

See also:
DT_RESET_ID_BY_IDX()

Parameters
• node_id – node identifier

Returns
the id cell value at index 0

DT_INST_RESET_ID_BY_IDX(inst, idx)
Get a DT_DRV_COMPAT instance’s Reset Controller specifier’s id cell value at an index.

See also:
DT_RESET_ID_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number
  • idx – logical index into “resets”

Returns
the id cell value at index “idx”

DT_INST_RESET_ID(inst)
Equivalent to DT_INST_RESET_ID_BY_IDX(inst, 0)

See also:
DT_INST_RESET_ID_BY_IDX()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
the id cell value at index 0

SPI These conveniences may be used for nodes which describe either SPI controllers or devices, depending on the case.

group devicetree-spi
Defines

DT_SPI_HAS_CS_GPIOS(spi)
Does a SPI controller node have chip select GPIOs configured?
SPI bus controllers use the “cs-gpios” property for configuring chip select GPIOs. Its value is a phandle-array which specifies the chip select lines.

Example devicetree fragment:

```
spi1: spi@... {
  compatible = "vnd.spi";
  cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
             <&gpio2 20 GPIO_ACTIVE_LOW>;
};
spi2: spi@... {
  compatible = "vnd.spi";
};
```

Example usage:

```
DT_SPI_HAS_CS_GPIOS(DT_NODELABEL(spi1)) // 1
DT_SPI_HAS_CS_GPIOS(DT_NODELABEL(spi2)) // 0
```

Parameters
- `spi` – a SPI bus controller node identifier

Returns
1 if “spi” has a cs-gpios property, 0 otherwise

DT_SPI_NUM_CS_GPIOS(spi)
Number of chip select GPIOs in a SPI controller’s cs-gpios property.

Example devicetree fragment:

```
spi1: spi@... {
  compatible = "vnd.spi";
  cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
             <&gpio2 20 GPIO_ACTIVE_LOW>;
};
spi2: spi@... {
  compatible = "vnd.spi";
};
```

Example usage:

```
DT_SPI_NUM_CS_GPIOS(DT_NODELABEL(spi1)) // 2
DT_SPI_NUM_CS_GPIOS(DT_NODELABEL(spi2)) // 0
```

Parameters
- `spi` – a SPI bus controller node identifier

Returns
Logical length of spi’s cs-gpios property, or 0 if “spi” doesn’t have a cs-gpios property

5.2. Devicetree
**DT_SPI_DEV_HAS_CS_GPIOS(spi_dev)**

Does a SPI device have a chip select line configured? Example devicetree fragment:

```c
spi1: spi@... {
    compatible = "vnd.spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
              <&gpio2 20 GPIO_ACTIVE_LOW>;
    a: spi-dev-a@0 {
        reg = <0>;
    };
    b: spi-dev-b@1 {
        reg = <1>;
    };
};
spi2: spi@... {
    compatible = "vnd.spi";
    c: spi-dev-c@0 {
        reg = <0>;
    };
};
```

Example usage:

```c
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(a)) // 1
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(b)) // 1
DT_SPI_DEV_HAS_CS_GPIOS(DT_NODELABEL(c)) // 0
```

**Parameters**

- *spi_dev* – a SPI device node identifier

**Returns**

1 if *spi_dev*'s bus node `DT_BUS(spi_dev)` has a chip select pin at index `DT_REG_ADDR(spi_dev)`, 0 otherwise

**DT_SPI_DEV_CS_GPIOS_CTLR(spi_dev)**

Get a SPI device’s chip select GPIO controller’s node identifier. Example devicetree fragment:

```c
gpio1: gpio@... {
};
gpio2: gpio@... {
};
spi@... {
    compatible = "vnd.spi"
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
              <&gpio2 20 GPIO_ACTIVE_LOW>;
    a: spi-dev-a@0 {
        reg = <0>;
    };
    b: spi-dev-b@1 {
```

(continues on next page)
Example usage:

```c
DT_SPI_DEV_CS_GPIOS_CTLR(DT_NODELABEL(a)) // DT_NODELABEL(gpio1)
DT_SPI_DEV_CS_GPIOS_CTLR(DT_NODELABEL(b)) // DT_NODELABEL(gpio2)
```

**Parameters**

- `spi_dev` – a SPI device node identifier

**Returns**

node identifier for `spi_dev`'s chip select GPIO controller

**Deprecated:**

If used to obtain a device instance with `device_get_binding`, consider using `DEVICE_DT_GET(DT_SPI_DEV_CS_GPIOS_CTLR(node))`.

Example devicetree fragment:

```c
gpio1: gpio@... {
    label = "GPIO_1";
};

gpio2: gpio@... {
    label = "GPIO_2";
};

spi1: spi@... {
    compatible = "vnd_spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>, <&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};
```

Example usage:

```c
DT_SPI_DEV_CS_GPIOS_LABEL(DT_NODELABEL(a)) // "GPIO_1"
DT_SPI_DEV_CS_GPIOS_LABEL(DT_NODELABEL(b)) // "GPIO_2"
```

**Parameters**

- `spi_dev` – a SPI device node identifier

**Returns**

label property of `spi_dev`'s chip select GPIO controller
DT_SPI_DEV_CS_GPIOS_PIN(spi_dev)
Get a SPI device's chip select GPIO pin number.

It's an error if the GPIO specifier for spi_dev's entry in its bus node's cs-gpios property has no pin cell.

Example devicetree fragment:

```
spi: spi@... {
    compatible = "vnd.spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,
               <&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
}
```

Example usage:

```
DT_SPI_DEV_CS_GPIOS_PIN(DT_NODELABEL(a)) // 10
DT_SPI_DEV_CS_GPIOS_PIN(DT_NODELABEL(b)) // 20
```

**Parameters**

- spi_dev – a SPI device node identifier

**Returns**

pin number of spi_dev's chip select GPIO

DT_SPI_DEV_CS_GPIOS_FLAGS(spi_dev)
Get a SPI device's chip select GPIO flags.

Example devicetree fragment:

```
spi: spi@... {
    compatible = "vnd.spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };
}
```

Example usage:

```
DT_SPI_DEV_CS_GPIOS_FLAGS(DT_NODELABEL(a)) // GPIO_ACTIVE_LOW
```

If the GPIO specifier for spi_dev's entry in its bus node's cs-gpios property has no flags cell, this expands to zero.

**Parameters**

- spi_dev – a SPI device node identifier

**Returns**

flags value of spi_dev's chip select GPIO specifier, or zero if there is none
DT_INST_SPI_DEV_HAS_CS_GPIOS(inst)
   Equivalent to DT_SPI_DEV_HAS_CS_GPIOS(DT_DRV_INST(inst)).

See also:
DT_SPI_DEV_HAS_CS_GPIOS()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
1 if the instance's bus has a CS pin at index DT_INST_REG_ADDR(inst), 0 otherwise

DT_INST_SPI_DEV_CS_GPIOS_CTLR(inst)
   Get GPIO controller node identifier for a SPI device instance This is equivalent to
   DT_SPI_DEV_CS_GPIOS_CTLR(DT_DRV_INST(inst)).

See also:
DT_SPI_DEV_CS_GPIOS_CTLR()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
node identifier for instance's chip select GPIO controller

DT_INST_SPI_DEV_CS_GPIOS_LABEL(inst)
   Get GPIO controller name for a SPI device instance This is equivalent to
   DT_SPI_DEV_CS_GPIOS_LABEL(DT_DRV_INST(inst)).

Deprecated:
   If used to obtain a device instance with device_get_binding, consider using
   DEVICE_DT_GET(DT_INST_SPI_DEV_CS_GPIOS_CTLR(node)).

See also:
DT_SPI_DEV_CS_GPIOS_LABEL()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
label property of the instance’s chip select GPIO controller

DT_INST_SPI_DEV_CS_GPIOS_PIN(inst)
   Equivalent to DT_SPI_DEV_CS_GPIOS_PIN(DT_DRV_INST(inst)).

See also:
DT_SPI_DEV_CS_GPIOS_PIN()
• inst – DT_DRV_COMPAT instance number

Returns
pin number of the instance's chip select GPIO

DT_INST_SPI_DEV_CS_GPIOS_FLAGS(inst)
    DT_SPI_DEV_CS_GPIOS_FLAGS(DT_DRV_INST(inst)).

See also:
    DT_SPI_DEV_CS_GPIOS_FLAGS()

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
flags value of the instance's chip select GPIO specifier, or zero if there is none

Chosen nodes The special /chosen node contains properties whose values describe system-wide settings. The DT_CHOSEN() macro can be used to get a node identifier for a chosen node.

group devicetree-generic-chosen

Defines

DT_CHOSEN(prop)
    Get a node identifier for a /chosen node property.
    This is only valid to call if DT_HAS_CHOSEN(prop) is 1.

Parameters
• prop – lowercase-and-underscores property name for the /chosen node

Returns
    a node identifier for the chosen node property

DT_HAS_CHOSEN(prop)
    Test if the devicetree has a /chosen node.

Parameters
• prop – lowercase-and-underscores devicetree property

Returns
    1 if the chosen property exists and refers to a node, 0 otherwise

Zephyr-specific chosen nodes The following table documents some commonly used Zephyr-specific chosen nodes.

Sometimes, a chosen node's label property will be used to set the default value of a Kconfig option which in turn configures a hardware-specific device. This is usually for backwards compatibility in cases when the Kconfig option predates devicetree support in Zephyr. In other cases, there is no Kconfig option, and the devicetree node is used directly in the source code to select a device.
Table 5.1: Zephyr-specific chosen properties

<table>
<thead>
<tr>
<th>Property</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>zephyr, bt-c2h-uart</td>
<td>Selects the UART used for host communication in the bluetooth-hci-uart-sample</td>
</tr>
<tr>
<td>zephyr, bt-mon-uart</td>
<td>Sets UART device used for the Bluetooth monitor logging</td>
</tr>
<tr>
<td>zephyr, bt-uart</td>
<td>Sets UART device used by Bluetooth</td>
</tr>
<tr>
<td>zephyr, canbus</td>
<td>Sets the default CAN controller</td>
</tr>
<tr>
<td>zephyr, ccm</td>
<td>Core-Coupled Memory node on some STM32 SoCs</td>
</tr>
<tr>
<td>zephyr, code-partition</td>
<td>Flash partition that the Zephyr image's text section should be linked into</td>
</tr>
<tr>
<td>zephyr, console</td>
<td>Sets UART device used by console driver</td>
</tr>
<tr>
<td>zephyr, display</td>
<td>Sets the default display controller</td>
</tr>
<tr>
<td>zephyr, keyboard-scan</td>
<td>Sets the default keyboard scan controller</td>
</tr>
<tr>
<td>zephyr, ccm</td>
<td>Data Tightly Coupled Memory node on some Arm SoCs</td>
</tr>
<tr>
<td>zephyr, entropy</td>
<td>A device which can be used as a system-wide entropy source</td>
</tr>
<tr>
<td>zephyr, flash</td>
<td>A node whose reg is sometimes used to set the defaults for CONFIG_FLASH_BASE_ADDRESS and CONFIG_FLASH_SIZE</td>
</tr>
<tr>
<td>zephyr, flash-controller</td>
<td>The node corresponding to the flash controller device for the zephyr, flash node</td>
</tr>
<tr>
<td>zephyr, gdbstub-uart</td>
<td>Sets UART device used by the GDB stub subsystem</td>
</tr>
<tr>
<td>zephyr, ieee802154</td>
<td>Used by the networking subsystem to set the IEEE 802.15.4 device</td>
</tr>
<tr>
<td>zephyr, ipc</td>
<td>Used by the OpenAMP subsystem to specify the inter-process communication (IPC) device</td>
</tr>
<tr>
<td>zephyr, ipc_shm</td>
<td>A node whose reg is used by the OpenAMP subsystem to determine the base address and size of the shared memory (SHM) usable for interprocess-communication (IPC)</td>
</tr>
<tr>
<td>zephyr, itcm</td>
<td>Instruction Tightly Coupled Memory node on some Arm SoCs</td>
</tr>
<tr>
<td>zephyr, ocm</td>
<td>On-chip memory node on Xilinx Zynq-7000 and ZynqMP SoCs</td>
</tr>
<tr>
<td>zephyr, osdp-uart</td>
<td>Sets UART device used by OSDP subsystem</td>
</tr>
<tr>
<td>zephyr, ot-uart</td>
<td>Used by the OpenThread to specify UART device for Spinel protocol</td>
</tr>
<tr>
<td>zephyr, pcie-controller</td>
<td>The node corresponding to the PCIe Controller</td>
</tr>
<tr>
<td>zephyr, ppp-uart</td>
<td>Sets UART device used by PPP</td>
</tr>
<tr>
<td>zephyr, settings-partition</td>
<td>Fixed partition node. If defined this selects the partition used by the NVS and FCB settings backends.</td>
</tr>
<tr>
<td>zephyr, shell-uart</td>
<td>Sets UART device used by serial shell backend</td>
</tr>
<tr>
<td>zephyr, sram</td>
<td>A node whose reg sets the base address and size of SRAM memory available to the Zephyr image, used during linking</td>
</tr>
<tr>
<td>zephyr, tracing-uart</td>
<td>Sets UART device used by tracing subsystem</td>
</tr>
<tr>
<td>zephyr, uart-mcumgr</td>
<td>UART used for Device Management</td>
</tr>
<tr>
<td>zephyr, uart-pipe</td>
<td>Sets UART device used by serial pipe driver</td>
</tr>
<tr>
<td>zephyr, usb-device</td>
<td>USB device node. If defined and has a vbus-gpios property, these will be used by the USB subsystem to enable/disable VBUS</td>
</tr>
</tbody>
</table>

**Bindings index**

This page documents the available devicetree bindings. See Devicetree bindings for an introduction to the Zephyr bindings file format.

**Vendor index**  This section contains an index of hardware vendors. Click on a vendor's name to go to the list of bindings for that vendor.

- Generic or vendor-independent
- Altera Corp. (altr)
- AMS AG (ams)
- Analog Devices, Inc. (adi)
• Andes Technology Corporation (andestech)
• Apa Electronic Co., Ltd (apa)
• Aptina Imaging (aptina)
• Arduino (arduino)
• ARM Ltd. (arm)
• Asahi Kasei Corp. (asahi-kasei)
• ASMedia Technology Inc. (asmedia)
• ASPEED Technology Inc. (aspeed)
• Atmel Corporation (atmel)
• Avago Technologies (avago)
• Bosch Sensortec GmbH (bosch)
• Broadcom Corporation (brcm)
• Cadence Design Systems Inc. (cdns)
• Cypress Semiconductor Corporation (cypress)
• Espressif Systems (espressif)
• Fairchild Semiconductor (fcs)
• FocalTech Systems Co., Ltd (focaltech)
• Freescale Semiconductor (fsl)
• Future Technology Devices International Ltd. (ftdi)
• Gaisler (gaisler)
• GigaDevice Semiconductor (gd)
• GreeLed Electronic Ltd. (greeled)
• Guangzhou Aosong Electronic Co., Ltd. (aosong)
• Holtek Semiconductor, Inc. (holtek)
• Honeywell (honeywell)
• HOPERF Microelectronics Co. Ltd (hoperf)
• Hynitron (hynitron)
• ILI Technology Corporation (ILITEK) (ilitek)
• Imagination Technologies Ltd. (formerly MIPS Technologies Inc.) (mti)
• Infineon Technologies (infineon)
• Intel Corporation (intel)
• Intersil (isil)
• InvenSense Inc. (invensense)
• Inventek Systems (inventek)
• ITE Tech. Inc. (ite)
• JEDEC Solid State Technology Association (jedec)
• Kvaser (kvaser)
• Lattice Semiconductor (lattice)
• Linaro Limited (linaro)
- LiteX SoC builder (litex)
- Maxim Integrated Products (maxim)
- Measurement Specialties (meas)
- Micro:bit Educational Foundation (microbit)
- Microchip Technology Inc. (microchip)
- Microchip Technology Inc. (formerly Microsemi Corporation) (microsemi)
- Micron Technology Inc. (micron)
- Motorola, Inc. (motorola)
- Nordic Semiconductor (nordic)
- Nuclei System Technology (nuclei)
- Nuvoton Technology Corporation (nuvoton)
- NXP Semiconductors (nxp)
- OmniVision Technologies (ovti)
- open-isa.org (openisa)
- OpenCores.org (opencores)
- Panasonic Corporation (panasonic)
- Plantower Co., Ltd (plantower)
- QEMU, a generic and open source machine emulator and virtualizer (qemu)
- Qorvo, Inc (formerly Decawave) (decawave)
- Quectel Wireless Solutions Co., Ltd. (quectel)
- QuickLogic Corp. (quicklogic)
- Raspberry Pi Foundation (raspberrypi)
- Raydium Semiconductor Corp. (raydium)
- Renesas Electronics Corporation (renesas)
- Richtek Technology Corporation (richtek)
- RISC-V Foundation (riscv)
- ROCKTECH DISPLAYS LIMITED (rocktech)
- Seeed Technology Co., Ltd (seeed)
- SEGGER Microcontroller GmbH (segger)
- Semtech Corporation (semtech)
- Sensirion AG (sensirion)
- Sharp Corporation (sharp)
- Shenzhen Huiding Technology Co., Ltd. (goodix)
- Sierra Wireless (swir)
- SiFive, Inc. (sifive)
- Silicon Laboratories (silabs)
- SIMCom Wireless Solutions Co., LTD (simcom)
- Sitronix Technology Corporation (sitronix)
- Skyworks Solutions, Inc. (skyworks)
• Smart Battery System (sbs)
• Solomon Systech Limited (solomon)
• SparkFun Electronics (sparkfun)
• Standard Microsystems Corporation (smsc)
• StarFive Technology Co. Ltd. (starfive)
• STMicroelectronics (st)
• Synopsys, Inc. (snps)
• Synopsys, Inc. (formerly ARC International PLC) (arc)
• Telink Semiconductor (telink)
• Texas Instruments (ti)
• u-blox (u-blox)
• UltraChip Inc. (ultrachip)
• Vishay Intertechnology, Inc (vishay)
• Wistron NeWeb Corporation (wnc)
• WIZnet Co., Ltd. (wiznet)
• Worldsemi Co., Limited (worldsemi)
• Würth Elektronik GmbH. (we)
• Xen Hypervisor (xen)
• Xilinx (xlnx)
• Zephyr-specific binding (zephyr)
• Zhengzhou Winsen Electronics Technology Co., Ltd. (wisen)
• Unknown vendor

Bindings by vendor  This section contains available bindings, grouped by vendor. Within each group, bindings are listed by the “compatible” property they apply to, like this:

Vendor name (vendor prefix)

• <compatible-A>
• <compatible-B> (on <bus-name> bus)
• <compatible-C>
• ...

The text “(on <bus-name> bus)” appears when bindings may behave differently depending on the bus the node appears on. For example, this applies to some sensor device nodes, which may appear as children of either I2C or SPI bus nodes.

Generic or vendor-independent

• dtbinding_adafruit_feather_header
• dtbinding_arduino_header_r3
• dtbinding_arduino_mkr_header
• dtbinding_arduino_nano_header_r3
• dtbinding_atmel_xplained_header
• dtbinding_atmel_xplained_pro_header
• dtbinding_can_transceiver_gpio
• dtbinding_ethernet_phy
• dtbinding_fixed_clock
• dtbinding_fixed_factor_clock
• dtbinding_fixed_partitions
• dtbinding_fuel_gauge
• dtbinding_generic_fem_two_ctrl_pins
• dtbinding_gpio_i2c
• dtbinding_gpio_keys
• dtbinding_gpio_leds
• dtbinding_lm75
• dtbinding_lm77
• dtbinding_mikro_bus
• dtbinding_mmio_sram
• dtbinding_neorv32_cpu
• dtbinding_neorv32_gpio
• dtbinding_neorv32_machine_timer
• dtbinding_neorv32_trng
• dtbinding_neorv32_uart
• dtbinding_ns16550
• dtbinding_particle_gen3_header
• dtbinding_pci_host_ecam_generic
• dtbinding_power_domain
• dtbinding_power_domain_gpio
• dtbinding_pwm_leds
• dtbinding_regulator_fixed
• dtbinding_sample_controller
• dtbinding_shared_irq
• dtbinding_soc_nv_flash
• dtbinding_syscon
• dtbinding_usb_audio
• dtbinding_usb_audio_hp
• dtbinding_usb_audio_hs
• dtbinding_usb_audio_mic
• dtbinding_usb_c_connector
• dtbinding_usb_nop_xceiv
• dtbinding_vexriscv_intc0
• dtbinding_voltage_divider
Altera Corp. (altr)
- dtbinding_altr_jtag_uart
- dtbinding_altr_msgdma
- dtbinding_altr_nios2_i2c
- dtbinding_altr_nios2_qspi
- dtbinding_altr_nios2_qspi_nor
- dtbinding_altr_nios2f

AMS AG (ams)
- dtbinding_ams_as6212
- dtbinding_ams_ccs811
- dtbinding_ams_ens210
- dtbinding_ams_iaqcore

Analog Devices, Inc. (adi)
- dtbinding_adi_adt7420
- dtbinding_adi_adxl345_spi
- dtbinding_adi_adxl345_i2c
- dtbinding_adi_adxl362
- dtbinding_adi_adxl372_spi
- dtbinding_adi_adxl372_i2c

Andes Technology Corporation (andestech)
- dtbinding_andestech_atcgpio100
- dtbinding_andestech_atciic100
- dtbinding_andestech_aticpit100
- dtbinding_andestech_atcspi200
- dtbinding_andestech_machine_timer

Apa Electronic Co., Ltd (apa)
- dtbinding_apa_apa102

Aptina Imaging (aptina)
- dtbinding_aptina_mt9m114

Arduino (arduino)
- dtbinding_arduino_uno_adc
ARM Ltd. (arm)

- dtbinding_arm_armv6m_mpu
- dtbinding_arm_armv6m_systick
- dtbinding_arm_armv7m_itm
- dtbinding_arm_armv7m_mpu
- dtbinding_arm_armv7m_systick
- dtbinding_arm_armv8_timer
- dtbinding_arm_armv8.1m_mpu
- dtbinding_arm_armv8.1m_systick
- dtbinding_arm_armv8m_itm
- dtbinding_arm_armv8m_mpu
- dtbinding_arm_armv8m_systick
- dtbinding_arm_beetle_syscon
- dtbinding_arm_cmsdk_dtimer
- dtbinding_arm_cmsdk_gpio
- dtbinding_arm_cmsdk_timer
- dtbinding_arm_cmsdk_uart
- dtbinding_arm_cmsdk_watchdog
- dtbinding_arm_cortex_a53
- dtbinding_arm_cortex_a72
- dtbinding_arm_cortex_m0
- dtbinding_arm_cortex_m0+
- dtbinding_arm_cortex_m1
- dtbinding_arm_cortex_m23
- dtbinding_arm_cortex_m3
- dtbinding_arm_cortex_m33
- dtbinding_arm_cortex_m33f
- dtbinding_arm_cortex_m4
- dtbinding_arm_cortex_m4f
- dtbinding_arm_cortex_m7
- dtbinding_arm_cortex_r4
- dtbinding_arm_cortex_r4f
- dtbinding_arm_cortex_r5
- dtbinding_arm_cortex_r52
- dtbinding_arm_cortex_r5f
- dtbinding_arm_cortex_r7
- dtbinding_arm_cortex_r82
- dtbinding_arm_cryptocell_310
- dtbinding_arm_cryptocell_312
• dtbinding_arm_dma_pl330
• dtbinding_arm_dtc
• dtbinding_arm_ethos_u
• dtbinding_arm_gic
• dtbinding_arm_gic_v3_its
• dtbinding_arm_itcm
• dtbinding_arm_mhu
• dtbinding_arm_mps2_fpgaio_gpio
• dtbinding_arm_mps3_fpgaio_gpio
• dtbinding_arm_pl011
• dtbinding_arm_pl022
• dtbinding_arm_psci_0_2
• dtbinding_arm_scc
• dtbinding_arm_v6m_nvic
• dtbinding_arm_v7m_nvic
• dtbinding_arm_v8.1m_nvic
• dtbinding_arm_v8m_nvic
• dtbinding_arm_versatile_i2c

Asahi Kasei Corp. (asahi-kasei)
• dtbinding_asahi_kasei_ak8975

ASMedia Technology Inc. (asmedia)
• dtbinding_asmedia_asm2364

ASPEED Technology Inc. (aspeed)
• dtbinding_aspeed_ast10x0_clock

Atmel Corporation (atmel)
• dtbinding_atmel_at24
• dtbinding_atmel_24mac402
• dtbinding_atmel_at25
• dtbinding_atmel_at45
• dtbinding_atmel_ataes132a
• dtbinding_atmel_rf2xx
• dtbinding_atmel_sam_afec
• dtbinding_atmel_sam_can
• dtbinding_atmel_sam_dac
• dtbinding_atmel_sam_flash_controller
- dtbinding_atmel_sam_gmac
- dtbinding_atmel_sam_gpio
- dtbinding_atmel_sam_i2c_twi
- dtbinding_atmel_sam_i2c_twihs
- dtbinding_atmel_sam_i2c_twim
- dtbinding_atmel_sam_mdio
- dtbinding_atmel_sam_pinctrl
- dtbinding_atmel_sam_pwm
- dtbinding_atmel_sam_rstc
- dtbinding_atmel_sam_smc
- dtbinding_atmel_sam_spi
- dtbinding_atmel_sam_ssc
- dtbinding_atmel_sam_tc
- dtbinding_atmel_sam_tc_qdec
- dtbinding_atmel_sam_trng
- dtbinding_atmel_sam_uart
- dtbinding_atmel_sam_usart
- dtbinding_atmel_sam_usbc
- dtbinding_atmel_sam_usbhs
- dtbinding_atmel_sam_watchdog
- dtbinding_atmel_sam_xdma
- dtbinding_atmel_sam0_adc
- dtbinding_atmel_sam0_dac
- dtbinding_atmel_sam0_dmac
- dtbinding_atmel_sam0_eic
- dtbinding_atmel_sam0_gmac
- dtbinding_atmel_sam0_gpio
- dtbinding_atmel_sam0_i2c
- dtbinding_atmel_sam0_id
- dtbinding_atmel_sam0_nvmctrl
- dtbinding_atmel_sam0_pinctrl
- dtbinding_atmel_sam0_pinmux
- dtbinding_atmel_sam0_rtc
- dtbinding_atmel_sam0_sercom
- dtbinding_atmel_sam0_spi
- dtbinding_atmel_sam0_tc32
- dtbinding_atmel_sam0_tcc_pwm
- dtbinding_atmel_sam0_uart
- dtbinding_atmel_sam0_usb

5.2. Devicetree
• dtbinding_atmel_sam0_watchdog
• dtbinding_atmel_sam4l_flashcalw_controller
• dtbinding_atmel_sam4l_gpio
• dtbinding_atmel_sam4l_uid
• dtbinding_atmel_samc2x_gclk
• dtbinding_atmel_samc2x_mclk
• dtbinding_atmel_samd2x_gclk
• dtbinding_atmel_samd2x_pm
• dtbinding_atmel_samd5x_gclk
• dtbinding_atmel_samd5x_mclk
• dtbinding_atmel_saml2x_gclk
• dtbinding_atmel_saml2x_mclk
• dtbinding_atmel_winc1500

Avago Technologies (avago)
• dtbinding_avago_apds9960

Bosch Sensortec GmbH (bosch)
• dtbinding_bosch_bma280
• dtbinding_bosch_bmc150_magn
• dtbinding_bosch_bme280_spi
• dtbinding_bosch_bme280_i2c
• dtbinding_bosch_bme680_spi
• dtbinding_bosch_bme680_i2c
• dtbinding_bosch_bmg160
• dtbinding_bosch_bmi160_i2c
• dtbinding_bosch_bmi160_spi
• dtbinding_bosch_bmi270_i2c
• dtbinding_bosch_bmi270
• dtbinding_bosch_bmi270_spi
• dtbinding_bosch_bmm150
• dtbinding_bosch_bmp388_i2c
• dtbinding_bosch_bmp388_spi
• dtbinding_bosch_m_can_base

Broadcom Corporation (brcm)
• dtbinding_brcm_iproc_pax_dma_v1
• dtbinding_brcm_iproc_pax_dma_v2
• dtbinding_brcm_iproc_pcie_ep
**Cadence Design Systems Inc. (cdns)**
- dtbinding_cdns_qspi_nor
- dtbinding_cdns_tensilica_xtensa_lx4
- dtbinding_cdns_tensilica_xtensa_lx6
- dtbinding_cdns_tensilica_xtensa_lx7
- dtbinding_cdns_xtensa_core_intc

**Cypress Semiconductor Corporation (cypress)**
- dtbinding_cypress_cy8c95xx_gpio
- dtbinding_cypress_cy8c95xx_gpio_port
- dtbinding_cypress_psoc6_flash_controller
- dtbinding_cypress_psoc6_gpio
- dtbinding_cypress_psoc6_hsiom
- dtbinding_cypress_psoc6_intmux
- dtbinding_cypress_psoc6_intmux_ch
- dtbinding_cypress_psoc6_pinctrl
- dtbinding_cypress_psoc6_spi
- dtbinding_cypress_psoc6_uart
- dtbinding_cypress_psoc6_uid

**Espressif Systems (espressif)**
- dtbinding_espressif_esp_at
- dtbinding_espressif_esp32_eth
- dtbinding_espressif_esp32_flash_controller
- dtbinding_espressif_esp32_gpio
- dtbinding_espressif_esp32_i2c
- dtbinding_espressif_esp32_intc
- dtbinding_espressif_esp32_ipm
- dtbinding_espressif_esp32_ledc
- dtbinding_espressif_esp32_mcpwm
- dtbinding_espressif_esp32_mdio
- dtbinding_espressif_esp32_pcnt
- dtbinding_espressif_esp32_pinctrl
- dtbinding_espressif_esp32_rtc
- dtbinding_espressif_esp32_rtc_timer
- dtbinding_espressif_esp32_spi
- dtbinding_espressif_esp32_systimer
- dtbinding_espressif_esp32_timer
- dtbinding_espressif_esp32_trng
• dtbinding_espressif_esp32_twai
• dtbinding_espressif_esp32_uart
• dtbinding_espressif_esp32_usb_serial
• dtbinding_espressif_esp32_watchdog
• dtbinding_espressif_esp32_wifi
• dtbinding_espressif_riscv

Fairchild Semiconductor (fcs)
• dtbinding_fcs_fxl6408

FocalTech Systems Co., Ltd (focaltech)
• dtbinding_focaltech_ft5336

Freescale Semiconductor (fsl)
• dtbinding_fsl_imx21_i2c
• dtbinding_fsl_imx27_pwm

Future Technology Devices International Ltd. (ftdi)
• dtbinding_ftdi_ft800

Gaisler (gaisler)
• dtbinding_gaisler_apbuart
• dtbinding_gaisler_gptimer
• dtbinding_gaisler_irqmp
• dtbinding_gaisler_leon3

GigaDevice Semiconductor (gd)
• dtbinding_bd_gd32_adc
• dtbinding_bd_gd32_afio
• dtbinding_bd_gd32_cctl
• dtbinding_bd_gd32_dac
• dtbinding_bd_gd32_dma
• dtbinding_bd_gd32_exti
• dtbinding_bd_gd32_flash_controller
• dtbinding_bd_gd32_fwgdgt
• dtbinding_bd_gd32_gpio
• dtbinding_bd_gd32_i2c
• dtbinding_bd_gd32_nv_flash_v1
• dtbinding_bd_gd32_nv_flash_v2
• dtbinding_bd_gd32_nv_flash_v3
- `dtbinding_gd_gd32_pinctrlAf`
- `dtbinding_gd_gd32_pinctrlAfio`
- `dtbinding_gd_gd32_pwm`
- `dtbinding_gd_gd32_rctl`
- `dtbinding_gd_gd32_rcu`
- `dtbinding_gd_gd32_spi`
- `dtbinding_gd_gd32_syscfg`
- `dtbinding_gd_gd32_timer`
- `dtbinding_gd_gd32_uart`
- `dtbinding_gd_gd32_wwdgt`

**GreeLed Electronic Ltd. (greeled)**
- `dtbinding_greeled_lpd8803`
- `dtbinding_greeled_lpd8806`

**Guangzhou Aosong Electronic Co., Ltd. (aosong)**
- `dtbinding_aosong_dht`

**Holtek Semiconductor, Inc. (holtek)**
- `dtbinding_holtek_ht16k33`
- `dtbinding_holtek_ht16k33_keysca`

**Honeywell (honeywell)**
- `dtbinding_honeywell_hmc5883l`
- `dtbinding_honeywell_mpr`
- `dtbinding_honeywell_sm351lt`

**HOPERF Microelectronics Co. Ltd (hoperf)**
- `dtbinding_hoperf_hp206c`
- `dtbinding_hoperf_th02`

**Hynitron (hynitron)**
- `dtbinding_hynitron_cst816s`

**ILI Technology Corporation (ILITEK) (ilitek)**
- `dtbinding_ilitek_ili9340`
- `dtbinding_ilitek_ili9341`
- `dtbinding_ilitek_ili9488`
Imagination Technologies Ltd. (formerly MIPS Technologies Inc.) (mti)
  • dbinding_mti_cpu_intc

Infineon Technologies (infineon)
  • dbinding_infineon_dps310
  • dbinding_infineon_xmc4xxx_flash_controller
  • dbinding_infineon_xmc4xxx_gpio
  • dbinding_infineon_xmc4xxx_nv_flash
  • dbinding_infineon_xmc4xxx_pinctrl
  • dbinding_infineon_xmc4xxx_uart

Intel Corporation (intel)
  • dbinding_intel_ace_art_counter
  • dbinding_intel_ace_intc
  • dbinding_intel_ace_RTC_counter
  • dbinding_intel_ace_timestamp
  • dbinding_intel_adsp_dfpmcch
  • dbinding_intel_adsp_dfpmccu
  • dbinding_intel_adsp_gpdma
  • dbinding_intel_adsp_hda_host_in
  • dbinding_intel_adsp_hda_host_out
  • dbinding_intel_adsp_hda_link_in
  • dbinding_intel_adsp_hda_link_out
  • dbinding_intel_adsp_host_ipc
  • dbinding_intel_adsp_idc
  • dbinding_intel_adsp_imr
  • dbinding_intel_adsp_mailbox
  • dbinding_intel_adsp_mem_window
  • dbinding_intel_adsp_mtl_tlb
  • dbinding_intel_adsp_power_domain
  • dbinding_intel_adsp_sha
  • dbinding_intel_adsp_shim_clkctl
  • dbinding_intel_adsp_timer
  • dbinding_intel_adsp_tlb
  • dbinding_intel_agilex_clock
  • dbinding_intel_alh_dai
  • dbinding_intel_apollo_lake
  • dbinding_intel_atom
  • dbinding_intel_cavs_i2s
• dtbinding_intel_cavs_intc
• dtbinding_intel_dai_dmic
• dtbinding_intel_e1000
• dtbinding_intel_elkhart_lake
• dtbinding_intel_gna
• dtbinding_intel_gpio
• dtbinding_intel_hpet
• dtbinding_intel_ibecc
• dtbinding_intel_ioapic
• dtbinding_intel_lakemont
• dtbinding_intel_multiboot_framebuffer
• dtbinding_intel_pcie
• dtbinding_intel_raptor_lake
• dtbinding_intel_ssp_dai
• dtbinding_intel_ssp_sspbase
• dtbinding_intel_vt_d
• dtbinding_intel_x86

Intersil (isil)
• dtbinding_isil_isl29035

InvenSense Inc. (invensense)
• dtbinding_invensense_icm42605
• dtbinding_invensense_icm42670
• dtbinding_invensense_mpu6050
• dtbinding_invensense_mpu9250

Inventek Systems (inventek)
• dtbinding_inventek_eswifi
• dtbinding_inventek_eswifi_uart

ITE Tech. Inc. (ite)
• dtbinding_ite_enhance_i2c
• dtbinding_ite_it8xxx2_adc
• dtbinding_ite_it8xxx2_bbram
• dtbinding_ite_it8xxx2_flash_controller
• dtbinding_ite_it8xxx2_gpio
• dtbinding_ite_it8xxx2_i2c
• dtbinding_ite_it8xxx2_ilm

5.2. Devicetree
• dtbinding_ite_it8xxx2_intc
• dtbinding_ite_it8xxx2_kscan
• dtbinding_ite_it8xxx2_peci
• dtbinding_ite_it8xxx2_pinctrl
• dtbinding_ite_it8xxx2_pinctrl_func
• dtbinding_ite_it8xxx2_pwm
• dtbinding_ite_it8xxx2_pwmprs
• dtbinding_ite_it8xxx2_sspi
• dtbinding_ite_it8xxx2_tach
• dtbinding_ite_it8xxx2_timer
• dtbinding_ite_it8xxx2_uart
• dtbinding_ite_it8xxx2_usbpd
• dtbinding_ite_it8xxx2_vcmp
• dtbinding_ite_it8xxx2_watchdog
• dtbinding_ite_it8xxx2_wuc
• dtbinding_ite_it8xxx2_wuc_map
• dtbinding_ite_riscv_ite

JEDEC Solid State Technology Association (jedec)
• dtbinding_jedec_spi_nor

Kvaser (kvaser)
• dtbinding_kvaser_pcican

Lattice Semiconductor (lattice)
• dtbinding_lattice_ice40_fpga

Linaro Limited (linaro)
• dtbinding_linaro_96b_lsocn_1v8
• dtbinding_linaro_96b_lsocn_3v3

LiteX SoC builder (litex)
• dtbinding_litex_clk
• dtbinding_litex_clkout
• dtbinding_litex_dna0
• dtbinding_litex_eth0
• dtbinding_litex_gpio
• dtbinding_litex_i2c
• dtbinding_litex_i2s
• dtbinding_litex_prbs
• dtbinding_litex_pwm
• dtbinding_litex_spi
• dtbinding_litex_timer0
• dtbinding_litex_uart0

Maxim Integrated Products (maxim)
• dtbinding_maxim_ds18b20
• dtbinding_maxim_ds2484
• dtbinding_maxim_ds2485
• dtbinding_maxim_ds3231
• dtbinding_maxim_max17055
• dtbinding_maxim_max17262
• dtbinding_maxim_max30101
• dtbinding_maxim_max31875
• dtbinding_maxim_max44009
• dtbinding_maxim_max6675
• dtbinding_maxim_max7219

Measurement Specialties (meas)
• dtbinding_meas_ms5607_spi
• dtbinding_meas_ms5607_i2c
• dtbinding_meas_ms5837

Micro:bit Educational Foundation (microbit)
• dtbinding_microbit_edge_connector

Microchip Technology Inc. (microchip)
• dtbinding_microchip_cap1203
• dtbinding_microchip_enc28j60
• dtbinding_microchip_enc424j600
• dtbinding_microchip_ksz8794
• dtbinding_microchip_ksz8863
• dtbinding_microchip_mcp230xx
• dtbinding_microchip_mcp23s17
• dtbinding_microchip_mcp23sxx
• dtbinding_microchip_mcp2515
• dtbinding_microchip_mcp3204
• dtbinding_microchip_mcp3208
• dtbinding_microchip_mcp4725
- dtbinding_microchip_mcp4728
- dtbinding_microchip_mcp7940n
- dtbinding_microchip_mcp9808
- dtbinding_microchip_mpfs_gpio
- dtbinding_microchip_mpfs_qspi
- dtbinding_microchip_xec_adc
- dtbinding_microchip_xec_adc_v2
- dtbinding_microchip_xec_bbram
- dtbinding_microchip_xec_ecia
- dtbinding_microchip_xec_ecia_girq
- dtbinding_microchip_xec ecs
- dtbinding_microchip_xec_eeprom
- dtbinding_microchip_xec_espi
- dtbinding_microchip_xec_espi_host_dev
- dtbinding_microchip_xec_espi_saf
- dtbinding_microchip_xec_espi_saf_v2
- dtbinding_microchip_xec_espi_v2
- dtbinding_microchip_xec_espi_vw_routing
- dtbinding_microchip_xec_gpio
- dtbinding_microchip_xec_gpio_v2
- dtbinding_microchip_xec_i2c
- dtbinding_microchip_xec_i2c_v2
- dtbinding_microchip_xec_kscan
- dtbinding_microchip_xec_pcr
- dtbinding_microchip_xec_peci
- dtbinding_microchip_xec_peci
- dtbinding_microchip_xec_pinctrl
- dtbinding_microchip_xec_pinmux
- dtbinding_microchip_xec_ps2
- dtbinding_microchip_xec_pwm
- dtbinding_microchip_xec_qmspi
- dtbinding_microchip_xec_qmspi_full_duplex
- dtbinding_microchip_xec_qmspi_ldma
- dtbinding_microchip_xec_rtos_timer
- dtbinding_microchip_xec_tach
- dtbinding_microchip_xec_timer
- dtbinding_microchip_xec_uart
- dtbinding_microchip_xec_watchdog
Microchip Technology Inc. (formerly Microsemi Corporation) (microsemi)
  • dtbinding_microsemi_coreuart

Micron Technology Inc. (micron)
  • dtbinding_micron_mt25qu02g

Motorola, Inc. (motorola)
  • dtbinding_motorola_mc146818

Nordic Semiconductor (nordic)
  • dtbinding_nordic_mbox_nrf_ipc
  • dtbinding_nordic_npm6001
  • dtbinding_nordic_npm6001_gpio
  • dtbinding_nordic_npm6001_wdt
  • dtbinding_nordic_nrf_acl
  • dtbinding_nordic_nrf_adc
  • dtbinding_nordic_nrf_bprot
  • dtbinding_nordic_nrf_cc310
  • dtbinding_nordic_nrf_cc312
  • dtbinding_nordic_nrf_ccm
  • dtbinding_nordic_nrf_clock
  • dtbinding_nordic_nrf_comp
  • dtbinding_nordic_nrf_ctrlapperi
  • dtbinding_nordic_nrf_dcnf
  • dtbinding_nordic_nrf_dppic
  • dtbinding_nordic_nrf_ecb
  • dtbinding_nordic_nrf_egu
  • dtbinding_nordic_nrf_ficr
  • dtbinding_nordic_nrf_gpio
  • dtbinding_nordic_nrf_gpio_forwarder
  • dtbinding_nordic_nrf_gpiote
  • dtbinding_nordic_nrf_i2s
  • dtbinding_nordic_nrf_ieee802154
  • dtbinding_nordic_nrf_ipc
  • dtbinding_nordic_nrf_kmu
  • dtbinding_nordic_nrf_led_matrix
  • dtbinding_nordic_nrf_lpcmp
  • dtbinding_nordic_nrf_mpu
  • dtbinding_nordic_nrf_mutex
• dtbinding_nordic_nrf_mwu
• dtbinding_nordic_nrf_nfct
• dtbinding_nordic_nrf_oscillators
• dtbinding_nordic_nrf_pdm
• dtbinding_nordic_nrf_pinctrl
• dtbinding_nordic_nrf_power
• dtbinding_nordic_nrf_ppi
• dtbinding_nordic_nrf_pwm
• dtbinding_nordic_nrf_qdec
• dtbinding_nordic_nrf_qspi
• dtbinding_nordic_nrf_radio
• dtbinding_nordic_nrf_regulators
• dtbinding_nordic_nrf_reset
• dtbinding_nordic_nrf_rng
• dtbinding_nordic_nrf_RTC
• dtbinding_nordic_nrf_saadc
• dtbinding_nordic_nrf_spi
• dtbinding_nordic_nrf_spim
• dtbinding_nordic_nrf_spis
• dtbinding_nordic_nrf_spu
• dtbinding_nordic_nrf_sw_pwm
• dtbinding_nordic_nrf_sw
• dtbinding_nordic_nrf_swi
• dtbinding_nordic_nrf_temp
• dtbinding_nordic_nrf_timer
• dtbinding_nordic_nrf_twi
• dtbinding_nordic_nrf_twim
• dtbinding_nordic_nrf_twis
• dtbinding_nordic_nrf_uart
• dtbinding_nordic_nrf_uarte
• dtbinding_nordic_nrf_uicr
• dtbinding_nordic_nrf_usbd
• dtbinding_nordic_nrf_usbreg
• dtbinding_nordic_nrf_vmc
• dtbinding_nordic_nrf_wdt
• dtbinding_nordic_nrf21540_fem
• dtbinding_nordic_nrf21540_fem_spi
• dtbinding_nordic_nrf51_flash_controller
• dtbinding_nordic_nrf52_flash_controller
• dtbinding_nordic_nrf53_flash_controller
• dtbinding_nordic_nrf91_flash_controller
• dtbinding_nordic_qspi_nor

Nuclei System Technology (nuclei)
• dtbinding_nuclei_bumblebee
• dtbinding_nuclei_eclic
• dtbinding_nuclei_systimer

Nuvoton Technology Corporation (nuvoton)
• dtbinding_nuvoton_adc_cmp
• dtbinding_nuvoton_nct38xx_gpio
• dtbinding_nuvoton_nct38xx_gpio_alert
• dtbinding_nuvoton_nct38xx_gpio_port
• dtbinding_nuvoton_npcx_adc
• dtbinding_nuvoton_npcx_bbram
• dtbinding_nuvoton_npcx_booter_variant
• dtbinding_nuvoton_npcx_espi
• dtbinding_nuvoton_npcx_espi_vw_conf
• dtbinding_nuvoton_npcx_gpio
• dtbinding_nuvoton_npcx_host_sub
• dtbinding_nuvoton_npcx_host_uart
• dtbinding_nuvoton_npcx_i2c_ctrl
• dtbinding_nuvoton_npcx_i2c_port
• dtbinding_nuvoton_npcx_itim_timer
• dtbinding_nuvoton_npcx_kscan
• dtbinding_nuvoton_npcx_leakage_io
• dtbinding_nuvoton_npcx_lvolctrl_conf
• dtbinding_nuvoton_npcx_miwu
• dtbinding_nuvoton_npcx_miwu_int_map
• dtbinding_nuvoton_npcx_miwu_wui_map
• dtbinding_nuvoton_npcx_pcc
• dtbinding_nuvoton_npcx_peci
• dtbinding_nuvoton_npcx_pinctrl
• dtbinding_nuvoton_npcx_pinctrl_conf
• dtbinding_nuvoton_npcx_pinctrl_def
• dtbinding_nuvoton_npcx_power_psl
• dtbinding_nuvoton_npcx_ps2_channel
• dtbinding_nuvoton_npcx_ps2_ctrl
• dtbinding_nuvoton_npcx_pwm

5.2. Devicetree
• dtbinding_nuvoton_npcx_scf
• dtbinding_nuvoton_npcx_soc_id
• dtbinding_nuvoton_npcx_spi_fiu
• dtbinding_nuvoton_npcx_tach
• dtbinding_nuvoton_npcx_uart
• dtbinding_nuvoton_npcx_watchdog
• dtbinding_nuvoton_numicro_uart

**NXP Semiconductors (nxp)**
• dtbinding_nxp_css_v2
• dtbinding_nxp_flexpwm
• dtbinding_nxp_fxas21002_spi
• dtbinding_nxp_fxas21002_i2c
• dtbinding_nxp_fxos8700_spi
• dtbinding_nxp_fxos8700_i2c
• dtbinding_nxp_gpt_hw_timer
• dtbinding_nxp_iap_fmc11
• dtbinding_nxp_iap_fmc54
• dtbinding_nxp_iap_fmc55
• dtbinding_nxp_iap_fmc553
• dtbinding_nxp_imx_anatop
• dtbinding_nxp_imx_caam
• dtbinding_nxp_imx_ccm
• dtbinding_nxp_imx_ccm_rev2
• dtbinding_nxp_imx_csi
• dtbinding_nxp_imx_dtc
• dtbinding_nxp_imx_elcdif
• dtbinding_nxp_imx_epit
• dtbinding_nxp_imx_flexspi
• dtbinding_nxp_imx_flexspi_hyperflash
• dtbinding_nxp_imx_flexspi_hyperram
• dtbinding_nxp_imx_flexspi_mx25um51345g
• dtbinding_nxp_imx_flexspi_nor
• dtbinding_nxp_imx_gpio
• dtbinding_nxp_imx_gpr
• dtbinding_nxp_imx_gpt
• dtbinding_nxp_imx_iomuxc
• dtbinding_nxp_imx_itcm
• dtbinding_nxp_imx_iuart
- dtbinding_nxp_imx_lpi2c
- dtbinding_nxp_imx_lpspi
- dtbinding_nxp_imx_mipi_dsi
- dtbinding_nxp_imx_mu
- dtbinding_nxp_imx_pwm
- dtbinding_nxp_imx_qtmr
- dtbinding_nxp_imx_semc
- dtbinding_nxp_imx_snvs_rtc
- dtbinding_nxp_imx_tmr
- dtbinding_nxp_imx_uart
- dtbinding_nxp_imx_usdhc
- dtbinding_nxp_imx_wdog
- dtbinding_nxp_imx7d_pinctrl
- dtbinding_nxp_imx8m_pinctrl
- dtbinding_nxp_imx8mp_pinctrl
- dtbinding_nxp_kinetis_acmp
- dtbinding_nxp_kinetis_adc12
- dtbinding_nxp_kinetis_adc16
- dtbinding_nxp_kinetis_dac
- dtbinding_nxp_kinetis_dac32
- dtbinding_nxp_kinetis_dspi
- dtbinding_nxp_kinetis_ethernet
- dtbinding_nxp_kinetis_flexcan
- dtbinding_nxp_kinetis_ftfa
- dtbinding_nxp_kinetis_ftfe
- dtbinding_nxp_kinetis_ftfl
- dtbinding_nxp_kinetis_ftm
- dtbinding_nxp_kinetis_ftm_pwm
- dtbinding_nxp_kinetis_gpio
- dtbinding_nxp_kinetis_i2c
- dtbinding_nxp_kinetis_ke1xf_sim
- dtbinding_nxp_kinetis_lpcsi
- dtbinding_nxp_kinetis_lptmr
- dtbinding_nxp_kinetis_lpuart
- dtbinding_nxp_kinetis_mcg
- dtbinding_nxp_kinetis_pcc
- dtbinding_nxp_kinetis_pinctrl
- dtbinding_nxp_kinetis_pinmux
- dtbinding_nxp_kinetis_pit
• dtbinding_nxp_kinetis_ptp
• dtbinding_nxp_kinetis_pwt
• dtbinding_nxp_kinetis_rng
• dtbinding_nxp_kinetis_rtc
• dtbinding_nxp_kinetis_scg
• dtbinding_nxp_kinetis_sim
• dtbinding_nxp_kinetis_temperature
• dtbinding_nxp_kinetis_tpm
• dtbinding_nxp_kinetis_trng
• dtbinding_nxp_kinetis_uart
• dtbinding_nxp_kinetis_usbd
• dtbinding_nxp_kinetis_wdog
• dtbinding_nxp_kinetis_wdog32
• dtbinding_nxp_kw41z_ieee802154
• dtbinding_nxp_lpc_ctimer
• dtbinding_nxp_lpc_dma
• dtbinding_nxp_lpc_flexcomm
• dtbinding_nxp_lpc_gpio
• dtbinding_nxp_lpc_i2c
• dtbinding_nxp_lpc_i2s
• dtbinding_nxp_lpc_iocon
• dtbinding_nxp_lpc_iocon_pinctrl
• dtbinding_nxp_lpc_iocon_pio
• dtbinding_nxp_lpc_lpadc
• dtbinding_nxp_lpc_mailbox
• dtbinding_nxp_lpc_mcan
• dtbinding_nxp_lpc_rng
• dtbinding_nxp_lpc_rtc
• dtbinding_nxp_lpc_sdif
• dtbinding_nxp_lpc_spi
• dtbinding_nxp_lpc_syscon
• dtbinding_nxp_lpc_uid
• dtbinding_nxp_lpc_usart
• dtbinding_nxp_lpc_wwdt
• dtbinding_nxp_lpc11u6x_eeprom
• dtbinding_nxp_lpc11u6x_gpio
• dtbinding_nxp_lpc11u6x_i2c
• dtbinding_nxp_lpc11u6x_pinctrl
• dtbinding_nxp_lpc11u6x_pinmux
• dtbinding_nxp_lpc11u6x_syscon
• dtbinding_nxp_lpc11u6x_uart
• dtbinding_nxp_mcr20a
• dtbinding_nxp_mcux_12b1mmps_sar
• dtbinding_nxp_mcux_edma
• dtbinding_nxp_mcux_i2s
• dtbinding_nxp_mcux_i3c
• dtbinding_nxp_mcux_rt_pinctrl
• dtbinding_nxp_mcux_rt11xx_pinctrl
• dtbinding_nxp_mcux_usbd
• dtbinding_nxp_os_timer
• dtbinding_nxp_pca9420
• dtbinding_nxp_pca95xx
• dtbinding_nxp_pca9633
• dtbinding_nxp_pcal6408a
• dtbinding_nxp_pcf8574
• dtbinding_nxp_rt_iiocon_pinctrl
• dtbinding_nxp_s32_gpio
• dtbinding_nxp_s32_linflexd
• dtbinding_nxp_s32_siul2_eirq
• dtbinding_nxp_s32_spi
• dtbinding_nxp_s32ze_pinctrl
• dtbinding_nxp_sctimer_pwm

OmniVision Technologies (ovti)
• dtbinding_ovti_ov2640
• dtbinding_ovti_ov7725

open-isa.org (openisa)
• dtbinding_openisa_rv32m1_event_unit
• dtbinding_openisa_rv32m1_ftfe
• dtbinding_openisa_rv32m1_genfsk
• dtbinding_openisa_rv32m1_gpio
• dtbinding_openisa_rv32m1_intmux
• dtbinding_openisa_rv32m1_intmux_ch
• dtbinding_openisa_rv32m1_lpi2c
• dtbinding_openisa_rv32m1_lpspi
• dtbinding_openisa_rv32m1_lptmr
• dtbinding_openisa_rv32m1_lpuart
• dtbinding_openisa_rv32m1_pcc
• dtbinding_openisa_rv32m1_pinctrl
• dtbinding_openisa_rv32m1_pinmux
• dtbinding_openisa_rv32m1_tpm
• dtbinding_openisa_rv32m1_trng

OpenCores.org (opencores)
  • dtbinding_opencores_spi_simple

Panasonic Corporation (panasonic)
  • dtbinding_panasonic_amg88xx
  • dtbinding_panasonic_reduced_arduino_header

Plantower Co., Ltd (plantower)
  • dtbinding_plantower_pms7003

QEMU, a generic and open source machine emulator and virtualizer (qemu)
  • dtbinding_qemu_ivshmem
  • dtbinding_qemu_nios2_zephyr

Qorvo, Inc (formerly Decawave) (decawave)
  • dtbinding_decawave_dw1000

Quectel Wireless Solutions Co., Ltd. (quectel)
  • dtbinding_quectel_bg9x

QuickLogic Corp. (quicklogic)
  • dtbinding_quicklogic_eos_s3_gpio
  • dtbinding_quicklogic_usbserialport_s3b

Raspberry Pi Foundation (raspberrypi)
  • dtbinding_raspberrypi_pico_adc
  • dtbinding_raspberrypi_pico_flash_controller
  • dtbinding_raspberrypi_pico_gpio
  • dtbinding_raspberrypi_pico_pinctrl
  • dtbinding_raspberrypi_pico_pwm
  • dtbinding_raspberrypi_pico_reset
  • dtbinding_raspberrypi_pico_spi
  • dtbinding_raspberrypi_pico_uart
  • dtbinding_raspberrypi_pico_usbd
• dtbinding_raspberrypi_pico_watchdog

**Raydium Semiconductor Corp. (raydium)**
• dtbinding_raydium_rm68200

**Renesas Electronics Corporation (renesas)**
• dtbinding_renesas_pwm_rcar
• dtbinding_renesas_r8a7795_cpg_mssr
• dtbinding_renesas_rcar_can
• dtbinding_renesas_rcar_cmt
• dtbinding_renesas_rcar_gpio
• dtbinding_renesas_rcar_i2c
• dtbinding_renesas_rcar_pfc
• dtbinding_renesas_rcar_scif
• dtbinding_renesas_smartbond_flash_controller
• dtbinding_renesas_smartbond_gpio
• dtbinding_renesas_smartbond_pinctrl
• dtbinding_renesas_smartbond_uart

**Richtek Technology Corporation (richtek)**
• dtbinding_richtek_rt1718s
• dtbinding_richtek_rt1718s_gpio_port

**RISC-V Foundation (riscv)**
• dtbinding_riscv_cpu_intc

**ROCKTECH DISPLAYS LIMITED (rocktech)**
• dtbinding_rocktech_rk043fn02h_ct

**Seeed Technology Co., Ltd (seeed)**
• dtbinding_seeed_grove_lcd_rgb
• dtbinding_seeed_grove_light
• dtbinding_seeed_grove_temperature
• dtbinding_seeed_xiao_header

**SEGGER Microcontroller GmbH (segger)**
• dtbinding_segger_rtt_uart

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5.2. Devicetree
Semtech Corporation (semtech)
  • dtbinding_semtech_sx1261
  • dtbinding_semtech_sx1262
  • dtbinding_semtech_sx1272
  • dtbinding_semtech_sx1276
  • dtbinding_semtech_sx1509b
  • dtbinding_semtech_sx9500

Sensirion AG (sensirion)
  • dtbinding_sensirion_sgp40
  • dtbinding_sensirion_sht3xd
  • dtbinding_sensirion_sht4x
  • dtbinding_sensirion_shtcx

Sharp Corporation (sharp)
  • dtbinding_sharp_ls0xx

Shenzhen Huiding Technology Co., Ltd. (goodix)
  • dtbinding_goodix_gt911

Sierra Wireless (swir)
  • dtbinding_swir_hl7800

SiFive, Inc. (sifive)
  • dtbinding_sifive_clint0
  • dtbinding_sifive_dtim0
  • dtbinding_sifive_e24
  • dtbinding_sifive_e31
  • dtbinding_sifive_e51
  • dtbinding_sifive_gpio0
  • dtbinding_sifive_i2c0
  • dtbinding_sifive_pinctrl
  • dtbinding_sifive_plic_1.0.0
  • dtbinding_sifive_pwm0
  • dtbinding_sifive_s7
  • dtbinding_sifive_spi0
  • dtbinding_sifive_uart0
  • dtbinding_sifive_wdt
Silicon Laboratories (silabs)
  • dtbinding_silabs_gecko_ethernet
  • dtbinding_silabs_gecko_flash_controller
  • dtbinding_silabs_gecko_gpio
  • dtbinding_silabs_gecko_gpio_port
  • dtbinding_silabs_gecko_i2c
  • dtbinding_silabs_gecko_leuart
  • dtbinding_silabs_gecko_pwm
  • dtbinding_silabs_gecko_rtcc
  • dtbinding_silabs_gecko_semailbox
  • dtbinding_silabs_gecko_spi_usart
  • dtbinding_silabs_gecko_timer
  • dtbinding_silabs_gecko_trng
  • dtbinding_silabs_gecko_uart
  • dtbinding_silabs_gecko_usart
  • dtbinding_silabs_gecko_wdog
  • dtbinding_silabs_si7006
  • dtbinding_silabs_si7055
  • dtbinding_silabs_si7060
  • dtbinding_silabs_si7210

SIMCom Wireless Solutions Co., LTD (simcom)
  • dtbinding_simcom_sim7080

Sitronix Technology Corporation (sitronix)
  • dtbinding_sitronix_st7735r
  • dtbinding_sitronix_st7789v

Skyworks Solutions, Inc. (skyworks)
  • dtbinding_skyworks_sky13351

Smart Battery System (sbs)
  • dtbinding_sbs_sbs_gauge
  • dtbinding_sbs_sbs_gauge_new_api

Solomon Systech Limited (solomon)
  • dtbinding_solomon_ssd1306fb_i2c
  • dtbinding_solomon_ssd1306fb_spi
  • dtbinding_solomon_ssd16xxfb
SparkFun Electronics (sparkfun)
   • dtbinding_sparkfun_pro_micro_header

Standard Microsystems Corporation (smsc)
   • dtbinding_smsc_lan9220

StarFive Technology Co. Ltd. (starfive)
   • dtbinding_starfive_jh7100_clint

STMicroelectronics (st)
   • dtbinding_st_hts221_spi
   • dtbinding_st_hts221_i2c
   • dtbinding_st_i3g4250d
   • dtbinding_st_iis2dh_spi
   • dtbinding_st_iis2dh_i2c
   • dtbinding_st_iis2dlpc_i2c
   • dtbinding_st_iis2dlpc_spi
   • dtbinding_st_iis2iclx_spi
   • dtbinding_st_iis2iclx_i2c
   • dtbinding_st_iis2mdc_i2c
   • dtbinding_st_iis2mdc_spi
   • dtbinding_st_iis3dhhc_spi
   • dtbinding_st_ism330dhcx_i2c
   • dtbinding_st_ism330dhcx_spi
   • dtbinding_st_lis2dh_spi
   • dtbinding_st_lis2dh_i2c
   • dtbinding_st_lis2dh12_i2c
   • dtbinding_st_lis2ds12_i2c
   • dtbinding_st_lis2ds12_spi
   • dtbinding_st_lis2dw12_i2c
   • dtbinding_st_lis2dw12_spi
   • dtbinding_st_lis2mdl_spi
   • dtbinding_st_lis2mdl_i2c
   • dtbinding_st_lis3dh_i2c
   • dtbinding_st_lis3mdl_magn
   • dtbinding_st_lps22hb_press
   • dtbinding_st_lps22hh_i3c
   • dtbinding_st_lps22hh_spi
   • dtbinding_st_lps22hh_i2c
• dtbinding_st_lps25hb_press
• dtbinding_st_lsm303agr_accel_i2c
• dtbinding_st_lsm303agr_accel_spi
• dtbinding_st_lsm303dlhc_accel
• dtbinding_st_lsm303dlhc_magn
• dtbinding_st_lsm6ds0
• dtbinding_st_lsm6dsl_i2c
• dtbinding_st_lsm6dsl_spi
• dtbinding_st_lsm6do_i2c
• dtbinding_st_lsm6do_spi
• dtbinding_st_lsm6do32_spi
• dtbinding_st_lsm6do32_i2c
• dtbinding_st_lsm9ds0_gyro_i2c
• dtbinding_st_lsm9ds0_mfd_i2c
• dtbinding_st_mpxxdttyy_i2s
• dtbinding_st_stm32_adc
• dtbinding_st_stm32_aes
• dtbinding_st_stm32_backup_sram
• dtbinding_st_stm32_can
• dtbinding_st_stm32_ccm
• dtbinding_st_stm32_clock_mux
• dtbinding_st_stm32_counter
• dtbinding_st_stm32_cryp
• dtbinding_st_stm32_dac
• dtbinding_st_stm32_dma
• dtbinding_st_stm32_dma_v1
• dtbinding_st_stm32_dma_v2
• dtbinding_st_stm32_dma_v2bis
• dtbinding_st_stm32_dmamux
• dtbinding_st_stm32_eeprom
• dtbinding_st_stm32_ethernet
• dtbinding_st_stm32_exti
• dtbinding_st_stm32_fdcan
• dtbinding_st_stm32_flash_controller
• dtbinding_st_stm32_fmc
• dtbinding_st_stm32_fmc_nor_psram
• dtbinding_st_stm32_fmc_sram
• dtbinding_st_stm32_gpio
• dtbinding_st_stm32_hse_clock
• dtbinding_st_stm32_hsem_mailbox
• dtbinding_st_stm32_i2c_v1
• dtbinding_st_stm32_i2c_v2
• dtbinding_st_stm32_i2s
• dtbinding_st_stm32_ipcc_mailbox
• dtbinding_st_stm32_lptim
• dtbinding_st_stm32_lpuart
• dtbinding_st_stm32_lse_clock
• dtbinding_st_stm32_ltdc
• dtbinding_st_stm32_msi_clock
• dtbinding_st_stm32_nv_flash
• dtbinding_st_stm32_ospi
• dtbinding_st_stm32_ospi_nor
• dtbinding_st_stm32_otgfs
• dtbinding_st_stm32_otghs
• dtbinding_st_stm32_pinctrl
• dtbinding_st_stm32_pwm
• dtbinding_st_stm32_qdec
• dtbinding_st_stm32_qspi
• dtbinding_st_stm32_qspi_nor
• dtbinding_st_stm32_rcc
• dtbinding_st_stm32_rng
• dtbinding_st_stm32_rtc
• dtbinding_st_stm32_sdmmc
• dtbinding_st_stm32_spi
• dtbinding_st_stm32_spi_fifo
• dtbinding_st_stm32_spi_subghz
• dtbinding_st_stm32_temp
• dtbinding_st_stm32_temp_cal
• dtbinding_st_stm32_timers
• dtbinding_st_stm32_uart
• dtbinding_st_stm32_UCPD
• dtbinding_st_stm32_usart
• dtbinding_st_stm32_usb
• dtbinding_st_stm32_usbphyc
• dtbinding_st_stm32_vbat
• dtbinding_st_stm32_watchdog
• dtbinding_st_stm32_window_watchdog
• dtbinding_st_stm32f0_flash_controller
• dtbinding_st_stm32f0_pll_clock
• dtbinding_st_stm32f0_rcc
• dtbinding_st_stm32f1_flash_controller
• dtbinding_st_stm32f1_pinctrl
• dtbinding_st_stm32f1_pll_clock
• dtbinding_st_stm32f100_pll_clock
• dtbinding_st_stm32f105_pll_clock
• dtbinding_st_stm32f105_pll2_clock
• dtbinding_st_stm32f2_flash_controller
• dtbinding_st_stm32f2_pll_clock
• dtbinding_st_stm32f3_flash_controller
• dtbinding_st_stm32f4_flash_controller
• dtbinding_st_stm32f4_pll_clock
• dtbinding_st_stm32f7_flash_controller
• dtbinding_st_stm32f7_pll_clock
• dtbinding_st_stm32g0_flash_controller
• dtbinding_st_stm32g0_hsi_clock
• dtbinding_st_stm32g0_pll_clock
• dtbinding_st_stm32g4_flash_controller
• dtbinding_st_stm32g4_pll_clock
• dtbinding_st_stm32h7_fdcan
• dtbinding_st_stm32h7_flash_controller
• dtbinding_st_stm32h7_fmc
• dtbinding_st_stm32h7_hsi_clock
• dtbinding_st_stm32h7_pll_clock
• dtbinding_st_stm32h7_rcc
• dtbinding_st_stm32h7_spi
• dtbinding_st_stm32l0_flash_controller
• dtbinding_st_stm32l0_msi_clock
• dtbinding_st_stm32l0_pll_clock
• dtbinding_st_stm32l1_flash_controller
• dtbinding_st_stm32l4_flash_controller
• dtbinding_st_stm32l4_pll_clock
• dtbinding_st_stm32l5_flash_controller
• dtbinding_st_stm32mp1_rcc
• dtbinding_st_stm32u5_dma
• dtbinding_st_stm32u5_flash_controller
• dtbinding_st_stm32u5_msi_clock
• dtbinding_st_stm32u5_pll_clock
• dtbinding_st_stm32u5_rcc
• dtbinding_st_stm32wb_flash_controller
• dtbinding_st_stm32wb_pll_clock
• dtbinding_st_stm32wb_rcc
• dtbinding_st_stm32wl_hse_clock
• dtbinding_st_stm32wl_rcc
• dtbinding_st_stm32wl_subghz_radio
• dtbinding_st_stmpe1600
• dtbinding_st_stts751_i2c
• dtbinding_st_vl53l0x

Synopsys, Inc. (snps)
• dtbinding_snps_arc_iot_sysconf
• dtbinding_snps_arc_timer
• dtbinding_snps_arcem
• dtbinding_snps_archs_ici
• dtbinding_snps_archs_idu_intc
• dtbinding_snps_arccv2_intc
• dtbinding_snps_creg_gpio
• dtbinding_snps_designware_dma
• dtbinding_snps_designware_ethernet
• dtbinding_snps_designware_gpio
• dtbinding_snps_designware_i2c
• dtbinding_snps_designware_intc
• dtbinding_snps_designware_spi
• dtbinding_snps_designware_usb
• dtbinding_snps_ethernet_cyclonev
• dtbinding_snps_nsim_uart

Synopsys, Inc. (formerly ARC International PLC) (arc)
• dtbinding_arc_dccm
• dtbinding_arc_iccm

Telink Semiconductor (telink)
• dtbinding_telink_b91
• dtbinding_telink_b91_adc
• dtbinding_telink_b91_flash_controller
• dtbinding_telink_b91_gpio
• dtbinding_telink_b91_i2c
• dtbinding_telink_b91_pinctrl
• dtbinding_telink_b91_power
• dtbinding_telink_b91_pwm
• dtbinding_telink_b91_spi
• dtbinding_telink_b91_trng
• dtbinding_telink_b91_uart
• dtbinding_telink_b91_zb
• dtbinding_telink_machine_timer

**Texas Instruments (ti)**
• dtbinding_ti_ads1013
• dtbinding_ti_ads1014
• dtbinding_ti_ads1015
• dtbinding_ti_ads1113
• dtbinding_ti_ads1114
• dtbinding_ti_ads1115
• dtbinding_ti_ads1119
• dtbinding_ti_boosterpack_header
• dtbinding_ti_bq274xx
• dtbinding_ti_cc1200
• dtbinding_ti_cc13xx_cc26xx_adc
• dtbinding_ti_cc13xx_cc26xx_flash_controller
• dtbinding_ti_cc13xx_cc26xx_gpio
• dtbinding_ti_cc13xx_cc26xx_i2c
• dtbinding_ti_cc13xx_cc26xx_ieee802154
• dtbinding_ti_cc13xx_cc26xx_ieee802154_subghz
• dtbinding_ti_cc13xx_cc26xx_pinctrl
• dtbinding_ti_cc13xx_cc26xx_radio
• dtbinding_ti_cc13xx_cc26xx_rtc
• dtbinding_ti_cc13xx_cc26xx_spi
• dtbinding_ti_cc13xx_cc26xx_trng
• dtbinding_ti_cc13xx_cc26xx_uart
• dtbinding_ti_cc2520
• dtbinding_ti_cc32xx_adc
• dtbinding_ti_cc32xx_gpio
• dtbinding_ti_cc32xx_i2c
• dtbinding_ti_cc32xx_uart
• dtbinding_ti_cc32xx_watchdog
• dtbinding_ti_dac43608

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• dtbinding_ti_dac53608  
• dtbinding_ti_dac60508  
• dtbinding_ti_dac70508  
• dtbinding_ti_dac80508  
• dtbinding_ti_fdc2x1x  
• dtbinding_ti_hdc  
• dtbinding_ti_hdc2010  
• dtbinding_ti_hdc2021  
• dtbinding_ti_hdc2022  
• dtbinding_ti_hdc2080  
• dtbinding_ti_hdc20xx  
• dtbinding_ti_ina219  
• dtbinding_ti_ina230  
• dtbinding_ti_ina237  
• dtbinding_ti_lmp90077  
• dtbinding_ti_lmp90078  
• dtbinding_ti_lmp90079  
• dtbinding_ti_lmp90080  
• dtbinding_ti_lmp90097  
• dtbinding_ti_lmp90098  
• dtbinding_ti_lmp90099  
• dtbinding_ti_lmp90100  
• dtbinding_ti_lmp90xxx_gpio  
• dtbinding_ti_lp3943  
• dtbinding_ti_lp503x  
• dtbinding_ti_lp5562  
• dtbinding_ti_msp432p4xx_uart  
• dtbinding_ti_opt3001  
• dtbinding_ti_sn74hc595  
• dtbinding_ti_stellaris_ethernet  
• dtbinding_ti_stellaris_flash_controller  
• dtbinding_ti_stellaris_gpio  
• dtbinding_ti_stellaris_uart  
• dtbinding_ti_tca6424a  
• dtbinding_ti_tca9538  
• dtbinding_ti_tca9546a  
• dtbinding_ti_tca9548a  
• dtbinding_ti_tlc59108  
• dtbinding_ti_tlc5971
• dtbinding_ti_tlv320dac
• dtbinding_ti_tmp007
• dtbinding_ti_tmp108
• dtbinding_ti_tmp112
• dtbinding_ti_tmp116
• dtbinding_ti_tmp116_eeprom

u-blox (u-blox)
  • dtbinding_u_blox_sara_r4

UltraChip Inc. (ultrachip)
  • dtbinding_ultrachip_uc8176
  • dtbinding_ultrachip_uc8179

Vishay Intertechnology, Inc (vishay)
  • dtbinding_vishay_vcnl4040

Wistron NeWeb Corporation (wnc)
  • dtbinding_wnc_m14a2a

WIZnet Co., Ltd. (wiznet)
  • dtbinding_wiznet_w5500

Worldsemi Co., Limited (worldsemi)
  • dtbinding_worldsemi_ws2812_gpio
  • dtbinding_worldsemi_ws2812_spi

Würth Elektronik GmbH. (we)
  • dtbinding_we_wsen_hids_i2c
  • dtbinding_we_wsen_hids_spi
  • dtbinding_we_wsen_itds

Xen Hypervisor (xen)
  • dtbinding_xen_hvc_uart
  • dtbinding_xen_xen_4.15
Xilinx (xlnx)

- dtbinding_xlnx_fpga
- dtbinding_xlnx_gem
- dtbinding_xlnx_pinctrl_zynq
- dtbinding_xlnx_ps_gpio
- dtbinding_xlnx_ps_gpio_bank
- dtbinding_xlnx_ttcps
- dtbinding_xlnx_xps_gpio_1.00.a
- dtbinding_xlnx_xps_gpio_1.00.a_gpio2
- dtbinding_xlnx_xps_spi_2.00.a
- dtbinding_xlnx_xps_timer_1.00.a
- dtbinding_xlnx_xps_timer_1.00.a_pwm
- dtbinding_xlnx_xps_uartlite_1.00.a
- dtbinding_xlnx_xuartps
- dtbinding_xlnx_zynq_ocm

Zephyr-specific binding (zephyr)

- dtbinding_zephyr_adc_emul
- dtbinding_zephyr_bbram_emul
- dtbinding_zephyr_bt_hci_entropy
- dtbinding_zephyr_bt_hci_spi
- dtbinding_zephyr_bt_hci_spi_slave
- dtbinding_zephyr_can_loopback
- dtbinding_zephyr_cdc_acm_uart
- dtbinding_zephyr_coredump
- dtbinding_zephyr_counter_watchdog
- dtbinding_zephyr_dummy_dc
- dtbinding_zephyr_ec_host_cmd_periph_espi
- dtbinding_zephyr_emu_eeprom
- dtbinding_zephyr_espi_emul_controller
- dtbinding_zephyr_fake_can
- dtbinding_zephyr_fake_eeprom
- dtbinding_zephyr_flash_disk
- dtbinding_zephyr_fstab
- dtbinding_zephyr_fstab_littlefs
- dtbinding_zephyr_gpio_emul
- dtbinding_zephyr_gpio_emul_sdl
- dtbinding_zephyr_gsm_ppp
- dtbinding_zephyr_i2c_emul_controller
5.3 Configuration System (Kconfig)

The Zephyr kernel and subsystems can be configured at build time to adapt them for specific application and platform needs. Configuration is handled through Kconfig, which is the same configuration system used by the Linux kernel. The goal is to support configuration without having to change any source code.

Configuration options (often called symbols) are defined in Kconfig files, which also specify dependencies between symbols that determine what configurations are valid. Symbols can be grouped into menus and sub-menus to keep the interactive configuration interfaces organized.
The output from Kconfig is a header file autoconf.h with macros that can be tested at build time. Code for unused features can be compiled out to save space.

The following sections explain how to set Kconfig configuration options, go into detail on how Kconfig is used within the Zephyr project, and have some tips and best practices for writing Kconfig files.

5.3.1 Interactive Kconfig interfaces

There are two interactive configuration interfaces available for exploring the available Kconfig options and making temporary changes: menuconfig and guiconfig. menuconfig is a curses-based interface that runs in the terminal, while guiconfig is a graphical configuration interface.

**Note:** The configuration can also be changed by editing zephyr/.config in the application build directory by hand. Using one of the configuration interfaces is often handier, as they correctly handle dependencies between configuration symbols.

If you try to enable a symbol with unsatisfied dependencies in zephyr/.config, the assignment will be ignored and overwritten when re-configuring.

To make a setting permanent, you should set it in a *.conf file, as described in Setting Kconfig configuration values.

**Tip:** Saving a minimal configuration file (with e.g. D in menuconfig) and inspecting it can be handy when making settings permanent. The minimal configuration file only lists symbols that differ from their default value.

To run one of the configuration interfaces, do this:

1. Build your application as usual using either west or cmake:

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

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

2. To run the terminal-based menuconfig interface, use either of these commands:

   ```
   west build -t menuconfig
   ```

   ```
   ninja menuconfig
   ```

   To run the graphical guiconfig, use either of these commands:

   ```
   west build -t guiconfig
   ```

   ```
   ninja guiconfig
   ```

   **Note:** If you get an import error for tkinter when trying to run guiconfig, you are missing required packages. See Install Linux Host Dependencies. The package you need is usually called something like python3-tk/python3-tkinter.
tkinter is not included by default in many Python installations, despite being part of the standard library.

The two interfaces are shown below:

![Image showing two interfaces: one for menus and another for icons.](image)

guiconfig always shows the help text and other information related to the currently selected item in the bottom window pane. In the terminal interface, press ? to view the same information.

**Note:** If you prefer to work in the guiconfig interface, then it's a good idea to check any changes to Kconfig files you make in single-menu mode, which is toggled via a checkbox at the top. Unlike full-tree mode, single-menu mode will distinguish between symbols defined with `config` and symbols defined with `menuconfig`, showing you what things would look like in the `menuconfig` interface.

3. Change configuration values in the `menuconfig` interface as follows:

   - Navigate the menu with the arrow keys. Common Vim key bindings are supported as well.
   - Use Space and Enter to enter menus and toggle values. Menus appear with `--->` next to them. Press ESC to return to the parent menu.

   Boolean configuration options are shown with `[ ]` brackets, while numeric and string-valued configuration symbols are shown with `( )` brackets. Symbol values that can’t be changed are shown as `--` or `--*--`.

   **Note:** You can also press Y or N to set a boolean configuration symbol to the corresponding value.

   - Press ? to display information about the currently selected symbol, including its help text. Press ESC or Q to return from the information display to the menu.

   In the guiconfig interface, either click on the image next to the symbol to change its value, or double-click on the row with the symbol (this only works if the symbol has no children, as double-clicking a symbol with children open/closes its menu instead).

   guiconfig also supports keyboard controls, which are similar to `menuconfig`. 
4. Pressing Q in the `menuconfig` interface will bring up the save-and-quit dialog (if there are changes to save):

Press Y to save the kernel configuration options to the default filename (`zephyr/.config`). You will typically save to the default filename unless you are experimenting with different configurations.

The `guiconfig` interface will also prompt for saving the configuration on exit if it has been modified.

**Note:** The configuration file used during the build is always `zephyr/.config`. If you have another saved configuration that you want to build with, copy it to `zephyr/.config`. Make sure to back up your original configuration file.

Also note that filenames starting with a dot are not listed by `ls` by default on Linux and macOS. Use the `-a` flag to see them.

Finding a symbol in the menu tree and navigating to it can be tedious. To jump directly to a symbol, press the `/` key (this also works in `guiconfig`). This brings up the following dialog, where you can search for symbols by name and jump to them. In `guiconfig`, you can also change symbol values directly within the dialog.

If you jump to a symbol that isn't currently visible (e.g., due to having unsatisfied dependencies), then show-all mode will be enabled. In show-all mode, all symbols are displayed, including currently invisible symbols. To turn off show-all mode, press A in `menuconfig` or Ctrl-A in `guiconfig`.

**Note:** Show-all mode can't be turned off if there are no visible items in the current menu.
### 5.3. Configuration System (Kconfig)

- **WATCHDOG 0** Watchdog driver instance name
- **[] Disable at boot**
- **[ ] QMSI Watchdog driver**

Save configuration?  
(Y)es (N)o (C)ancel

**[Space/Enter] Toggle/enter**  
**[ESC] Leave menu**  
**[S] Save**  
**[O] Load**  
**[?] Symbol info**  
**[/] Jump to symbol**  
**[F] Toggle show-help mode**  
**[C] Toggle show-name mode**  
**[A] Toggle show-all mode**  
**[Q] Quit (prompts for save)**  
**[D] Save minimal config (advanced)**

**IWDG STM32** "Independent Watchdog (IWDG) Driver for STM32 family of MCUs"
**WATCHDOG** "Watchdog Support"
**WDOG CMSDK_APB** "CMSDK_APB Watchdog Driver for ARM family of MCUs"
**WDOG CMSDK_APB_START_AT_BOOT** "Start Watchdog during boot"
**WDT @ NAME** "Watchdog driver instance name"
**WDT_ESP32** "ESP32 Watchdog (WDT) Driver"
**WDT_ESP32_IRQ** "IRQ line for watchdog interrupt"
**WDT_QMSI** "QMSI Watchdog driver"
**WDT_SAM** "Atmel SAM MCU Family Watchdog (WDT) Driver"
**WDT_SAM0** "Atmel SAM0 series Watchdog (WDT) Driver"

Type text to narrow the search. Regexes are supported (via Python's 're' module). The up/down cursor keys step in the list. [Enter] jumps to the selected symbol. [ESC] aborts the search. Type multiple space-separated strings/regexes to find entries that match all of them. Type Ctrl-F to view the help of the selected item without leaving the dialog.
To figure out why a symbol you jumped to isn’t visible, inspect its dependencies, either by pressing \texttt{?} in \texttt{menuconfig} or in the information pane at the bottom in \texttt{guiconfig}. If you discover that the symbol depends on another symbol that isn’t enabled, you can jump to that symbol in turn to see if it can be enabled.

\textbf{Note:} In \texttt{menuconfig}, you can press Ctrl-F to view the help of the currently selected item in the jump-to dialog without leaving the dialog.

For more information on \texttt{menuconfig} and \texttt{guiconfig}, see the Python docstrings at the top of \texttt{menuconfig.py} and \texttt{guiconfig.py}.

\section*{5.3.2 Setting Kconfig configuration values}

The \texttt{menuconfig} and \texttt{guiconfig} interfaces can be used to test out configurations during application development. This page explains how to make settings permanent.

All Kconfig options can be searched in the Kconfig search page.

\textbf{Note:} Before making changes to Kconfig files, it’s a good idea to also go through the \texttt{Kconfig - Tips and Best Practices} page.

\section*{Visible and invisible Kconfig symbols}

When making Kconfig changes, it’s important to understand the difference between \textit{visible} and \textit{invisible} symbols.

\begin{itemize}
  \item A visible symbol is a symbol defined with a prompt. Visible symbols show up in the interactive configuration interfaces (hence \textit{visible}), and can be set in configuration files.

  Here’s an example of a visible symbol:

  \begin{verbatim}
  config FPU
  bool "Support floating point operations"
  depends on HAS_FPU
  \end{verbatim}

  The symbol is shown like this in \texttt{menuconfig}, where it can be toggled:

  \begin{verbatim}
  [ ] Support floating point operations
  \end{verbatim}

  \item An \textit{invisible} symbol is a symbol without a prompt. Invisible symbols are not shown in the interactive configuration interfaces, and users have no direct control over their value. They instead get their value from defaults or from other symbols.

  Here’s an example of an invisible symbol:

  \begin{verbatim}
  config CPU_HAS_FPU
  bool help
  "This symbol is y if the CPU has a hardware floating point unit."
  \end{verbatim}

  In this case, CPU\_HAS\_FPU is enabled through other symbols having select CPU\_HAS\_FPU.
Setting symbols in configuration files

Visible symbols can be configured by setting them in configuration files. The initial configuration is produced by merging a _defconfig file for the board with application settings, usually from prj.conf. See The Initial Configuration below for more details.

Assignments in configuration files use this syntax:

```
CONFIG_<symbol name>=<value>
```

There should be no spaces around the equals sign.

bool symbols can be enabled or disabled by setting them to y or n, respectively. The FPU symbol from the example above could be enabled like this:

```
CONFIG_FPU=y
```

**Note:** A boolean symbol can also be set to n with a comment formatted like this:

```
# CONFIG_SOME_OTHER_BOOL is not set
```

This is the format you will see in the merged configuration in zephyr/.config.

This style is accepted for historical reasons: Kconfig configuration files can be parsed as makefiles (though Zephyr doesn’t use this). Having n-valued symbols correspond to unset variables simplifies tests in Make.

Other symbol types are assigned like this:

```
CONFIG_SOME_STRING="cool value"
CONFIG_SOME_INT=123
```

Comments use a #:

```
# This is a comment
```

Assignments in configuration files are only respected if the dependencies for the symbol are satisfied. A warning is printed otherwise. To figure out what the dependencies of a symbol are, use one of the interactive configuration interfaces (you can jump directly to a symbol with /), or look up the symbol in the Kconfig search page.

The Initial Configuration

The initial configuration for an application comes from merging configuration settings from three sources:

1. A BOARD-specific configuration file stored in boards/<architecture>/<BOARD>/_defconfig
2. Any CMake cache entries prefix with CONFIG_
3. The application configuration

The application configuration can come from the sources below. By default, prj.conf is used.

1. If CONF_FILE is set, the configuration file(s) specified in it are merged and used as the application configuration. CONF_FILE can be set in various ways:
   1. In CMakeLists.txt, before calling find_package(Zephyr)
   2. By passing -DCONF_FILE=<conf file(s)> directly or via west
   3. From the CMake variable cache
2. Otherwise if CONF_FILE is set, and a single configuration file of the form prj.<build>.conf is used, then if file boards/<BOARD>.<build>.conf exists in same folder as file prj.<build>.conf, the result of merging prj.<build>.conf and boards/<BOARD>.<build>.conf is used.

3. Otherwise, prj.<BOARD>.conf is used if it exists in the application configuration directory.

4. Otherwise, if boards/<BOARD>.conf exists in the application configuration directory, the result of merging it with prj.conf is used.

5. Otherwise, if board revisions are used and boards/<BOARD>.<revision>.conf exists in the application configuration directory, the result of merging it with prj.conf and boards/<BOARD>.conf is used.

6. Otherwise, prj.conf is used if it exists in the application configuration directory.

All configuration files will be taken from the application's configuration directory except for files with an absolute path that are given with the CONF_FILE, OVERLAY_CONFIG, and DTC_OVERLAY_FILE arguments. For these, a file in a Zephyr module can be referred by escaping the Zephyr module dir variable like this \${ZEPHYR_<module>_MODULE_DIR}/<path-to>/<file> when setting any of said variables in the application's CMakeLists.txt.

See Application Configuration Directory on how the application configuration directory is defined.

If a symbol is assigned both in <BOARD>_defconfig and in the application configuration, the value set in the application configuration takes precedence.

The merged configuration is saved to zephyr/.config in the build directory.

As long as zephyr/.config exists and is up-to-date (is newer than any BOARD and application configuration files), it will be used in preference to producing a new merged configuration. zephyr/.config is also the configuration that gets modified when making changes in the interactive configuration interfaces.

Configuring invisible Kconfig symbols

When making changes to the default configuration for a board, you might have to configure invisible symbols. This is done in boards/<architecture>/<BOARD>/Kconfig.defconfig, which is a regular Kconfig file.

Note: Assignments in .config files have no effect on invisible symbols, so this scheme is not just an organizational issue.

Assigning values in Kconfig.defconfig relies on defining a Kconfig symbol in multiple locations. As an example, say we want to set FOO_WIDTH below to 32:

```plaintext
config FOO_WIDTH
  int
```

To do this, we extend the definition of FOO_WIDTH as follows, in Kconfig.defconfig:

```plaintext
if BOARD_MY_BOARD
  config FOO_WIDTH
default 32
endif
```

Note: Since the type of the symbol (int) has already been given at the first definition location, it does not need to be repeated here. Only giving the type once at the “base” definition of the symbol is a good idea for reasons explained in Common Kconfig shorthands.
default values in Kconfig.defconfig files have priority over default values given on the “base” definition of a symbol. Internally, this is implemented by including the Kconfig.defconfig files first. Kconfig uses the first default with a satisfied condition, where an empty condition corresponds to if y (is always satisfied).

Note that conditions from surrounding top-level if's are propagated to symbol properties, so the above default is equivalent to default 32 if BOARD_MY_BOARD.

**Warning:** When defining a symbol in multiple locations, dependencies are ORed together rather than ANDed together. It is not possible to make the dependencies of a symbol more restrictive by defining it in multiple locations.

For example, the direct dependencies of the symbol below becomes DEP1 || DEP2:

```plaintext
config FOO
    ... depends on DEP1
config FOO
    ... depends on DEP2
```

When making changes to Kconfig.defconfig files, always check the symbol's direct dependencies in one of the interactive configuration interfaces afterwards. It is often necessary to repeat dependencies from the base definition of the symbol to avoid weakening a symbol’s dependencies.

**Motivation for Kconfig.defconfig files** One motivation for this configuration scheme is to avoid making fixed BOARD-specific settings configurable in the interactive configuration interfaces. If all board configuration were done via `<BOARD>_defconfig`, all symbols would have to be visible, as values given in `<BOARD>_defconfig` have no effect on invisible symbols.

Having fixed settings be user-configurable would clutter up the configuration interfaces and make them harder to understand, and would make it easier to accidentally create broken configurations.

When dealing with fixed board-specific settings, also consider whether they should be handled via devicetree instead.

**Configuring choices** There are two ways to configure a Kconfig choice:

1. By setting one of the choice symbols to y in a configuration file.

   Setting one choice symbol to y automatically gives all other choice symbols the value n.

   If multiple choice symbols are set to y, only the last one set to y will be honored (the rest will get the value n). This allows a choice selection from a board defconfig file to be overridden from an application prj.conf file.

2. By changing the default of the choice in Kconfig.defconfig.

   As with symbols, changing the default for a choice is done by defining the choice in multiple locations. For this to work, the choice must have a name.

   As an example, assume that a choice has the following base definition (here, the name of the choice is FOO):

```plaintext
choice FOO
    bool "Foo choice"
    default B

config A
```

(continues on next page)
true "A"

config B
  bool "B"
endchoice

To change the default symbol of FOO to A, you would add the following definition to Kconfig.

defconfig:

choice FOO
default A
endchoice

The Kconfig.defconfig method should be used when the dependencies of the choice might not be satisfied. In that case, you're setting the default selection whenever the user makes the choice visible.

More Kconfig resources  The Kconfig - Tips and Best Practices page has some tips for writing Kconfig files.

The kconfiglib.py docstring docstring (at the top of the file) goes over how symbol values are calculated in detail.

5.3.3  Kconfig - Tips and Best Practices

This page covers some Kconfig best practices and explains some Kconfig behaviors and features that might be cryptic or that are easily overlooked.

Note:  The official Kconfig documentation is kconfig-language.rst and kconfig-macro-language.rst.
What to turn into Kconfig options

When deciding whether something belongs in Kconfig, it helps to distinguish between symbols that have prompts and symbols that don’t.

If a symbol has a prompt (e.g. bool "Enable foo"), then the user can change the symbol’s value in the menuconfig or guiconfig interface (see Interactive Kconfig interfaces), or by manually editing configuration files. Conversely, a symbol without a prompt can never be changed directly by the user, not even by manually editing configuration files.

Only put a prompt on a symbol if it makes sense for the user to change its value.

Symbols without prompts are called hidden or invisible symbols, because they don’t show up in menuconfig and guiconfig. Symbols that have prompts can also be invisible, when their dependencies are not satisfied.

Symbols without prompts can’t be configured directly by the user (they derive their value from other symbols), so less restrictions apply to them. If some derived setting is easier to calculate in Kconfig than e.g. during the build, then do it in Kconfig, but keep the distinction between symbols with and without prompts in mind.

See the optional prompts section for a way to deal with settings that are fixed on some machines and configurable on other machines.

What not to turn into Kconfig options

In Zephyr, Kconfig configuration is done after selecting a target board. In general, it does not make sense to use Kconfig for a value that corresponds to a fixed machine-specific setting. Usually, such settings should be handled via devicetree instead.

In particular, avoid adding new Kconfig options of the following types:

Options that specify a device in the system by name  For example, if you are writing an I2C device driver, avoid creating an option named MY_DEVICE_I2C_BUS_NAME for specifying the bus node your device is controlled by. See Device drivers that depend on other devices for alternatives.
Similarly, if your application depends on a hardware-specific PWM device to control an RGB LED, avoid creating an option like `MY_PWM_DEVICE_NAME`. See *Applications that depend on board-specific devices* for alternatives.

**Options that specify fixed hardware configuration**  For example, avoid `Kconfig` options specifying a GPIO pin.

An alternative applicable to device drivers is to define a GPIO specifier with type phandle-array in the device binding, and using the `GPIO` devicetree API from C. Similar advice applies to other cases where `devicetree.h` provides *Hardware specific APIs* for referring to other nodes in the system. Search the source code for drivers using these APIs for examples.

An application-specific devicetree binding to identify board specific properties may be appropriate. See `tests/drivers/gpio/gpio_basic_api` for an example.

For applications, see `blinky-sample` for a devicetree-based alternative.

**select statements**

The `select` statement is used to force one symbol to `y` whenever another symbol is `y`. For example, the following code forces `CONSOLE` to `y` whenever `USB_CONSOLE` is `y`:

```
config CONSOLE
  bool "Console support"
...

config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
```

This section covers some pitfalls and good uses for `select`.

**select pitfalls**  `select` might seem like a generally useful feature at first, but can cause configuration issues if overused.

For example, say that a new dependency is added to the `CONSOLE` symbol above, by a developer who is unaware of the `USB_CONSOLE` symbol (or simply forgot about it):

```
config CONSOLE
  bool "Console support"
  depends on STRING_ROUTINES
...

config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
```

Enabling `USB_CONSOLE` now forces `CONSOLE` to `y`, even if `STRING_ROUTINES` is `n`.

To fix the problem, the `STRING_ROUTINES` dependency needs to be added to `USB_CONSOLE` as well:

```
config USB_CONSOLE
  bool "USB console support"
  select CONSOLE
  depends on STRING_ROUTINES
...

config STRING_ROUTINES
  bool "Include string routines"
```

More insidious cases with dependencies inherited from `if` and `menu` statements are common.

An alternative attempt to solve the issue might be to turn the `depends` on into another `select`:  

---

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config CONSOLE
  bool "Console support"
  select STRING_ROUTINES

...

config USB_CONSOLE
  bool "USB console support"
  select CONSOLE

In practice, this often amplifies the problem, because any dependencies added to STRING_ROUTINES now need to be copied to both CONSOLE and USB_CONSOLE.

In general, whenever the dependencies of a symbol are updated, the dependencies of all symbols that (directly or indirectly) select it have to be updated as well. This is very often overlooked in practice, even for the simplest case above.

Chains of symbols selecting each other should be avoided in particular, except for simple helper symbols, as covered below in Using select for helper symbols.

Liberal use of select also tends to make Kconfig files harder to read, both due to the extra dependencies and due to the non-local nature of select, which hides ways in which a symbol might get enabled.

**Alternatives to select** For the example in the previous section, a better solution is usually to turn the select into a depends on:

config CONSOLE
  bool "Console support"

...

config USB_CONSOLE
  bool "USB console support"
  depends on CONSOLE

This makes it impossible to generate an invalid configuration, and means that dependencies only ever have to be updated in a single spot.

An objection to using depends on here might be that configuration files that enable USB_CONSOLE now also need to enable CONSOLE:

CONFIG_CONSOLE=y
CONFIG_USB_CONSOLE=y

This comes down to a trade-off, but if enabling CONSOLE is the norm, then a mitigation is to make CONSOLE default to y:

config CONSOLE
  bool "Console support"
  default y

This gives just a single assignment in configuration files:

CONFIG_USB_CONSOLE=y

Note that configuration files that do not want CONSOLE enabled now have to explicitly disable it:

CONFIG_CONSOLE=n
Using `select` for helper symbols  A good and safe use of `select` is for setting “helper” symbols that capture some condition. Such helper symbols should preferably have no prompt or dependencies.

For example, a helper symbol for indicating that a particular CPU/SoC has an FPU could be defined as follows:

```c
config CPU_HAS_FPU
  bool
  help
   If y, the CPU has an FPU
...

config SOC_FOO
  bool "FOO SoC"
  select CPU_HAS_FPU
...

config SOC_BAR
  bool "BAR SoC"
  select CPU_HAS_FPU
```

This makes it possible for other symbols to check for FPU support in a generic way, without having to look for particular architectures:

```c
config FPU
  bool "Support floating point operations"
  depends on CPU_HAS_FPU
```

The alternative would be to have dependencies like the following, possibly duplicated in several spots:

```c
config FPU
  bool "Support floating point operations"
  depends on SOC_FOO || SOC_BAR || ...
```

Invisible helper symbols can also be useful without `select`. For example, the following code defines a helper symbol that has the value y if the machine has some arbitrarily-defined “large” amount of memory:

```c
config LARGE_MEM
  def_bool MEM_SIZE >= 64
```

**Note:** This is short for the following:

```c
config LARGE_MEM
  bool
  default MEM_SIZE >= 64
```

**select recommendations** In summary, here are some recommended practices for `select`:

- Avoid selecting symbols with prompts or dependencies. Prefer `depends on`. If `depends on` causes annoying bloat in configuration files, consider adding a Kconfig default for the most common value.

  Rare exceptions might include cases where you’re sure that the dependencies of the selecting and selected symbol will never drift out of sync, e.g. when dealing with two simple symbols defined close to one another within the same `if`. 

Chapter 5. Build and Configuration Systems
Common sense applies, but be aware that `select` often causes issues in practice. `depends on` is usually a cleaner and safer solution.

- Select simple helper symbols without prompts and dependencies however much you like. They’re a great tool for simplifying Kconfig files.

**Lack of conditional includes**

`if` blocks add dependencies to each item within the `if`, as if `depends on` was used.

A common misunderstanding related to `if` is to think that the following code conditionally includes the file `Kconfig.other`:

```c
if DEP
    source "Kconfig.other"
endif
```

In reality, there are no conditional includes in Kconfig. `if` has no special meaning around a `source`.

**Note:** Conditional includes would be impossible to implement, because `if` conditions may contain (either directly or indirectly) forward references to symbols that haven’t been defined yet.

Say that `Kconfig.other` above contains this definition:

```c
cfg FOO
    bool "Support foo"
```

In this case, `FOO` will end up with this definition:

```c
cfg FOO
    bool "Support foo"
    depends on DEP
```

Note that it is redundant to add `depends on DEP` to the definition of `FOO` in `Kconfig.other`, because the `DEP` dependency has already been added by `if DEP`.

In general, try to avoid adding redundant dependencies. They can make the structure of the Kconfig files harder to understand, and also make changes more error-prone, since it can be hard to spot that the same dependency is added twice.

**“Stuck” symbols in menuconfig and guiconfig**

There is a common subtle gotcha related to interdependent configuration symbols with prompts. Consider these symbols:

```c
cfg FOO
    bool "Foo"

cfg STACK_SIZE
    hex "Stack size"
    default 0x200 if FOO
    default 0x100
```

Assume that the intention here is to use a larger stack whenever `FOO` is enabled, and that the configuration initially has `FOO` disabled. Also, remember that Zephyr creates an initial configuration in `zephyr/.config` in the build directory by merging configuration files (including e.g. `prj.conf`). This configuration file exists before `menuconfig` or `guiconfig` is run.
When first entering the configuration interface, the value of STACK_SIZE is 0x100, as expected. After enabling FOO, you might reasonably expect the value of STACK_SIZE to change to 0x200, but it stays as 0x100.

To understand what's going on, remember that STACK_SIZE has a prompt, meaning it is user-configurable, and consider that all Kconfig has to go on from the initial configuration is this:

```
CONFIG_STACK_SIZE=0x100
```

Since Kconfig can't know if the 0x100 value came from a default or was typed in by the user, it has to assume that it came from the user. Since STACK_SIZE is user-configurable, the value from the configuration file is respected, and any symbol defaults are ignored. This is why the value of STACK_SIZE appears to be “frozen” at 0x100 when toggling FOO.

The right fix depends on what the intention is. Here’s some different scenarios with suggestions:

- If STACK_SIZE can always be derived automatically and does not need to be user-configurable, then just remove the prompt:

  ```
  config STACK_SIZE
  hex
  default 0x200 if FOO
  default 0x100
  ```

  Symbols without prompts ignore any value from the saved configuration.

- If STACK_SIZE should usually be user-configurable, but needs to be set to 0x200 when FOO is enabled, then disable its prompt when FOO is enabled, as described in optional prompts:

  ```
  config STACK_SIZE
  hex "Stack size" if !FOO
  default 0x200 if FOO
  default 0x100
  ```

- If STACK_SIZE should usually be derived automatically, but needs to be set to a custom value in rare circumstances, then add another option for making STACK_SIZE user-configurable:

  ```
  config CUSTOM_STACK_SIZE
  bool "Use a custom stack size"
  help
  Enable this if you need to use a custom stack size. When disabled, a suitable stack size is calculated automatically.
  
  config STACK_SIZE
  hex "Stack size" if CUSTOM_STACK_SIZE
  default 0x200 if FOO
  default 0x100
  ```

  As long as CUSTOM_STACK_SIZE is disabled, STACK_SIZE will ignore the value from the saved configuration.

It is a good idea to try out changes in the menuconfig or guiconfig interface, to make sure that things behave the way you expect. This is especially true when making moderately complex changes like these.

**Assignments to promptless symbols in configuration files**

Assignments to hidden (promptless, also called invisible) symbols in configuration files are always ignored. Hidden symbols get their value indirectly from other symbols, via e.g. default and select.

A common source of confusion is opening the output configuration file (zephyr/.config), seeing a bunch of assignments to hidden symbols, and assuming that those assignments must be respected when
the configuration is read back in by Kconfig. In reality, all assignments to hidden symbols in `zephyr/.config` are ignored by Kconfig, like for other configuration files.

To understand why `zephyr/.config` still includes assignments to hidden symbols, it helps to realize that `zephyr/.config` serves two separate purposes:

1. It holds the saved configuration, and
2. It holds configuration output. `zephyr/.config` is parsed by the CMake files to let them query configuration settings, for example.

The assignments to hidden symbols in `zephyr/.config` are just configuration output. Kconfig itself ignores assignments to hidden symbols when calculating symbol values.

**Note:** A minimal configuration, which can be generated from within the `menuconfig` and `guiconfig` interfaces, could be considered closer to just a saved configuration, without the full configuration output.

**depends on and string/int/hex symbols**

`depends on` works not just for bool symbols, but also for string, int, and hex symbols (and for choices).

The Kconfig definitions below will hide the `FOO_DEVICE_FREQUENCY` symbol and disable any configuration output for it when `FOO_DEVICE` is disabled.

```c
config FOO_DEVICE
  bool "Foo device"

config FOO_DEVICE_FREQUENCY
  int "Foo device frequency"
  depends on FOO_DEVICE
```

In general, it's a good idea to check that only relevant symbols are ever shown in the `menuconfig/guiconfig` interface. Having `FOO_DEVICE_FREQUENCY` show up when `FOO_DEVICE` is disabled (and possibly hidden) makes the relationship between the symbols harder to understand, even if code never looks at `FOO_DEVICE_FREQUENCY` when `FOO_DEVICE` is disabled.

**menuconfig symbols**

If the definition of a symbol `F00` is immediately followed by other symbols that depend on `F00`, then those symbols become children of `F00`. If `F00` is defined with `config F00`, then the children are shown indented relative to `F00`. Defining `F00` with `menuconfig F00` instead puts the children in a separate menu rooted at `F00`.

`menuconfig` has no effect on evaluation. It's just a display option.

`menuconfig` can cut down on the number of menus and make the menu structure easier to navigate. For example, say you have the following definitions:

```c
menu "Foo subsystem"

config FOO_SUBSYSTEM
  bool "Foo subsystem"

if FOO_SUBSYSTEM

config FOO_FEATURE_1
  bool "Foo feature 1"
```

(continues on next page)
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config FOO_FEATURE_2
  bool "Foo feature 2"

config FOO_FREQUENCY
  int "Foo frequency"

... lots of other FOO-related symbols

defined # FOO_SUBSYSTEM

demenu

In this case, it's probably better to get rid of the menu and turn FOO_SUBSYSTEM into a menuconfig symbol:

menuconfig FOO_SUBSYSTEM
  bool "Foo subsystem"

if FOO_SUBSYSTEM

  config FOO_FEATURE_1
    bool "Foo feature 1"

  config FOO_FEATURE_2
    bool "Foo feature 2"

  config FOO_FREQUENCY
    int "Foo frequency"

... lots of other FOO-related symbols

defined # FOO_SUBSYSTEM

In the menuconfig interface, this will be displayed as follows:

[*] Foo subsystem --->

Note that making a symbol without children a menuconfig is meaningless. It should be avoided, because it looks identical to a symbol with all children invisible:

[*] I have no children ----
[*] All my children are invisible ----

Commas in macro arguments

Kconfig uses commas to separate macro arguments. This means a construct like this will fail:

config FOO
  bool
default y if $(dt_chosen_enabled,"zephyr,bar")

To solve this problem, create a variable with the text and use this variable as argument, as follows:

DT_CHOSEN_ZEPHYR_BAR := zephyr,bar

config FOO
  bool
default y if $(dt_chosen_enabled, $(DT_CHOSEN_ZEPHYR_BAR))
Checking changes in menuconfig/guiconfig

When adding new symbols or making other changes to Kconfig files, it is a good idea to look up the symbols in menuconfig or guiconfig afterwards. To get to a symbol quickly, use the jump-to feature (press `/`).

Here are some things to check:

• Are the symbols placed in a good spot? Check that they appear in a menu where they make sense, close to related symbols.
  If one symbol depends on another, then it's often a good idea to place it right after the symbol it depends on. It will then be shown indented relative to the symbol it depends on in the menuconfig interface, and in a separate menu rooted at the symbol in guiconfig. This also works if several symbols are placed after the symbol they depend on.

• Is it easy to guess what the symbols do from their prompts?

• If many symbols are added, do all combinations of values they can be set to make sense?
  For example, if two symbols FOO_SUPPORT and NO_FOO_SUPPORT are added, and both can be enabled at the same time, then that makes a nonsensical configuration. In this case, it's probably better to have a single FOO_SUPPORT symbol.

• Are there any duplicated dependencies?
  This can be checked by selecting a symbol and pressing `?` to view the symbol information. If there are duplicated dependencies, then use the Included via ... path shown in the symbol information to figure out where they come from.

Checking changes with scripts/kconfig/lint.py

After you make Kconfig changes, you can use the scripts/kconfig/lint.py script to check for some potential issues, like unused symbols and symbols that are impossible to enable. Use `--help` to see available options.

Some checks are necessarily a bit heuristic, so a symbol being flagged by a check does not necessarily mean there's a problem. If a check returns a false positive e.g. due to token pasting in C (CONFIG_FOO_##index##_BAR), just ignore it.

When investigating an unknown symbol FOO_BAR, it is a good idea to run `git grep FOO_BAR` to look for references. It is also a good idea to search for some components of the symbol name with e.g. `git grep FOO` and `git grep BAR`, as it can help uncover token pasting.

Style recommendations and shorthands

This section gives some style recommendations and explains some common Kconfig shorthands.

Factoring out common dependencies  If a sequence of symbols/choices share a common dependency, the dependency can be factored out with an `if`.

As an example, consider the following code:

```c
config FOO
    bool "Foo"
    depends on DEP

config BAR
    bool "Bar"
    depends on DEP
```
(continues on next page)
choice
    prompt "Choice"
    depends on DEP

config BAZ
    bool "Baz"

config QAZ
    bool "Qaz"

endchoice

Here, the DEP dependency can be factored out like this:

if DEP

config FOO
    bool "Foo"

config BAR
    bool "Bar"

choice
    prompt "Choice"

config BAZ
    bool "Baz"

config QAZ
    bool "Qaz"

endchoice
endif # DEP

Note: Internally, the second version of the code is transformed into the first.

If a sequence of symbols/choices with shared dependencies are all in the same menu, the dependency can be put on the menu itself:

menu "Foo features"
    depends on FOO_SUPPORT

config FOO_FEATURE_1
    bool "Foo feature 1"

config FOO_FEATURE_2
    bool "Foo feature 2"

endmenu

If FOO_SUPPORT is n, the entire menu disappears.
Redundant defaults  bool symbols implicitly default to n, and string symbols implicitly default to the empty string. Therefore, default n and default "" are (almost) always redundant.

The recommended style in Zephyr is to skip redundant defaults for bool and string symbols. That also generates clearer documentation: (Implicitly defaults to n instead of n if <dependencies, possibly inherited>).

Defaults should always be given for int and hex symbols, however, as they implicitly default to the empty string. This is partly for compatibility with the C Kconfig tools, though an implicit 0 default might be less likely to be what was intended compared to other symbol types as well.

The one case where default n/default "" is not redundant is when defining a symbol in multiple locations and wanting to override e.g. a default y on a later definition. Note that a default n does not override a previously defined default y.

That is, FOO will be set to n in the example below. If the default n was omitted in the first definition, FOO would have been set to y.

```plaintext
config FOO
  bool " foo"
  default n

config FOO
  bool " foo"
  default y
```

In the following example FOO will get the value y.

```plaintext
config FOO
  bool " foo"
  default y

config FOO
  bool " foo"
  default n
```

Common Kconfig shorthands  Kconfig has two shorthands that deal with prompts and defaults.

- `<type> "prompt"` is a shorthand for giving a symbol/choice a type and a prompt at the same time. These two definitions are equal:

```plaintext
config FOO
  bool " foo"
```

```plaintext
config FOO
  bool
  prompt " foo"
```

The first style, with the shorthand, is preferred in Zephyr.

- `def_<type> <value>` is a shorthand for giving a type and a value at the same time. These two definitions are equal:

```plaintext
config FOO
  def_bool BAR && BAZ
```

```plaintext
config FOO
  bool
  default BAR && BAZ
```
Using both the `<type> "prompt"` and the `def_<type> <value>` shorthand in the same definition is redundant, since it gives the type twice.

The `def_<type> <value>` shorthand is generally only useful for symbols without prompts, and somewhat obscure.

**Note:** For a symbol defined in multiple locations (e.g., in a `Kconfig.defconfig` file in Zephyr), it is best to only give the symbol type for the “base” definition of the symbol, and to use default (instead of `def_<type> value`) for the remaining definitions. That way, if the base definition of the symbol is removed, the symbol ends up without a type, which generates a warning that points to the other definitions. That makes the extra definitions easier to discover and remove.

**Prompt strings** For a Kconfig symbol that enables a driver/subsystem FOO, consider having just “Foo” as the prompt, instead of “Enable Foo support” or the like. It will usually be clear in the context of an option that can be toggled on/off, and makes things consistent.

**Header comments and other nits** A few formatting nits, to help keep things consistent:

- Use this format for any header comments at the top of `Kconfig` files:

  ```
  # <Overview of symbols defined in the file, preferably in plain English>
  (Blank line)
  # Copyright (c) 2019 ...
  # SPDX-License-Identifier: <License>
  (Blank line)
  (Kconfig definitions)
  ```

- Format comments as `# Comment` rather than `#Comment`
- Put a blank line before/after each top-level `if` and `endif`
- Use a single tab for each indentation
- Indent help text with two extra spaces

**Lesser-known/used Kconfig features**

This section lists some more obscure Kconfig behaviors and features that might still come in handy.

**The `imply` statement** The `imply` statement is similar to `select`, but respects dependencies and doesn’t force a value. For example, the following code could be used to enable USB keyboard support by default on the FOO SoC, while still allowing the user to turn it off:

```c
config SOC_FOO
    bool "FOO SoC"
    imply USB_KEYBOARD

...  

cfg USB_KEYBOARD
    bool "USB keyboard support"
```

`imply` acts like a suggestion, whereas `select` forces a value.
Optional prompts   A condition can be put on a symbol's prompt to make it optionally configurable by the user. For example, a value MASK that's hardcoded to 0xFF on some boards and configurable on others could be expressed as follows:

```plaintext
config MASK
    hex "Bitmask" if HAS_CONFIGURABLE_MASK
    default 0xFF
```

**Note:** This is short for the following:

```plaintext
config MASK
    hex
    prompt "Bitmask" if HAS_CONFIGURABLE_MASK
    default 0xFF
```

The HAS_CONFIGURABLE_MASK helper symbol would get selected by boards to indicate that MASK is configurable. When MASK is configurable, it will also default to 0xFF.

Optional choices   Defining a choice with the optional keyword allows the whole choice to be toggled off to select none of the symbols:

```plaintext
choice
    prompt "Use legacy protocol"
    optional

config LEGACY_PROTOCOL_1
    bool "Legacy protocol 1"

config LEGACY_PROTOCOL_2
    bool "Legacy protocol 2"
endchoice
```

In the menuconfig interface, this will be displayed e.g. as [*] Use legacy protocol (Legacy protocol 1) --->, where the choice can be toggled off to enable neither of the symbols.

Visible if conditions   Putting a visible if condition on a menu hides the menu and all the symbols within it, while still allowing symbol default values to kick in.

As a motivating example, consider the following code:

```plaintext
menu "Foo subsystem"
    depends on HAS_CONFIGURABLE_FOO

config FOO_SETTING_1
    int "Foo setting 1"
    default 1

config FOO_SETTING_2
    int "Foo setting 2"
    default 2
endmenu
```

When HAS_CONFIGURABLE_FOO is n, no configuration output is generated for FOO_SETTING_1 and FOO_SETTING_2, as the code above is logically equivalent to the following code:
config FOO_SETTING_1
    int "Foo setting 1"
    default 1
    depends on HAS_CONFIGURABLE_FOO

config FOO_SETTING_2
    int "Foo setting 2"
    default 2
    depends on HAS_CONFIGURABLE_FOO

If we want the symbols to still get their default values even when HAS_CONFIGURABLE_FOO is n, but not be configurable by the user, then we can use visible if instead:

menu "Foo subsystem"
    visible if HAS_CONFIGURABLE_FOO

config FOO_SETTING_1
    int "Foo setting 1"
    default 1

config FOO_SETTING_2
    int "Foo setting 2"
    default 2
endmenu

This is logically equivalent to the following:

config FOO_SETTING_1
    int "Foo setting 1" if HAS_CONFIGURABLE_FOO
    default 1

config FOO_SETTING_2
    int "Foo setting 2" if HAS_CONFIGURABLE_FOO
    default 2

Note: See the optional prompts section for the meaning of the conditions on the prompts.

When HAS_CONFIGURABLE is n, we now get the following configuration output for the symbols, instead of no output:

...  
CONFIG_FOO_SETTING_1=1  
CONFIG_FOO_SETTING_2=2  
...

Other resources

The Intro to symbol values section in the Kconfiglib docstring goes over how symbols values are calculated in more detail.

5.3.4 Custom Kconfig Preprocessor Functions

Kconfiglib supports custom Kconfig preprocessor functions written in Python. These functions are defined in scripts/kconfig/kconfigfunctions.py.
Most of the custom preprocessor functions are used to get devicetree information into Kconfig. For example, the default value of a Kconfig symbol can be fetched from a devicetree `reg` property.

### Devicetree-related Functions

The functions listed below are used to get devicetree information into Kconfig. See the Python docstrings in `scripts/kconfig/kconfigfunctions.py` for detailed documentation.

The `_int` version of each function returns the value as a decimal integer, while the `_hex` version returns a hexadecimal value starting with `0x`.

```text
$(dt_has_compat,<compatible string>)
$(dt_compat_enabled,<compatible string>)
$(dt_compat_on_bus,<compatible string>,<bus>)
$(dt_chosen_label,<property in /chosen>)
$(dt_chosen_enabled,<property in /chosen>)
$(dt_chosen_path,<property in /chosen>)
$(dt_chosen_has_compat,<property in /chosen>)
$(dt_path_enabled,<node path>)
$(dt_alias_enabled,<node alias>)
$(dt_nodelabel_enabled,<node label>)
$(dt_nodelabel_enabled_with_compat,<node label>,<compatible string>)
$(dt_chosen_reg_addr_int,<property in /chosen>[,[<index>,<unit>]])
$(dt_chosen_reg_addr_hex,<property in /chosen>[,[<index>,<unit>]])
$(dt_chosen_reg_size_int,<property in /chosen>[,[<index>,<unit>]])
$(dt_chosen_reg_size_hex,<property in /chosen>[,[<index>,<unit>]])
$(dt_node_reg_addr_int,<node path>[,[<index>,<unit>]])
$(dt_node_reg_addr_hex,<node path>[,[<index>,<unit>]])
$(dt_node_reg_size_int,<node path>[,[<index>,<unit>]])
$(dt_node_reg_size_hex,<node path>[,[<index>,<unit>]])
$(dt_compat_enabled,<compatible string>)
$(dt_chosen_enabled,<property in /chosen>)
$(dt_nodelabel_bool_prop,<node label>,<prop>)
$(dt_nodelabel_has_prop,<node label>,<prop>)
$(dt_node_has_prop,<node path>,<prop>)
$(dt_nodelabel_has_prop,<node label>,<prop>)
$(dt_node_int_prop_int,<node path>,<prop>[,[<unit>]])
$(dt_node_int_prop_hex,<node path>,<prop>[,[<unit>]])
$(dt_node_str_prop_equals,<node path>,<prop>,<value>)
$(dt_nodelabel_has_compat,<node label>,<compatible string>)
$(dt_node_has_compat,<node path>,<compatible string>)
$(dt_nodelabel_path,<node label>)
$(dt_node_parent,<node path>)
$(shields_list_contains,<shield name>)
```

### Example Usage

Assume that the devicetree for some board looks like this:

```text
{
  soc {
    #address-cells = <1>;
    #size-cells = <1>;
    spi0: spi@10014000 {
```
compatible = "sifive,spi0";
reg = <0x10014000 0x1000 0x20010000 0x3c0900>;
reg-names = "control", "mem";

The second entry in reg in spi@1001400 (<0x20010000 0x3c0900>) corresponds to mem, and has the address 0x20010000. This address can be inserted into Kconfig as follows:

```c
config FLASH_BASE_ADDRESS
    default $(dt_node_reg_addr_hex,/soc/spi@1001400,1)
```

After preprocessor expansion, this turns into the definition below:

```c
config FLASH_BASE_ADDRESS
    default 0x20010000
```

### 5.3.5 Kconfig extensions

Zephyr uses the Kconfiglib implementation of Kconfig, which includes some Kconfig extensions:

- Environment variables in source statements are expanded directly, meaning no “bounce” symbols with option env="ENV_VAR" need to be defined.

Note: option env has been removed from the C tools as of Linux 4.18 as well.

The recommended syntax for referencing environment variables is $(F00) rather than $F00. This uses the new Kconfig preprocessor. The $F00 syntax for expanding environment variables is only supported for backwards compatibility.

- The source statement supports glob patterns and includes each matching file. A pattern is required to match at least one file.

Consider the following example:

```c
source "foo/bar/*/Kconfig"
```

If the pattern foo/bar/*/Kconfig matches the files foo/bar/baz/Kconfig and foo/bar/qaz/Kconfig, the statement above is equivalent to the following two source statements:

```c
source "foo/bar/baz/Kconfig"
source "foo/bar/qaz/Kconfig"
```

If no files match the pattern, an error is generated.

The wildcard patterns accepted are the same as for the Python glob module.

For cases where it's okay for a pattern to match no files (or for a plain filename to not exist), a separate osource (optional source) statement is available. osource is a no-op if no file matches.

Note: source and osource are analogous to include and -include in Make.

- An rsource statement is available for including files specified with a relative path. The path is relative to the directory of the Kconfig file that contains the rsource statement.

As an example, assume that foo/Kconfig is the top-level Kconfig file, and that foo/bar/Kconfig has the following statements:
source "qaz/Kconfig1"
rsresource "qaz/Kconfig2"

This will include the two files foo/qaz/Kconfig1 and foo/bar/qaz/Kconfig2.
rsresource can be used to create Kconfig “subtrees” that can be moved around freely.
rsresource also supports glob patterns.
A drawback of rsresource is that it can make it harder to figure out where a file gets included, so only
use it if you need it.

• An orsource statement is available that combines osource and rsresource.
For example, the following statement will include Kconfig1 and Kconfig2 from the current directory (if they exist):
ORSOURCE "Kconfig[12]"

• def_int, def_hex, and def_string keywords are available, analogous to def_bool. These set the
type and add a default at the same time.

Users interested in optimizing their configuration for security should refer to the Zephyr Security Guide’s
section on the Hardening Tool.

5.4 Zephyr CMake Package

The Zephyr CMake package is a convenient way to create a Zephyr-based application.

**Note:** The Application types section introduces the application types used in this page.

The Zephyr CMake package ensures that CMake can automatically select a Zephyr installation to use for
building the application, whether it is a Zephyr repository application, a Zephyr workspace application, or
a Zephyr freestanding application.

When developing a Zephyr-based application, then a developer simply needs to write
find_package(Zephyr)
in the beginning of the application CMakeLists.txt file.

To use the Zephyr CMake package it must first be exported to the CMake user package registry. This is
means creating a reference to the current Zephyr installation inside the CMake user package registry.

**Ubuntu**
In Linux, the CMake user package registry is found in:

```
~/.cmake/packages/Zephyr
```

**macOS**
In macOS, the CMake user package registry is found in:

```
~/.cmake/packages/Zephyr
```

**Windows**
In Windows, the CMake user package registry is found in:

```
HKEY_CURRENT_USER\Software\Kitware\CMake\Packages\Zephyr
```

The Zephyr CMake package allows CMake to automatically find a Zephyr base. One or more Zephyr
installations must be exported. Exporting multiple Zephyr installations may be useful when developing
or testing Zephyr freestanding applications, Zephyr workspace application with vendor forks, etc..
5.4.1 Zephyr CMake package export (west)

When installing Zephyr using `west` then it is recommended to export Zephyr using `west zephyr-export`.

5.4.2 Zephyr CMake package export (without west)

Zephyr CMake package is exported to the CMake user package registry using the following commands:

```bash
cmake -P <PATH-TO-ZEPHYR>/share/zephyr-package/cmake/zephyr_export.cmake
```

This will export the current Zephyr to the CMake user package registry.

To also export the Zephyr Unitest CMake package, run the following command in addition:

```bash
cmake -P <PATH-TO-ZEPHYR>/share/zephyrunittest-package/cmake/zephyr_export.cmake
```

5.4.3 Zephyr Base Environment Setting

The Zephyr CMake package search functionality allows for explicitly specifying a Zephyr base using an environment variable.

To do this, use the following `find_package()` syntax:

```bash
find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
```

This syntax instructs CMake to first search for Zephyr using the Zephyr base environment setting `ZEPHYR_BASE` and then use the normal search paths.

5.4.4 Zephyr CMake Package Search Order

When Zephyr base environment setting is not used for searching, the Zephyr installation matching the following criteria will be used:

- A Zephyr repository application will use the Zephyr in which it is located. For example:

  ```
  <projects>/zephyr-workspace/zephyr
    └── samples
        └── hello_world
  ```

  in this example, `hello_world` will use `<projects>/zephyr-workspace/zephyr`.

- Zephyr workspace application will use the Zephyr that share the same workspace. For example:

  ```
  <projects>/zephyr-workspace
    └── zephyr
        └── ...
        └── my_applications
            └── my_first_app
  ```

  in this example, `my_first_app` will use `<projects>/zephyr-workspace/zephyr` as this Zephyr is located in the same workspace as the Zephyr workspace application.

  **Note:** The root of a Zephyr workspace is identical to `west topdir` if the workspace was installed using `west`.

- Zephyr freestanding application will use the Zephyr registered in the CMake user package registry. For example:
in this example, only `<projects>/zephyr-workspace-2/zephyr` is exported to the CMake package registry and therefore this Zephyr will be used by the Zephyr freestanding application `<home>/app`.

If user wants to test the application with `<projects>/zephyr-workspace-1/zephyr`, this can be done by using the Zephyr Base environment setting, meaning set ZEPHYR_BASE=``<projects>/zephyr-workspace-1/zephyr` before running CMake.

**Note:** The Zephyr package selected on the first CMake invocation will be used for all subsequent builds. To change the Zephyr package, for example to test the application using Zephyr base environment setting, then it is necessary to do a pristine build first (See Rebuilding an Application).

### 5.4.5 Zephyr CMake Package Version

When writing an application then it is possible to specify a Zephyr version number x.y.z that must be used in order to build the application.

Specifying a version is especially useful for a Zephyr freestanding application as it ensures the application is built with a minimal Zephyr version.

It also helps CMake to select the correct Zephyr to use for building, when there are multiple Zephyr installations in the system.

For example:

```cmake
find_package(Zephyr 2.2.0)
pject(app)
```

will require app to be built with Zephyr 2.2.0 as minimum. CMake will search all exported candidates to find a Zephyr installation which matches this version criteria.

Thus it is possible to have multiple Zephyr installations and have CMake automatically select between them based on the version number provided, see CMake package version for details.

For example:

```
<projects>/zephyr-workspace-2.a
  zephyr                     (Exported to CMake)
<projects>/zephyr-workspace-2.b
  zephyr                     (Exported to CMake)
<home>/app
  CMakeLists.txt
  prj.conf
  src
  main.c
```

**5.4. Zephyr CMake Package**
in this case, there are two released versions of Zephyr installed at their own workspaces. Workspace 2.a and 2.b, corresponding to the Zephyr version.

To ensure `app` is built with minimum version 2.a the following `find_package` syntax may be used:

```cpp
find_package(Zephyr 2.a)
project(app)
```

Note that both 2.a and 2.b fulfill this requirement.

CMake also supports the keyword `EXACT`, to ensure an exact version is used, if that is required. In this case, the application `CMakeLists.txt` could be written as:

```cpp
find_package(Zephyr 2.a EXACT)
project(app)
```

In case no Zephyr is found which satisfies the version required, as example, the application specifies

```cpp
find_package(Zephyr 2.z)
project(app)
```

then an error similar to below will be printed:

```
Could not find a configuration file for package "Zephyr" that is compatible with requested version "2.z".

The following configuration files were considered but not accepted:

<projects>/zephyr-workspace-2.a/zephyr/share/zephyr-package/cmake/ZephyrConfig.cmake, version: 2.a.0
<projects>/zephyr-workspace-2.b/zephyr/share/zephyr-package/cmake/ZephyrConfig.cmake, version: 2.b.0
```

**Note:** It can also be beneficial to specify a version number for Zephyr repository applications and Zephyr workspace applications. Specifying a version in those cases ensures the application will only build if the Zephyr repository or workspace is matching. This can be useful to avoid accidental builds when only part of a workspace has been updated.

### 5.4.6 Multiple Zephyr Installations (Zephyr workspace)

Testing out a new Zephyr version, while at the same time keeping the existing Zephyr in the workspace untouched is sometimes beneficial.

Or having both an upstream Zephyr, Vendor specific, and a custom Zephyr in same workspace.

For example:

```
<projects>/zephyr-workspace
  └── zephyr
      ├── zephyr-vendor
      ├── zephyr-custom
      └── ...
  └── my_applications
      └── my_first_app
```

in this setup, `find_package(Zephyr)` has the following order of precedence for selecting which Zephyr to use:

- Project name: `zephyr`
First project, when Zephyr projects are ordered lexicographical, in this case.

- zephyr-custom
- zephyr-vendor

This means that my_first_app will use `<projects>/zephyr-workspace/zephyr`.

It is possible to specify a Zephyr preference list in the application.

A Zephyr preference list can be specified as:

```cmake
set(ZEPHYR_PREFER "zephyr-custom" "zephyr-vendor")
find_package(Zephyr)
project(my_first_app)
```

the ZEPHYR_PREFER is a list, allowing for multiple Zephyrs. If a Zephyr is specified in the list, but not found in the system, it is simply ignored and find_package(Zephyr) will continue to the next candidate.

This allows for temporary creation of a new Zephyr release to be tested, without touching current Zephyr. When testing is done, the zephyr-test folder can simply be removed. Such a CMakeLists.txt could look as:

```cmake
set(ZEPHYR_PREFER "zephyr-test")
find_package(Zephyr)
project(my_first_app)
```

### 5.4.7 Zephyr Build Configuration CMake package

The Zephyr Build Configuration CMake package provides a possibility for a Zephyr based project to control Zephyr build settings in a generic way.

It is similar to the per-user .zephyrrc file that can be used to set Environment Variables, but it sets CMake variables instead. It also allows you to automatically share the build configuration among all users through the project repository. It also allows more advanced use cases, such as loading of additional CMake boilerplate code.

The Zephyr Build Configuration CMake package will be loaded in the Zephyr boilerplate code after initial properties and ZEPHYR_BASE has been defined, but before CMake code execution. This allows the Zephyr Build Configuration CMake package to setup or extend properties such as: DTS_ROOT, BOARD_ROOT, TOOLCHAIN_ROOT / other toolchain setup, fixed overlays, and any other property that can be controlled. It also allows inclusion of additional boilerplate code.

To provide a Zephyr Build Configuration CMake package, create ZephyrBuildConfig.cmake and place it in a Zephyr workspace top-level folder as:

```shell
<projects>/zephyr-workspace
  ├── zephyr
  │    └── ...  
  │         └── zephyr application (can be named anything)
  │                └── share/zephyrbuild-package/cmake/ZephyrBuildConfig.cmake
```

The Zephyr Build Configuration CMake package will not search in any CMake default search paths, and thus cannot be installed in the CMake package registry. There will be no version checking on the Zephyr Build Configuration package.

**Note:** share/zephyrbuild-package/cmake/ZephyrBuildConfig.cmake follows the same folder structure as the Zephyr CMake package.
It is possible to place ZephyrBuildConfig.cmake directly in a `<zephyr application>/cmake` folder or another folder, as long as that folder is honoring the CMake package search algorithm.

A sample ZephyrBuildConfig.cmake can be seen below.

```cmake
# ZephyrBuildConfig.cmake sample code
# To ensure final path is absolute and does not contain ../.. in variable.
get_filename_component(APPLICATION_PROJECT_DIR '${CMAKE_CURRENT_LIST_DIR}/../../..' ABSOLUTE)

# Add this project to list of board roots
list(APPEND BOARD_ROOT ${(APPLICATION_PROJECT_DIR})}

# Default to GNU Arm Embedded toolchain if no toolchain is set
if(NOT ENV{ZEPHYR_TOOLCHAIN_VARIANT})
  set(ZEPHYR_TOOLCHAIN_VARIANT gnuarmemb)
  find_program(GNU_ARM_GCC arm-none-eabi-gcc)
  if(NOT ${GNU_ARM_GCC} STREQUAL GNU_ARM_GCC-NOTFOUND)
    # The toolchain root is located above the path to the compiler.
    get_filename_component(GNUARMEMB_TOOLCHAIN_PATH ${GNU_ARM_GCC}/../..ABSOLUTE)
  endif()
endif()
endif()
```

### 5.4.8 Zephyr Build Configuration CMake package (Freestanding application)

The Zephyr Build Configuration CMake package can be located outside a Zephyr workspace, for example located with a Zephyr freestanding application.

Create the build configuration as described in the previous section, and then refer to the location of your Zephyr Build Configuration CMake package using the CMake variable ZephyrBuildConfiguration_ROOT.

1. At the CMake command line, like this:
   ```
   cmake -DZephyrBuildConfiguration_ROOT=<path-to-build-config> ...
   ```

2. At the top of your application's top level `CMakeLists.txt`, like this:
   ```
   set(ZephyrBuildConfiguration_ROOT <path-to-build-config>)
   find_package(Zephyr REQUIRED HINTS $ENV{ZEPHYR_BASE})
   ```
   If you choose this option, make sure to set the variable **before** calling `find_package(Zephyr ...)`, as shown above.

3. In a separate `CMake` script which is pre-loaded to populate the CMake cache, like this:
   ```
   # Put this in a file with a name like "zephyr-settings.cmake"
   set(ZephyrBuildConfiguration_ROOT <path-to-build-config>)
   CACHE STRING "pre-cached build config"
   ```

   You can tell the build system to use this file by adding `-C zephyr-settings.cmake` to your CMake command line. This principle is useful when not using `west` as both this setting and Zephyr modules can be specified using the same file. See Zephyr module **Without West.**
5.4.9 Zephyr CMake package source code

The Zephyr CMake package source code in share/zephyr-package/cmake and share/zephyrunittest-package/cmake contains the CMake config package which is used by the CMake find_package function. It also contains code for exporting Zephyr as a CMake config package.

The following is an overview of the files in these directories:

ZephyrConfigVersion.cmake
The Zephyr package version file. This file is called by CMake to determine if this installation fulfills the requirements specified by user when calling find_package(Zephyr ...). It is also responsible for detection of Zephyr repository or workspace only installations.

ZephyrUnittestConfigVersion.cmake
Same responsibility as ZephyrConfigVersion.cmake, but for unit tests. Includes ZephyrConfigVersion.cmake.

ZephyrConfig.cmake
The Zephyr package file. This file is called by CMake to for the package meeting which fulfills the requirements specified by user when calling find_package(Zephyr ...). This file is responsible for sourcing of boilerplate code.

ZephyrUnittestConfig.cmake
Same responsibility as ZephyrConfig.cmake, but for unit tests. Includes ZephyrConfig.cmake.

zephyr_package_search.cmake
Common file used for detection of Zephyr repository and workspace candidates. Used by ZephyrConfigVersion.cmake and ZephyrConfig.cmake for common code.

zephyr_export.cmake
See Zephyr CMake package export (without west).

5.5 Sysbuild (System build)

Sysbuild is a higher-level build system that can be used to combine multiple other build systems together. It is a higher-level layer that combines one or more Zephyr build systems and optional additional build systems into a hierarchical build system.

For example, you can use sysbuild to build a Zephyr application together with the MCUboot bootloader, flash them both onto your device, and debug the results.

Sysbuild works by configuring and building at least a Zephyr application and, optionally, as many additional projects as you want. The additional projects can be either Zephyr applications or other types of builds you want to run.

Like Zephyr's build system, sysbuild is written in CMake and uses Kconfig.

5.5.1 Definitions

The following are some key concepts used in this document:

Single-image build
When sysbuild is used to create and manage just one Zephyr application's build system.

Multi-image build
When sysbuild is used to manage multiple build systems. The word “image” is used because your main goal is usually to generate the binaries of the firmware application images from each build system.

Domain
Every Zephyr CMake build system managed by sysbuild.
Multi-domain
When more than one Zephyr CMake build system (domain) is managed by sysbuild.

5.5.2 Architectural Overview
This figure is an overview of sysbuild’s inputs, outputs, and user interfaces:

The following are some key sysbuild features indicated in this figure:
- You can run sysbuild either with `west build` or directly via `cmake`.
- You can use sysbuild to generate application images from each build system, shown above as ELF, BIN, and HEX files.
- You can configure sysbuild or any of the build systems it manages using various configuration variables. These variables are namedpaced so that sysbuild can direct them to the right build system. In some cases, such as the `BOARD` variable, these are shared among multiple build systems.
- Sysbuild itself is also configured using Kconfig. For example, you can instruct sysbuild to build the MCUboot bootloader, as well as to build and link your main Zephyr application as an MCUboot child image, using sysbuild’s Kconfig files.
- Sysbuild integrates with west’s Building, Flashing and Debugging commands. It does this by managing the Flash and debug runners, and specifically the `runners.yaml` files that each Zephyr build system will contain. These are packed into a global view of how to flash and debug each build system in a `domains.yaml` file generated and managed by sysbuild.

5.5.3 Building with sysbuild
As mentioned above, you can run sysbuild via `west build` or `cmake`.

`west build`
Here is an example. For details, see *Sysbuild (multi-domain builds)* in the *west build* documentation.

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

**Tip:** To configure *west build* to use --sysbuild by default from now on, run:

```
w west config build.sysbuild True
```

Since sysbuild supports both single- and multi-image builds, this lets you use sysbuild all the time, without worrying about what type of build you are running.

To turn this off, run this before generating your build system:

```
w west config build.sysbuild False
```

To turn this off for just one *west build* command, run:

```
w west build --no-sysbuild ...
```

```
w west build
```

```
w west build -b reel_board --sysbuild samples/hello_world --DSB_CONFIG_BOOTLOADER_MCUBOOT=y -DCONFIG_DEBUG_OPTIMIZATIONS=y -Dmcuboot_DEBUG_OPTIMIZATIONS=y
```

```
w cmake
```

```
w cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world share/sysbuild
```

```
w ninja -Cbuild
```

To use sysbuild directly with CMake, you must specify the sysbuild project as the source folder, and give -DAPP_DIR=<path-to-sample> as an extra CMake argument. APP_DIR is the path to the main Zephyr application managed by sysbuild.

### 5.5.4 Configuration namespaces

When building a single Zephyr application without sysbuild, all CMake cache settings and Kconfig build options given on the command line as -D<var>=<value> or -DCONFIG_<var>=<value> are handled by the Zephyr build system.

However, when sysbuild combines multiple Zephyr build systems, there could be Kconfig settings exclusive to sysbuild (and not used by any of the applications). To handle this, sysbuild has namespaces for configuration variables. You can use these namespaces to direct settings either to sysbuild itself or to a specific Zephyr application managed by sysbuild using the information in these sections.

The following example shows how to build hello_world with MCUboot enabled, applying to both images debug optimizations:

```
w west build
```

```
w west build -b reel_board --sysbuild samples/hello_world --DSB_CONFIG_BOOTLOADER_MCUBOOT=y -DCONFIG_DEBUG_OPTIMIZATIONS=y -Dmcuboot_DEBUG_OPTIMIZATIONS=y
```

```
w cmake
```

```
w cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONFIG_BOOTLOADER_MCUBOOT=y -DCONFIG_DEBUG_OPTIMIZATIONS=y -Dmcuboot_DEBUG_OPTIMIZATIONS=y -Dshare/sysbuild
```

```
w ninja -Cbuild
```

See the following subsections for more information.
CMake variable namespacing

CMake variable settings can be passed to CMake using \(-D<var>=<value>\) on the command line. You can also set Kconfig options via CMake as \(-DCONFIG_\_<var>=<value>\) or \(-D<namespace>_CONFIG_\_<var>=<value>\).

Since sysbuild is the entry point for the build system, and sysbuild is written in CMake, all CMake variables are first processed by sysbuild.

Sysbuild creates a namespace for each domain. The namespace prefix is the domain's application name. See Adding Zephyr applications to sysbuild for more information.

To set the variable <var> in the namespace <namespace>, use this syntax:
\[-D<namespace>_<var>=<value>\]

For example, to set the CMake variable FOO in the my_sample application build system to the value BAR, run the following commands:

```
west build
west build --sysbuild ... -- -Dmy_sample_FOO=BAR
```

cmake

cmake -Dmy_sample_FOO=BAR ...

Kconfig namespacing

To set the sysbuild Kconfig option <var> to the value <value>, use this syntax:
\[-DSB_CONFIG_\_<var>=<value>\]

In the previous example, SB_CONFIG is the namespace prefix for sysbuild's Kconfig options. To set a Zephyr application's Kconfig option instead, use this syntax:
\[-D<namespace>_CONFIG_\_<var>=<value>\]

In the previous example, <namespace> is the application name discussed above in CMake variable namespacing.

For example, to set the Kconfig option FOO in the my_sample application build system to the value BAR, run the following commands:

```
west build
west build --sysbuild ... -- -Dmy_sample_CONFIG_FOO=BAR
```

cmake

cmake -Dmy_sample_CONFIG_FOO=BAR ...

Tip: When no <namespace> is used, the Kconfig setting is passed to the main Zephyr application my_sample.

This means that passing \(-DCONFIG_\_<var>=<value>\) and \(-Dmy_sample_CONFIG_\_<var>=<value>\) are equivalent.

This allows you to build the same application with or without sysbuild using the same syntax for setting Kconfig values at CMake time. For example, the following commands will work in the same way:
5.5.5 Sysbuild flashing using `west flash`

You can use `west flash` to flash applications with sysbuild. When invoking `west flash` on a build consisting of multiple images, each image is flashed in sequence. Extra arguments such as `--runner jlink` are passed to each invocation. For more details, see `Multi-domain flashing`.

5.5.6 Sysbuild debugging using `west debug`

You can use `west debug` to debug the main application, whether you are using sysbuild or not. Just follow the existing `west debug` guide to debug the main sample.

To debug a different domain (Zephyr application), such as mcuboot, use the `--domain` argument, as follows:

```
wester debug --domain mcuboot
```

For more details, see `Multi-domain debugging`.

5.5.7 Building a sample with MCUboot

Sysbuild supports MCUboot natively.

To build a sample like `hello_world` with MCUboot, enable MCUboot and build and flash the sample as follows:

```
wester build
```

```
wester build -b reel_board --sysbuild samples/hello_world -- -DSB_CONFIG_BOOTLOADER_MCUBOOT=y
```

```
cmake
```

```
cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONFIG_BOOTLOADER_MCUBOOT=y share/sysbuild
```

```
ninja -Cbuild
```

This builds `hello_world` and `mcuboot` for the `reel_board`, and then flashes both the `mcuboot` and `hello_world` application images to the board.

More detailed information regarding the use of MCUboot with Zephyr can be found in the [MCUboot with Zephyr documentation page](https://mcuboot.com/documentation) on the MCUboot website.

**Note:** MCUBoot default configuration will perform a full chip erase when flashed. This can be controlled through the MCUBoot Kconfig option `CONFIG_ZEPHYR_TRY_MASS_ERASE`. If this option is enabled, then flashing only MCUBoot, for example using `west flash --domain mcuboot`, may erase the entire flash, including the main application image.
5.5.8 Sysbuild Kconfig file

You can set sysbuild's Kconfig options for a single application using configuration files. By default, sysbuild looks for a configuration file named `sysbuild.conf` in the application top-level directory.

In the following example, there is a `sysbuild.conf` file that enables building and flashing with MCUboot whenever sysbuild is used:

```bash
<html>/application
  ├── CMakeLists.txt
  │    └── prj.conf
  └── sysbuild.conf
```

```
SB_CONFIG_BOOTLOADER_MCUBOOT=y
```

You can set a configuration file to use with the `-DSB_CONF_FILE=<sysbuild-conf-file>` CMake build setting.

For example, you can create `sysbuild-mcuboot.conf` and then specify this file when building with sysbuild, as follows:

```bash
west build
```

```bash
west build -b reel_board --sysbuild samples/hello_world -- -DSB_CONF_FILE=sysbuild-
  mcuboot.conf
```

```bash
cmake
```

```bash
cmake -Bbuild -GNinja -DBOARD=reel_board -DAPP_DIR=samples/hello_world -DSB_CONF_-
  FILE=sysbuild-mcuboot.conf share/sysbuild
```

```
ninja -Cbuild
```

5.5.9 Adding Zephyr applications to sysbuild

You can use the `ExternalZephyrProject_Add()` function to add Zephyr applications as sysbuild domains. Call this CMake function from your application's `sysbuild.cmake` file, or any other CMake file you know will run as part sysbuild CMake invocation.

Targeting the same board

To include `my_sample` as another sysbuild domain, targeting the same board as the main image, use this example:

```c
ExternalZephyrProject_Add(
    APPLICATION my_sample
    SOURCE_DIR <path-to>/my_sample
)
```

This could be useful, for example, if your board requires you to build and flash an SoC-specific bootloader along with your main application.

Targeting a different board

In sysbuild and Zephyr CMake build system a board may refer to:

- A physical board with a single core SoC.
- A specific core on a physical board with a multi-core SoC, such as nrf5340dk_nrf5340.
A specific SoC on a physical board with multiple SoCs, such as nrf9160dk_nrf9160 and nrf9160dk_nrf52840.

If your main application, for example, is built for mps2_an521, and your helper application must target the mps2_an521_remote board (cpu1), add a CMake function call that is structured as follows:

```cmake
ExternalZephyrProject_Add(
  APPLICATION my_sample
  SOURCE_DIR <path-to>/my_sample
  BOARD mps2_an521_remote
)
```

This could be useful, for example, if your main application requires another helper Zephyr application to be built and flashed alongside it, but the helper runs on another core in your SoC.

**Targeting conditionally using Kconfig**

You can control whether extra applications are included as sysbuild domains using Kconfig.

If the extra application image is specific to the board or an application, you can create two additional files: `sysbuild.cmake` and `Kconfig.sysbuild`.

For an application, this would look like this:

```plaintext
<home>/application
 ├── CMakeLists.txt
 ├── prj.conf
 ├── Kconfig.sysbuild
 └── sysbuild.cmake
```

In the previous example, `sysbuild.cmake` would be structured as follows:

```cmake
if(SB_CONFIG_SECOND_SAMPLE)
  ExternalZephyrProject_Add(
    APPLICATION second_sample
    SOURCE_DIR <path-to>/second_sample
  )
endif()
```

`Kconfig.sysbuild` would be structured as follows:

```cmake
source "sysbuild/Kconfig"
config SECOND_SAMPLE
  bool "Second sample"
  default y
```

This will include `second_sample` by default, while still allowing you to disable it using the Kconfig option `SECOND_SAMPLE`.

For more information on setting sysbuild Kconfig options, see [Kconfig namespace](#).

**Zephyr application configuration**

When adding a Zephyr application to sysbuild, such as MCUboot, then the configuration files from the application (MCUboot) itself will be used.

When integrating multiple applications with each other, then it is often necessary to make adjustments to the configuration of extra images.
Sysbuild gives users the ability of creating Kconfig fragments or devicetree overlays that will be used together with the application's default configuration. Sysbuild also allows users to change Application Configuration Directory in order to give users full control of an image's configuration.

**Zephyr application Kconfig fragment and devicetree overlay**  In the folder of the main application, create a Kconfig fragment or a devicetree overlay under a sysbuild folder, where the name of the file is `<image>.conf` or `<image>.overlay`, for example if your main application includes `my_sample` then create a `sysbuild/my_sample.conf` file or a devicetree overlay `sysbuild/my_sample.overlay`.

A Kconfig fragment could look as:

```
# sysbuild/my_sample.conf
CONFIG_FOO=n
```

**Zephyr application configuration directory** In the folder of the main application, create a new folder under `sysbuild/<image>/`. This folder will then be used as `APPLICATION_CONFIG_DIR` when building `<image>`. As an example, if your main application includes `my_sample` then create a `sysbuild/my_sample/` folder and place any configuration files in there as you would normally do:

```
<home>/application
 └── CMakeLists.txt
     └── prj.conf
         └── sysbuild
             └── my_sample
                 └── prj.conf
                     └── app.overlay
                         └── boards
                             └── <board_A>.conf
                             └── <board_A>.overlay
                             └── <board_B>.conf
                             └── <board_B>.overlay
```

All configuration files under the `sysbuild/my_sample/` folder will now be used when `my_sample` is included in the build, and the default configuration files for `my_sample` will be ignored.

This give you full control on how images are configured when integrating those with application.

### 5.5.10 Adding non-Zephyr applications to sysbuild

You can include non-Zephyr applications in a multi-image build using the standard CMake module ExternalProject. Please refer to the CMake documentation for usage details.

When using ExternalProject, the non-Zephyr application will be built as part of the sysbuild build invocation, but `west flash` or `west debug` will not be aware of the application. Instead, you must manually flash and debug the application.
Chapter 6

Connectivity

6.1 Bluetooth

This section contains information regarding the Bluetooth stack of the Zephyr OS. You can use this information to understand the principles behind the operation of the layers and how they were implemented. Zephyr includes a complete Bluetooth Low Energy stack from application to radio hardware, as well as portions of a Classical Bluetooth (BR/EDR) Host layer.

6.1.1 Overview

- **Supported Features**

Since its inception, Zephyr has had a strong focus on Bluetooth and, in particular, on Bluetooth Low Energy (BLE). Through the contributions of several companies and individuals involved in existing open source implementations of the Bluetooth specification (Linux's BlueZ) as well as the design and development of BLE radio hardware, the protocol stack in Zephyr has grown to be mature and feature-rich, as can be seen in the section below.

**Supported Features**

Zephyr comes integrated with a feature-rich and highly configurable Bluetooth stack.

- Bluetooth 5.0 compliant (ESR10)
  - Highly configurable
    - Features, buffer sizes/counts, stack sizes, etc.
  - Portable to all architectures supported by Zephyr (including big and little endian, alignment flavors and more)
  - Support for all combinations of Host and Controller builds:
    - Controller-only (HCI) over UART, SPI, and USB physical transports
    - Host-only over UART, SPI, and IPM (shared memory)
    - Combined (Host + Controller)
- Bluetooth-SIG qualified
  - Controller on Nordic Semiconductor hardware
Conformance tests run regularly on all layers

- Bluetooth Low Energy Controller support (LE Link Layer)
  - Unlimited role and connection count, all roles supported
  - Concurrent multi-protocol support ready
  - Intelligent scheduling of roles to minimize overlap
  - Portable design to any open BLE radio, currently supports Nordic Semiconductor nRF51 and nRF52, as well as proprietary radios
  - Supports little and big endian architectures, and abstracts the hard real-time specifics so that they can be encapsulated in a hardware-specific module
  - Support for Controller (HCI) builds over different physical transports

- Bluetooth Host support
  - Generic Access Profile (GAP) with all possible LE roles
    * Peripheral & Central
    * Observer & Broadcaster
  - GATT (Generic Attribute Profile)
    * Server (to be a sensor)
    * Client (to connect to sensors)
  - Pairing support, including the Secure Connections feature from Bluetooth 4.2
  - Non-volatile storage support for permanent storage of Bluetooth-specific settings and data
  - Bluetooth mesh support
    * Relay, Friend Node, Low-Power Node (LPN) and GATT Proxy features
    * Both Provisioning bearers supported (PB-ADV & PB-GATT)
    * Highly configurable, fits as small as 16k RAM devices
  - IPSP/6LoWPAN for IPv6 connectivity over Bluetooth LE
    * IPSP node sample application
  - Basic Bluetooth BR/EDR (Classic) support
    * Generic Access Profile (GAP)
    * Logical Link Control and Adaptation Protocol (L2CAP)
    * Serial Port emulation (RFCOMM protocol)
    * Service Discovery Protocol (SDP)
  - Clean HCI driver abstraction
    * 3-Wire (H:5) & 5-Wire (H:4) UART
    * SPI
    * Local controller support as a virtual HCI driver
  - Verified with multiple popular controllers
6.1.2 Bluetooth Stack Architecture

Overview

This page describes the software architecture of Zephyr's Bluetooth protocol stack.

Note: Zephyr supports mainly Bluetooth Low Energy (BLE), the low-power version of the Bluetooth specification. Zephyr also has limited support for portions of the BR/EDR Host. Throughout this architecture document we use BLE interchangeably for Bluetooth except when noted.

BLE Layers

There are 3 main layers that together constitute a full Bluetooth Low Energy protocol stack:

- **Host**: This layer sits right below the application, and is comprised of multiple (non real-time) network and transport protocols enabling applications to communicate with peer devices in a standard and interoperable way.

- **Controller**: The Controller implements the Link Layer (LE LL), the low-level, real-time protocol which provides, in conjunction with the Radio Hardware, standard-interoperable over-the-air communication. The LL schedules packet reception and transmission, guarantees the delivery of data, and handles all the LL control procedures.

- **Radio Hardware**: Hardware implements the required analog and digital baseband functional blocks that permit the Link Layer firmware to send and receive in the 2.4GHz band of the spectrum.

Host Controller Interface

The Bluetooth Specification describes the format in which a Host must communicate with a Controller. This is called the Host Controller Interface (HCI) protocol. HCI can be implemented over a range of different physical transports like UART, SPI, or USB. This protocol defines the commands that a Host can send to a Controller and the events that it can expect in return, and also the format for user and protocol data that needs to go over the air. The HCI ensures that different Host and Controller implementations can communicate in a standard way making it possible to combine Hosts and Controllers from different vendors.

Configurations

The three separate layers of the protocol and the standardized interface make it possible to implement the Host and Controller on different platforms. The two following configurations are commonly used:

- **Single-chip configuration**: In this configuration, a single microcontroller implements all three layers and the application itself. This can also be called a system-on-chip (SoC) implementation. In this case the BLE Host and the BLE Controller communicate directly through function calls and queues in RAM. The Bluetooth specification does not specify how HCI is implemented in this single-chip configuration and so how HCI commands, events, and data flows between the two can be implementation-specific. This configuration is well suited for those applications and designs that require a small footprint and the lowest possible power consumption, since everything runs on a single IC.

- **Dual-chip configuration**: This configuration uses two separate ICs, one running the Application and the Host, and a second one with the Controller and the Radio Hardware. This is sometimes also called a connectivity-chip configuration. This configuration allows for a wider variety of combinations of Hosts when using the Zephyr OS as a Controller. Since HCI ensures interoperability among Host and Controller implementations, including of course Zephyr's very own BLE Host and Controller, users of the Zephyr Controller can choose to use whatever Host running on any platform they prefer. For example, the host can be the Linux BLE Host stack (BlueZ) running on any processor capable of supporting Linux. The Host processor may of course also run Zephyr and the Zephyr OS BLE Host. Conversely, combining an IC running the Zephyr Host with an external Controller that does not run Zephyr is also supported.
**Build Types** The Zephyr software stack as an RTOS is highly configurable, and in particular, the BLE subsystem can be configured in multiple ways during the build process to include only the features and layers that are required to reduce RAM and ROM footprint as well as power consumption. Here's a short list of the different BLE-enabled builds that can be produced from the Zephyr project codebase:

- **Controller-only build**: When built as a BLE Controller, Zephyr includes the Link Layer and a special application. This application is different depending on the physical transport chosen for HCI:
  - hci_uart
  - hci_usb
  - hci_spi
  This application acts as a bridge between the UART, SPI or USB peripherals and the Controller subsystem, listening for HCI commands, sending application data and responding with events and received data. A build of this type sets the following Kconfig option values:
    - CONFIG_BT =y
    - CONFIG_BT_HCI =y
    - CONFIG_BT_HCI_RAW =y
    - CONFIG_BT_CTLR =y
    - CONFIG_BT_LL_SW_SPLIT =y (if using the open source Link Layer)

- **Host-only build**: A Zephyr OS Host build will contain the Application and the BLE Host, along with an HCI driver (UART or SPI) to interface with an external Controller chip. A build of this type sets the following Kconfig option values:
  - CONFIG_BT =y
  - CONFIG_BT_HCI =y
  - CONFIG_BT_CTLR =n

All of the samples located in samples/bluetooth except for the ones used for Controller-only builds can be built as Host-only

- **Combined build**: This includes the Application, the Host and the Controller, and it is used exclusively for single-chip (SoC) configurations. A build of this type sets the following Kconfig option values:
  - CONFIG_BT =y
  - CONFIG_BT_HCI =y
  - CONFIG_BT_CTLR =y
  - CONFIG_BT_LL_SW_SPLIT =y (if using the open source Link Layer)

All of the samples located in samples/bluetooth except for the ones used for Controller-only builds can be built as Combined

The picture below shows the SoC or single-chip configuration when using a Zephyr combined build (a build that includes both a BLE Host and a Controller in the same firmware image that is programmed onto the chip):

When using connectivity or dual-chip configurations, several Host and Controller combinations are possible, some of which are depicted below:

When using a Zephyr Host (left side of image), two instances of Zephyr OS must be built with different configurations, yielding two separate images that must be programmed into each of the chips respectively. The Host build image contains the application, the BLE Host and the selected HCI driver (UART or SPI), while the Controller build runs either the hci_uart, or the hci_spi app to provide an interface to the BLE Controller.
6.1. Bluetooth

Fig. 6.1: A Combined build on a Single-Chip configuration

Fig. 6.2: Host-only and Controller-only builds on dual-chip configurations
This configuration is not limited to using a Zephyr OS Host, as the right side of the image shows. One can indeed take one of the many existing GNU/Linux distributions, most of which include Linux's own BLE Host (BlueZ), to connect it via UART or USB to one or more instances of the Zephyr OS Controller build. BlueZ as a Host supports multiple Controllers simultaneously for applications that require more than one BLE radio operating at the same time but sharing the same Host stack.

**Source tree layout**

The stack is split up as follows in the source tree:

- **subsys/bluetooth/host**
  The host stack. This is where the HCI command and event handling as well as connection tracking happens. The implementation of the core protocols such as L2CAP, ATT, and SMP is also here.

- **subsys/bluetooth/controller**
  Bluetooth Controller implementation. Implements the controller-side of HCI, the Link Layer as well as access to the radio transceiver.

- **include/bluetooth/**
  Public API header files. These are the header files applications need to include in order to use Bluetooth functionality.

- **drivers/bluetooth/**
  HCI transport drivers. Every HCI transport needs its own driver. For example, the two common types of UART transport protocols (3-Wire and 5-Wire) have their own drivers.

- **samples/bluetooth/**
  Sample Bluetooth code. This is a good reference to get started with Bluetooth application development.

- **tests/bluetooth/**
  Test applications. These applications are used to verify the functionality of the Bluetooth stack, but are not necessary the best source for sample code (see samples/bluetooth instead).

- **doc/guides/bluetooth/**
  Extra documentation, such as PICS documents.

**Host**

The Bluetooth Host implements all the higher-level protocols and profiles, and most importantly, provides a high-level API for applications. The following diagram depicts the main protocol & profile layers of the host.

![Bluetooth Host protocol & profile layers](image)

Fig. 6.3: Bluetooth Host protocol & profile layers.
Lowest down in the host stack sits a so-called HCI driver, which is responsible for abstracting away the details of the HCI transport. It provides a basic API for delivering data from the controller to the host, and vice-versa.

Perhaps the most important block above the HCI handling is the Generic Access Profile (GAP). GAP simplifies Bluetooth LE access by defining four distinct roles of BLE usage:

- **Connection-oriented roles**
  - Peripheral (e.g. a smart sensor, often with a limited user interface)
  - Central (typically a mobile phone or a PC)

- **Connection-less roles**
  - Broadcaster (sending out BLE advertisements, e.g. a smart beacon)
  - Observer (scanning for BLE advertisements)

Each role comes with its own build-time configuration option: `CONFIG_BT_PERIPHERAL`, `CONFIG_BT_CENTRAL`, `CONFIG_BT_BROADCASTER` & `CONFIG_BT_OBSERVER`. Of the connection-oriented roles central implicitly enables observer role, and peripheral implicitly enables broadcaster role. Usually the first step when creating an application is to decide which roles are needed and go from there. Bluetooth mesh is a slightly special case, requiring at least the observer and broadcaster roles, and possibly also the Peripheral role. This will be described in more detail in a later section.

**Peripheral role** Most Zephyr-based BLE devices will most likely be peripheral-role devices. This means that they perform connectable advertising and expose one or more GATT services. After registering services using the `bt_gatt_service_register()` API the application will typically start connectable advertising using the `bt_le_adv_start()` API.

There are several peripheral sample applications available in the tree, such as samples/bluetooth/peripheral_hr.

**Central role** Central role may not be as common for Zephyr-based devices as peripheral role, but it is still a plausible one and equally well supported in Zephyr. Rather than accepting connections from other devices a central role device will scan for available peripheral device and choose one to connect to. Once connected, a central will typically act as a GATT client, first performing discovery of available services and then accessing one or more supported services.

To initially discover a device to connect to the application will likely use the `bt_le_scan_start()` API, wait for an appropriate device to be found (using the scan callback), stop scanning using `bt_le_scan_stop()` and then connect to the device using `bt_conn_create_le()`. If the central wants to keep automatically reconnecting to the peripheral it should use the `bt_le_set_auto_conn()` API.

There are some sample applications for the central role available in the tree, such as samples/bluetooth/central_hr.

**Observer role** An observer role device will use the `bt_le_scan_start()` API to scan for device, but it will not connect to any of them. Instead it will simply utilize the advertising data of found devices, combining it optionally with the received signal strength (RSSI).

**Broadcaster role** A broadcaster role device will use the `bt_le_adv_start()` API to advertise specific advertising data, but the type of advertising will be non-connectable, i.e. other device will not be able to connect to it.

**Connections** Connection handling and the related APIs can be found in the *Connection Management* section.
Security  To achieve a secure relationship between two Bluetooth devices a process called pairing is used. This process can either be triggered implicitly through the security properties of GATT services, or explicitly using the `bt_conn_security()` API on a connection object.

To achieve a higher security level, and protect against Man-In-The-Middle (MITM) attacks, it is recommended to use some out-of-band channel during the pairing. If the devices have a sufficient user interface this “channel” is the user itself. The capabilities of the device are registered using the `bt_conn_auth_cb_register()` API. The `bt_conn_auth_cb` struct that’s passed to this API has a set of optional callbacks that can be used during the pairing - if the device lacks some feature the corresponding callback may be set to NULL. For example, if the device does not have an input method but does have a display, the `passkey_entry` and `passkey_confirm` callbacks would be set to NULL, but the `passkey_display` would be set to a callback capable of displaying a passkey to the user.

Depending on the local and remote security requirements & capabilities, there are four possible security levels that can be reached:

- **BT_SECURITY_L1**
  - No encryption and no authentication.

- **BT_SECURITY_L2**
  - Encryption but no authentication (no MITM protection).

- **BT_SECURITY_L3**
  - Encryption and authentication using the legacy pairing method from Bluetooth 4.0 and 4.1.

- **BT_SECURITY_L4**
  - Encryption and authentication using the LE Secure Connections feature available since Bluetooth 4.2.

**Note:** Mesh has its own security solution through a process called provisioning. It follows a similar procedure as pairing, but is done using separate mesh-specific APIs.

**L2CAP**  L2CAP stands for the Logical Link Control and Adaptation Protocol. It is a common layer for all communication over Bluetooth connections, however an application comes in direct contact with it only when using it in the so-called Connection-oriented Channels (CoC) mode. More information on this can be found in the L2CAP API section.

**GATT**  The Generic Attribute Profile is the most common means of communication over LE connections. A more detailed description of this layer and the API reference can be found in the GATT API reference section.

**Mesh**  Mesh is a little bit special when it comes to the needed GAP roles. By default, mesh requires both observer and broadcaster role to be enabled. If the optional GATT Proxy feature is desired, then peripheral role should also be enabled.

The API reference for mesh can be found in the Mesh API reference section.

**LE Audio**  The LE audio is a set of profiles and services that utilizes GATT and Isochronous Channel to provide audio over Bluetooth Low Energy. The architecture and API references can be found in Bluetooth Audio Architecture.

**Persistent storage**  The Bluetooth host stack uses the settings subsystem to implement persistent storage to flash. This requires the presence of a flash driver and a designated “storage” partition on flash. A typical set of configuration options needed will look something like the following:
Once enabled, it is the responsibility of the application to call settings_load() after having initialized Bluetooth (using the bt_enable() API).

**Bluetooth Low Energy Controller**

**Hardware Requirements**

**Nordic Semiconductor**  The Nordic Semiconductor Bluetooth Low Energy Controller implementation requires the following hardware peripherals.

1. **Clock**
   - A Low Frequency Clock (LFCLOCK) or sleep clock, for low power consumption between Bluetooth radio events
   - A High Frequency Clock (HFCLOCK) or active clock, for high precision packet timing and software based transceiver state switching with inter-frame space (tIFS) timing inside Bluetooth radio events

2. **Real Time Counter (RTC)**
   - 1 instance
   - 2 capture/compare registers

3. **Timer**
   - 2 instances, one each for packet timing and tIFS software switching, respectively
   - 7 capture/compare registers (3 mandatory, 1 optional for ISR profiling, 4 for single timer tIFS switching) on first instance
   - 4 capture/compare registers for second instance, if single tIFS timer is not used.

4. **Programmable Peripheral Interconnect (PPI)**
   - 21 channels (20 channels when not using pre-defined channels)
   - 2 channel groups for software-based tIFS switching

5. **Distributed Programmable Peripheral Interconnect (DPPI)**
   - 20 channels
   - 2 channel groups for s/w tIFS switching

6. **Software Interrupt (SWI)**
   - 3 instances, for Lower Link Layer, Upper Link Layer High priority, and Upper Link Layer Low priority execution

7. **Radio**
   - 2.4 GHz radio transceiver with multiple radio standards such as 1 Mbps, 2 Mbps and Long Range Bluetooth Low Energy technology

8. **Random Number Generator (RNG)**
   - 1 instance
9. AES electronic codebook mode encryption (ECB)
   • 1 instance
10. Cipher Block Chaining - Message Authentication Code with Counter Mode encryption (CCM)
    • 1 instance
11. Accelerated address resolver (AAR)
    • 1 instance
12. GPIO
    • 2 GPIO pins for PA and LNA, 1 each.
    • 10 Debug GPIO pins (optional)
13. GPIO tasks and events (GPIOTE)
    • 1 instance
    • 1 channel for PA/LNA
14. Temperature sensor (TEMP)
    • For RC calibration
15. Interprocess Communication peripheral (IPC)
    • For HCI interface
16. UART
    • For HCI interface

Standard

Split

6.1.3 Bluetooth Audio Architecture

![Bluetooth Audio Architecture Diagram]

Fig. 6.4: Bluetooth Audio Architecture
Generic Audio Framework (GAF)

The Generic Audio Framework (GAF) is considered the middleware of the Bluetooth LE Audio architecture. The GAF contains the profiles and services that allows higher layer applications and profiles to set up streams, change volume, control media and telephony and more. The GAF builds on GATT, GAP and isochronous channels (ISO).

GAF uses GAP to connect, advertise and synchronize to other devices. GAF uses GATT to configure streams, associate streams with content (e.g. media or telephony), control volume and more. GAF uses ISO for the audio streams themselves, both as unicast (connected) audio streams or broadcast (unconnected) audio streams.

GAF mandates the use of the LC3 codec, but also supports other codecs.

![Fig. 6.5: Generic Audio Framework](image)

The top-level profiles TMAP and HAP are not part of the GAF, but rather provide top-level requirements for how to use the GAF.

GAF has been implemented in Zephyr with the following structure.

![Fig. 6.6: Zephyr Generic Audio Framework](image)

Currently CAP (and CAS) as well as CCP (and TBS) are not yet implemented in Zephyr. Similarly the top-level profiles TMAP and HAP are also not yet implemented.

6.1. Bluetooth
Using the Bluetooth Audio Stack  To use any of the profiles in the Bluetooth Audio Stack, including the top-level profiles outside of GAF, CONFIG_BT_AUDIO shall be enabled. This Kconfig option allows the enabling of the individual profiles inside of the Bluetooth Audio Stack. Each profile can generally be enabled on its own, but enabling higher-layer profiles (such as CAP, TMAP and HAP) will typically require enabling some of the lower layer profiles.

It is, however, possible to create a device that uses e.g. only Stream Control (with just the BAP), without using any of the content control or rendering/capture control profiles, or vice versa. Using the higher layer profiles will however typically provide a better user experience and better interoperability with other devices.

Stream Control (BAP)  Stream control is implemented by the Basic Audio Profile. This profile defines multiple roles:

- Unicast Client
- Unicast Server
- Broadcast Source
- Broadcast Sink
- Scan Delegator (not yet implemented)
- Broadcast assistant (not yet implemented)

Each role can be enabled individually, and it is possible to support more than one role.

The API reference for stream control can be found in Bluetooth Audio.

Rendering and Capture Control  Rendering and capture control is implemented by the Volume Control Profile (VCP) and Microphone Input Control Profile (MICP).

The VCP implementation supports the following roles

- Volume Control Service (VCS) Server
- Volume Control Service (VCS) Client

The MICP implementation supports the following roles

- Microphone Input Control Profile (MICP) Microphone Device (server)
- Microphone Input Control Profile (MICP) Microphone Controller (client)

The API reference for volume control can be found in Bluetooth Volume Control.

The API reference for microphone input control can be found in Bluetooth Microphone Input Control.

Content Control  Content control is implemented by the Call Control Profile (CCP) and Media Control Profile (MCP).

The CCP implementation is not yet implemented in Zephyr.

The MCP implementation supports the following roles

- Media Control Service (MCS) Server via the Media Proxy module
- Media Control Client (MCC)

The API reference for media control can be found in Bluetooth Media Control.
Coordinated Sets  Coordinated Sets is implemented by the Coordinated Sets Identification Profile (CSIP).

The CSIP implementation supports the following roles

- Coordinated Set Identification Service (CSIP) Set Member
- Coordinated Set Identification Service (CSIP) Set Coordinator

The API reference for media control can be found in Bluetooth Coordinated Sets.

6.1.4 Bluetooth Qualification

Qualification Listings

The Zephyr BLE stack has obtained qualification listings for both the Host and the Controller. See the tables below for a list of qualification listings

### Host qualifications

<table>
<thead>
<tr>
<th>Zephyr version</th>
<th>Link</th>
<th>Qualifying Company</th>
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<tbody>
<tr>
<td>2.2.x</td>
<td>QDID 151074</td>
<td>Demant A/S</td>
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<tr>
<td>1.14.x</td>
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<tr>
<td>1.13</td>
<td>QDID 119517</td>
<td>Nordic Semiconductor</td>
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### Mesh qualifications

<table>
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<th>Link</th>
<th>Qualifying Company</th>
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</thead>
<tbody>
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<td>The Linux Foundation</td>
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### Controller qualifications

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<th>Link</th>
<th>Qualifying Company</th>
<th>Compatible Hardware</th>
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<tr>
<td>2.2.x</td>
<td>QDID 150092</td>
<td>Nordic Semiconductor</td>
<td>nRF52x</td>
</tr>
<tr>
<td>1.14.x</td>
<td>QDID 135679</td>
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<td>1.9 to 1.13</td>
<td>QDID 101395</td>
<td>Nordic Semiconductor</td>
<td>nRF52x</td>
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</table>

ICS Features

The ICS features for each supported protocol & profile can be found in the following documents:

GAP ICS  PTS version: 8.0.3

M - mandatory
O - optional

### Device Configuration

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<thead>
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<th>Selected</th>
<th>Description</th>
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<td>BR/EDR (C.1)</td>
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<td>LE (C.2)</td>
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### Modes

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<td>Limited-discoverable mode (O)</td>
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<td>General-discoverable mode (O)</td>
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<td>Non-bondable mode (O)</td>
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### Security Aspects

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<td>Support of LMP-Authentication (M)</td>
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<tr>
<td>TSPC_GAP_2_3</td>
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<td>Initiate LMP-Authentication (C.5)</td>
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<td>Security mode 1 (C.2)</td>
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<td>Security mode 2 (O)</td>
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<td>TSPC_GAP_2_6</td>
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<td>Security mode 3 (C.7)</td>
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<td>Support of Authenticated link key (C.6)</td>
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<td>Security Optional (C.6)</td>
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<td>TSPC_GAP_2_11</td>
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<td>Secure Connections Only Mode (C.8)</td>
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<td>TSPC_GAP_2_12</td>
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### Idle Mode Procedures

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### Establishment Procedures

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<td>Support link establishment as initiator (M)</td>
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<td>TSPC_GAP_4_7</td>
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LE Roles

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Broadcaster Physical Layer

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Broadcaster Link Layer States

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<td>TSPC_GAP_7_3</td>
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Broadcaster Link Layer Advertising Event Types

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Broadcaster Link Layer Advertising Data Types

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<th>Description</th>
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<td>AD Type – Local Name (O)</td>
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<td>AD Type – Flags (O)</td>
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<td>AD Type – Manufacturer Specific Data (O)</td>
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<td>AD Type - URI (O)</td>
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Broadcaster Connection Modes and Procedures

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### Broadcaster Broadcasting and Observing Features

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<td>TSPC_GAP_10_3</td>
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<td>Broadcast Isochronous Broadcasting mode (C.2)</td>
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### Broadcaster Privacy Feature

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<td>Non-Resolvable Private Address Generation Procedure (C.2)</td>
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### Periodic Advertising Modes and Procedures

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### Broadcaster Security Aspects Features

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### Observer Physical Layer

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### Observer Link Layer States

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### Observer Link Layer Scanning Types

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### Observer Connection Modes and Procedures

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### Observer Broadcasting and Observing Features

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<td>Broadcast Isochronous Termination procedure (C.2)</td>
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### Observer Privacy Feature

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<td>Non-Resolvable Private Address Generation Procedure (C.1)</td>
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<td>Resolvable Private Address Resolution Procedure (O)</td>
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<td>Resolvable Private Address Generation Procedure (C.2)</td>
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### Periodic Advertising Modes and Procedures

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<td>Periodic Advertising Synchronization Establishment procedure with listening for periodic advertising (C.1)</td>
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### Observer Security Aspects Features

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<td>LE Security Mode 3 (C.1)</td>
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<td>LE Security Mode 3, Level 1 (C.2)</td>
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<td>TSPC_GAP_17b_3</td>
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### Peripheral Physical Layer

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### Peripheral Link Layer States

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<td>True</td>
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<td>TSPC_GAP_19_3</td>
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<td>Connection, Peripheral Role (M)</td>
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### Peripheral Link Layer Advertising Event Types
### Peripheral Link Layer Advertising Data Types

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<td>TSPC_GAP_20A_2</td>
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<td>TSPC_GAP_20A_3</td>
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<td>AD Type – Flags (C.2)</td>
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<tr>
<td>TSPC_GAP_20A_4</td>
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<td>AD Type – Manufacturer Specific Data (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_5</td>
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<td>TSPC_GAP_20A_6</td>
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<td>TSPC_GAP_20A_7</td>
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<td>TSPC_GAP_20A_8</td>
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<td>AD Type – Peripheral Connection Interval Range (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_9</td>
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<td>AD Type – Service Solicitation (C.1)</td>
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<tr>
<td>TSPC_GAP_20A_10</td>
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<td>AD Type – Service Data (C.1)</td>
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<td>AD Type – Appearance (C.1)</td>
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<td>AD Type – Public Target Address (C.1)</td>
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<td>AD Type – Random Target Address (C.1)</td>
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<td>TSPC_GAP_20A_14</td>
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<td>TSPC_GAP_20A_16</td>
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<td>AD Type – URI (O)</td>
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### Peripheral Link Layer Control Procedures

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<td>Connection Update Procedure (M)</td>
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<td>TSPC_GAP_21_2</td>
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<td>Channel Map Update Procedure (M)</td>
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<td>TSPC_GAP_21_3</td>
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<td>Encryption Procedure (O)</td>
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<td>TSPC_GAP_21_4</td>
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<tr>
<td>TSPC_GAP_21_5</td>
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<td>Version Exchange Procedure (M)</td>
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<td>Termination Procedure (M)</td>
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<td>TSPC_GAP_21_7</td>
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<td>LE Ping Procedure (O)</td>
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<td>TSPC_GAP_21_8</td>
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<td>TSPC_GAP_21_10</td>
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<td>TSPC_GAP_21_11</td>
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<td>PHY Update Procedure (C.2)</td>
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<td>Minimum Number Of Used Channels Procedure (C.2)</td>
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### Peripheral Discovery Modes and Procedures

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<td>TSPC_GAP_22_3</td>
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<td>TSPC_GAP_22_4</td>
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<td>Name Discovery Procedure (O)</td>
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### Peripheral Connection Modes and Procedures

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<td>TSPC_GAP_23_4</td>
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<td>Connection Parameter Update Procedure (O)</td>
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<tr>
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### Peripheral Bonding Modes and Procedures

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<td>TSPC_GAP_24_4</td>
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### Peripheral Security Aspects Features

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<td>Authenticate Signed Data Procedure (O)</td>
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<td>TSPC_GAP_25_7</td>
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<tr>
<td>TSPC_GAP_25_11</td>
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<td>Unauthenticated Pairing (LE security mode 1 level 2) with LE Secure Connections Pairing only (C.3)</td>
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<tr>
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### Peripheral Privacy Feature

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### Peripheral GAP Characteristics
## Periodic Advertising Modes and Procedures

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## Central Physical Layer

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<td>TSPC_GAP_28_1</td>
<td>True</td>
<td>Transmitter (M)</td>
</tr>
<tr>
<td>TSPC_GAP_28_2</td>
<td>True</td>
<td>Receiver (M)</td>
</tr>
</tbody>
</table>

## Central Link Layer States

<table>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_GAP_29_1</td>
<td>True</td>
<td>Standby (M)</td>
</tr>
<tr>
<td>TSPC_GAP_29_2</td>
<td>True</td>
<td>Scanning (M)</td>
</tr>
<tr>
<td>TSPC_GAP_29_3</td>
<td>True</td>
<td>Initiating (M)</td>
</tr>
<tr>
<td>TSPC_GAP_29_4</td>
<td>True</td>
<td>Connection, Central Role (M)</td>
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## Central Link Layer Scanning Types

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<tr>
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<td>True</td>
<td>Passive Scanning (O)</td>
</tr>
<tr>
<td>TSPC_GAP_30_2</td>
<td>True</td>
<td>Active Scanning (C.1)</td>
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## Central Link Layer Control Procedures

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<tr>
<td>TSPC_GAP_31_1</td>
<td>True</td>
<td>Connection Update Procedure (M)</td>
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<tr>
<td>TSPC_GAP_31_2</td>
<td>True</td>
<td>Channel Map Update Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_31_3</td>
<td>True</td>
<td>Encryption Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_31_4</td>
<td>True</td>
<td>Central Initiated Feature Exchange Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_31_5</td>
<td>True</td>
<td>Version Exchange Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_31_6</td>
<td>True</td>
<td>Termination Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_31_7</td>
<td>False</td>
<td>LE Ping Procedure (O)</td>
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<tr>
<td>TSPC_GAP_31_8</td>
<td>True</td>
<td>Peripheral Initiated Feature Exchange Procedure (C.1)</td>
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<tr>
<td>TSPC_GAP_31_9</td>
<td>True</td>
<td>Connection Parameter Request Procedure (O)</td>
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<tr>
<td>TSPC_GAP_31_10</td>
<td>True</td>
<td>Data Length Update Procedure (O)</td>
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<tr>
<td>TSPC_GAP_31_11</td>
<td>True</td>
<td>PHY Update Procedure (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_31_12</td>
<td>False</td>
<td>Minimum Number Of Used Channels Procedure (C.2)</td>
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### Central Discovery Modes and Procedures

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<td>TSPC_GAP_32_1</td>
<td>True</td>
<td>Limited Discovery Procedure (O)</td>
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<tr>
<td>TSPC_GAP_32_2</td>
<td>True</td>
<td>General Discovery Procedure (M)</td>
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<tr>
<td>TSPC_GAP_32_3</td>
<td>True</td>
<td>Name Discovery Procedure (O)</td>
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### Central Connection Modes and Procedures

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<tr>
<td>TSPC_GAP_33_1</td>
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<td>Auto Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_2</td>
<td>True</td>
<td>General Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_3</td>
<td>False</td>
<td>Selective Connection Establishment Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_33_4</td>
<td>True</td>
<td>Selective Connection Establishment Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_5</td>
<td>True</td>
<td>Connection Parameter Update Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_6</td>
<td>True</td>
<td>Terminate Connection Procedure (M)</td>
</tr>
<tr>
<td>TSPC_GAP_33_7</td>
<td>False</td>
<td>Connected Isochronous Stream Creation procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_33_8</td>
<td>False</td>
<td>Connected Isochronous Stream Termination procedure (C.1)</td>
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### Central Bonding Modes and Procedures

<table>
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<tbody>
<tr>
<td>TSPC_GAP_34_1</td>
<td>True</td>
<td>Non-Bondable Mode (M)</td>
</tr>
<tr>
<td>TSPC_GAP_34_2</td>
<td>True</td>
<td>Bondable Mode (O)</td>
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<tr>
<td>TSPC_GAP_34_3</td>
<td>True</td>
<td>Bonding Procedure (O)</td>
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### Central Security Features

<table>
<thead>
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<tbody>
<tr>
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<td>True</td>
<td>Security Mode 1 (O)</td>
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<tr>
<td>TSPC_GAP_35_2</td>
<td>True</td>
<td>Security Mode 2 (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_3</td>
<td>True</td>
<td>Authentication Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_4</td>
<td>False</td>
<td>Authorization Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_5</td>
<td>True</td>
<td>Connection Data Signing Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_6</td>
<td>True</td>
<td>Authenticate Signed Data Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_35_7</td>
<td>True</td>
<td>Authenticated Pairing (LE security mode 1 level 3) (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_35_8</td>
<td>True</td>
<td>Unauthenticated Pairing (LE security mode 1 level 2) (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_35_9</td>
<td>True</td>
<td>LE Security Mode 1 Level 4 (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_10</td>
<td>True</td>
<td>Secure Connections Only Mode (C.3)</td>
</tr>
<tr>
<td>TSPC_GAP_35_11</td>
<td>False</td>
<td>Unauthenticated Pairing (LE security mode 1 level 2) with LE Secure Connections Pairing only (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_12</td>
<td>False</td>
<td>Authenticated Pairing (LE security mode 1 level 3) with LE Secure Connections Pairing only (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_35_13</td>
<td>True</td>
<td>Minimum 128 Bit entropy key (C.4)</td>
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### Central Privacy Feature

<table>
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<tr>
<td>TSPC_GAP_36_1</td>
<td>True</td>
<td>Privacy Feature (O)</td>
</tr>
<tr>
<td>TSPC_GAP_36_2</td>
<td>True</td>
<td>Non-Resolvable Private Address Generation Procedure (O)</td>
</tr>
<tr>
<td>TSPC_GAP_36_3</td>
<td>True</td>
<td>Resolvable Private Address Resolution Procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_36_4</td>
<td>True</td>
<td>Resolvable Private Address Generation Procedure (C.1)</td>
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## Central GAP Characteristics

<table>
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<tbody>
<tr>
<td>TSPC_GAP_37_1</td>
<td>True</td>
<td>Device Name (M)</td>
</tr>
<tr>
<td>TSPC_GAP_37_2</td>
<td>True</td>
<td>Appearance (M)</td>
</tr>
<tr>
<td>TSPC_GAP_37_3</td>
<td>True</td>
<td>Central Address Resolution (C.1)</td>
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## Periodic Advertising Modes and Procedures

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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_GAP_37a_1</td>
<td>False</td>
<td>Periodic Advertising Synchronization Transfer procedure (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_37a_2</td>
<td>False</td>
<td>Periodic Advertising Synchronization Establishment procedure over an LE connection without listening for periodic advertising (C.2)</td>
</tr>
<tr>
<td>TSPC_GAP_37a_3</td>
<td>False</td>
<td>Periodic Advertising Synchronization Establishment procedure over an LE connection with listening for periodic advertising (C.3)</td>
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## BR/EDR/LE Roles

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<tr>
<td>TSPC_GAP_38_1</td>
<td>False</td>
<td>Broadcaster (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_38_2</td>
<td>False</td>
<td>Observer (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_38_3</td>
<td>False</td>
<td>Peripheral (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_38_4</td>
<td>False</td>
<td>Central (C.1)</td>
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## Central BR/EDR/LE Security Aspects

<table>
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<tr>
<td>TSPC_GAP_41_1</td>
<td>False</td>
<td>Security Aspects (M)</td>
</tr>
<tr>
<td>TSPC_GAP_41_2a</td>
<td>False</td>
<td>Derivation of BR/EDR Link Key from LE LTK (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_41_2b</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
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## Peripheral BR/EDR/LE Security Aspects

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<tr>
<td>TSPC_GAP_43_1</td>
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<td>Security Aspects (M)</td>
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<tr>
<td>TSPC_GAP_43_2a</td>
<td>False</td>
<td>Derivation of BR/EDR Link Key from LE LTK (C.1)</td>
</tr>
<tr>
<td>TSPC_GAP_43_2b</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
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## Central Simultaneous BR/EDR and LE Transports

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<tr>
<td>TSPC_GAP_44_1</td>
<td>False</td>
<td>Simultaneous BR/EDR and LE Transports – BR/EDR Peripheral to the same device (O)</td>
</tr>
<tr>
<td>TSPC_GAP_44_2</td>
<td>False</td>
<td>Simultaneous BR/EDR and LE Transports – BR/EDR Central to the same device (O)</td>
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## Peripheral Simultaneous BR/EDR and LE Transports
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<tr>
<td>TSPC_GAP_45_1</td>
<td>False</td>
<td>Simultaneous BR/EDR and LE Transports – BR/EDR Peripheral to the same device (O)</td>
</tr>
<tr>
<td>TSPC_GAP_45_2</td>
<td>False</td>
<td>Simultaneous BR/EDR and LE Transports – BR/EDR Central to the same device (O)</td>
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</tbody>
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**GATT ICS**  
PTS version: 8.0.3  
M - mandatory  
O - optional

### Generic Attribute Profile Support

<table>
<thead>
<tr>
<th>Parameter Name</th>
<th>Selected</th>
<th>Description</th>
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<tr>
<td>TSPC_GATT_1_1</td>
<td>True</td>
<td>Generic Attribute Profile (GATT) Client (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_1_2</td>
<td>True</td>
<td>Generic Attribute Profile (GATT) Server (C.2)</td>
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### GATT role configuration

<table>
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<tr>
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<tr>
<td>TSPC_GATT_1a_1</td>
<td>True</td>
<td>GATT Client over LE (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_1a_2</td>
<td>False</td>
<td>GATT Client over BR/EDR (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_1a_3</td>
<td>True</td>
<td>GATT Server over LE (C.3)</td>
</tr>
<tr>
<td>TSPC_GATT_1a_4</td>
<td>False</td>
<td>GATT Server over BR/EDR (C.4)</td>
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### Attribute Protocol Transport

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<tr>
<td>TSPC_GATT_2_1</td>
<td>False</td>
<td>Attribute Protocol Supported over BR/EDR (L2CAP fixed channel support) (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_2_2</td>
<td>True</td>
<td>Attribute Protocol Supported over LE (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_2_3</td>
<td>True</td>
<td>Enhanced ATT bearer Attribute Protocol Supported (L2CAP fixed EATT PSM supported) (C.3)</td>
</tr>
<tr>
<td>TSPC_GATT_2_3a</td>
<td>True</td>
<td>Enhanced ATT bearer supported over LE (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT_2_3b</td>
<td>False</td>
<td>Enhanced ATT bearer supported over BR/EDR (C.5)</td>
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### Generic Attribute Profile Feature Support, by Client

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<tr>
<td>TSPC_GATT_3_1</td>
<td>True</td>
<td>Exchange MTU (C.11)</td>
</tr>
<tr>
<td>TSPC_GATT_3_2</td>
<td>True</td>
<td>Discover All Primary Services (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_3</td>
<td>True</td>
<td>Discover Primary Services by Service UUID (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_4</td>
<td>True</td>
<td>Find Included Services (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_5</td>
<td>True</td>
<td>Discover All characteristics of a Service (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_6</td>
<td>True</td>
<td>Discover Characteristics by UUID (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_7</td>
<td>True</td>
<td>Discover All Characteristic Descriptors (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_8</td>
<td>True</td>
<td>Read Characteristic Value (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_9</td>
<td>True</td>
<td>Read Using Characteristic UUID (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_10</td>
<td>True</td>
<td>Read Long Characteristic Values (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_11</td>
<td>True</td>
<td>Read Multiple Characteristic Values (O)</td>
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### Table 6.1 – continued from previous page

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<td>Write without Response (O)</td>
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<tr>
<td>TSPC_GATT_3_13</td>
<td>True</td>
<td>Signed Write Without Response (C.11)</td>
</tr>
<tr>
<td>TSPC_GATT_3_14</td>
<td>True</td>
<td>Write Characteristic Value (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_15</td>
<td>True</td>
<td>Write Long Characteristic Values (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_16</td>
<td>True</td>
<td>Characteristic Value Reliable Writes (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_17</td>
<td>True</td>
<td>Notifications (C.7)</td>
</tr>
<tr>
<td>TSPC_GATT_3_18</td>
<td>True</td>
<td>Indications (M)</td>
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<td>TSPC_GATT_3_19</td>
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<td>Read Characteristic Descriptors (O)</td>
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<tr>
<td>TSPC_GATT_3_20</td>
<td>True</td>
<td>Read Long Characteristic Descriptors (O)</td>
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<tr>
<td>TSPC_GATT_3_21</td>
<td>True</td>
<td>Write Characteristic Descriptors (O)</td>
</tr>
<tr>
<td>TSPC_GATT_3_22</td>
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<td>TSPC_GATT_3_23</td>
<td>True</td>
<td>Service Changed Characteristic (M)</td>
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<td>TSPC_GATT_3_24</td>
<td>False</td>
<td>Configured Broadcast (C.2)</td>
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<tr>
<td>TSPC_GATT_3_25</td>
<td>True</td>
<td>Client Supported Features Characteristic (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT_3_26</td>
<td>True</td>
<td>Database Hash Characteristic (C.4)</td>
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<td>TSPC_GATT_3_27</td>
<td>False</td>
<td>Read and Interpret Characteristic Presentation Format (O)</td>
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<tr>
<td>TSPC_GATT_3_28</td>
<td>False</td>
<td>Read and Interpret Characteristic Aggregate Format (C.6)</td>
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<td>TSPC_GATT_3_29</td>
<td>False</td>
<td>Read Multiple Variable Length Characteristic Values (C.9)</td>
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<tr>
<td>TSPC_GATT_3_30</td>
<td>False</td>
<td>Multiple Variable Length Notifications (C.10)</td>
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### Generic Attribute Profile Feature Support, by Server

<table>
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<td>True</td>
<td>Exchange MTU (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT_4_2</td>
<td>True</td>
<td>Discover All Primary Services (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_3</td>
<td>True</td>
<td>Discover Primary Services by Service UUID (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_4</td>
<td>True</td>
<td>Find Included Services (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_5</td>
<td>True</td>
<td>Discover All characteristics of a Service (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_6</td>
<td>True</td>
<td>Discover Characteristics by UUID (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_7</td>
<td>True</td>
<td>Discover All Characteristic Descriptors (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_8</td>
<td>True</td>
<td>Read Characteristic Value (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_9</td>
<td>True</td>
<td>Read Using Characteristic UUID (M)</td>
</tr>
<tr>
<td>TSPC_GATT_4_10</td>
<td>True</td>
<td>Read Long Characteristic Values (C.12)</td>
</tr>
<tr>
<td>TSPC_GATT_4_11</td>
<td>True</td>
<td>Read Multiple Characteristic Values (O)</td>
</tr>
<tr>
<td>TSPC_GATT_4_12</td>
<td>True</td>
<td>Write without Response (C.2)</td>
</tr>
<tr>
<td>TSPC_GATT_4_13</td>
<td>True</td>
<td>Signed Write Without Response (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT_4_14</td>
<td>True</td>
<td>Write Characteristic Value (C.3)</td>
</tr>
<tr>
<td>TSPC_GATT_4_15</td>
<td>True</td>
<td>Write Long Characteristic Values (C.12)</td>
</tr>
<tr>
<td>TSPC_GATT_4_16</td>
<td>True</td>
<td>Characteristic Value Reliable Writes (O)</td>
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<tr>
<td>TSPC_GATT_4_17</td>
<td>True</td>
<td>Notifications (O)</td>
</tr>
<tr>
<td>TSPC_GATT_4_18</td>
<td>True</td>
<td>Indications (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_4_19</td>
<td>True</td>
<td>Read Characteristic Descriptors (C.12)</td>
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<tr>
<td>TSPC_GATT_4_20</td>
<td>True</td>
<td>Read Long Characteristic Descriptors (C.12)</td>
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<tr>
<td>TSPC_GATT_4_21</td>
<td>True</td>
<td>Write Characteristic Descriptors (C.12)</td>
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<tr>
<td>TSPC_GATT_4_22</td>
<td>True</td>
<td>Write Long Characteristic Descriptors (O)</td>
</tr>
<tr>
<td>TSPC_GATT_4_23</td>
<td>True</td>
<td>Service Changed Characteristic (C.1)</td>
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<tr>
<td>TSPC_GATT_4_24</td>
<td>False</td>
<td>Configured Broadcast (C.5)</td>
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<tr>
<td>TSPC_GATT_4_25</td>
<td>True</td>
<td>Execute Write Request with empty queue (C.7)</td>
</tr>
<tr>
<td>TSPC_GATT_4_26</td>
<td>True</td>
<td>Client Supported Features Characteristic (C.9)</td>
</tr>
<tr>
<td>TSPC_GATT_4_27</td>
<td>True</td>
<td>Database Hash Characteristic (C.8)</td>
</tr>
<tr>
<td>TSPC_GATT_4_28</td>
<td>False</td>
<td>Report Characteristic Value: Characteristic Presentation Format (O)</td>
</tr>
<tr>
<td>TSPC_GATT_4_29</td>
<td>False</td>
<td>Report aggregate Characteristic Value: Characteristic Aggregate Format (C.10)</td>
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continues on next page
### SDP Interoperability

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<tr>
<td>TSPC_GATT_6_2</td>
<td>False</td>
<td>Discover GATT Services using Service Discovery Profile (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_6_3</td>
<td>False</td>
<td>Publish SDP record for GATT services support via BR/EDR (C.2)</td>
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### Attribute Protocol Transport Security

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<tr>
<td>TSPC_GATT_7_1</td>
<td>False</td>
<td>Security Mode 4 (C.1)</td>
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<tr>
<td>TSPC_GATT_7_2</td>
<td>True</td>
<td>LE Security Mode 1 (C.5)</td>
</tr>
<tr>
<td>TSPC_GATT_7_3</td>
<td>True</td>
<td>LE Security Mode 2 (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT_7_4</td>
<td>True</td>
<td>LE Authentication Procedure (C.4)</td>
</tr>
<tr>
<td>TSPC_GATT_7_5</td>
<td>True</td>
<td>LE connection data signing procedure (C.2)</td>
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<tr>
<td>TSPC_GATT_7_6</td>
<td>True</td>
<td>LE Authenticate signed data procedure (C.2)</td>
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<tr>
<td>TSPC_GATT_7_7</td>
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<td>LE Authorization Procedure (C.3)</td>
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### Multiple Simultaneous ATT Bearers

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<tr>
<td>TSPC_GATT_8_1</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and ATT over BR/EDR (C.1)</td>
</tr>
<tr>
<td>TSPC_GATT_8_2</td>
<td>True</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and EATT over LE (C.2)</td>
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<tr>
<td>TSPC_GATT_8_3</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over BR/EDR and EATT over BR/EDR (C.3)</td>
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<tr>
<td>TSPC_GATT_8_4</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over LE and EATT over BR/EDR (C.4)</td>
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<tr>
<td>TSPC_GATT_8_5</td>
<td>False</td>
<td>Support for multiple simultaneous active ATT bearers from same device – ATT over BR/EDR and EATT over LE (C.5)</td>
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<tr>
<td>TSPC_GATT_8_6</td>
<td>False</td>
<td>Support for multiple simultaneous active EATT bearers from same device – EATT over BR/EDR and EATT over LE (C.6)</td>
</tr>
<tr>
<td>TSPC_GATT_8_7</td>
<td>True</td>
<td>Support for multiple simultaneous active EATT bearers from same device – EATT over BR/EDR and EATT over LE (C.7)</td>
</tr>
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**L2CAP ICS**  
PTS version: 8.0.3

- **M** - mandatory
- **O** - optional

**L2CAP Transport Configuration**
### Roles

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<tr>
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<tr>
<td>TSPC_L2CAP_0_1</td>
<td>False</td>
<td>BR/EDR (includes possible support of GAP LE Broadcaster or LE Observer roles) (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_0_2</td>
<td>True</td>
<td>LE (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_0_3</td>
<td>False</td>
<td>BR/EDR/LE (C.3)</td>
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### General Operation

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<tr>
<td>TSPC_L2CAP_2_1</td>
<td>False</td>
<td>Support of L2CAP signalling channel (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_2</td>
<td>False</td>
<td>Support of configuration process (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_3</td>
<td>False</td>
<td>Support of connection oriented data channel (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_4</td>
<td>False</td>
<td>Support of command echo request (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_5</td>
<td>False</td>
<td>Support of command echo response (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_6</td>
<td>False</td>
<td>Support of command information request (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_7</td>
<td>False</td>
<td>Support of command information response (C.16)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_8</td>
<td>False</td>
<td>Support of a channel group (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_9</td>
<td>False</td>
<td>Support of packet for connectionless channel (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_10</td>
<td>False</td>
<td>Support retransmission mode (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_11</td>
<td>False</td>
<td>Support flow control mode (C.17)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_12</td>
<td>False</td>
<td>Enhanced Retransmission Mode (C.11)</td>
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<tr>
<td>TSPC_L2CAP_2_13</td>
<td>False</td>
<td>Streaming Mode (O)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_14</td>
<td>False</td>
<td>FCS Option (C.1)</td>
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<tr>
<td>TSPC_L2CAP_2_15</td>
<td>False</td>
<td>Generate Local Busy Condition (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_16</td>
<td>False</td>
<td>Send Reject (C.2)</td>
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<tr>
<td>TSPC_L2CAP_2_17</td>
<td>False</td>
<td>Send Selective Reject (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_18</td>
<td>False</td>
<td>Mandatory use of ERTM (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_19</td>
<td>False</td>
<td>Mandatory use of Streaming Mode (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_20</td>
<td>False</td>
<td>Optional use of ERTM (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_21</td>
<td>False</td>
<td>Optional use of Streaming Mode (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_22</td>
<td>False</td>
<td>Send data using SAR in ERTM (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_23</td>
<td>False</td>
<td>Send data using SAR in Streaming Mode (C.6)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_24</td>
<td>False</td>
<td>Actively request Basic Mode for a PSM that supports the use of ERTM or Streaming Mode (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_25</td>
<td>False</td>
<td>Supports performing L2CAP channel mode configuration fallback from SM to ERTM (C.8)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_26</td>
<td>False</td>
<td>Supports sending more than one unacknowledged I-Frame when operating in ERTM (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_27</td>
<td>False</td>
<td>Supports sending more than three unacknowledged I-Frame when operating in ERTM (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_28</td>
<td>False</td>
<td>Supports configuring the peer TxWindow greater than 1. (C.10)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_29</td>
<td>False</td>
<td>AMP Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_30</td>
<td>False</td>
<td>Fixed Channel Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_31</td>
<td>False</td>
<td>AMP Manager Support (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_32</td>
<td>False</td>
<td>ERTM over AMP (C.11)</td>
</tr>
<tr>
<td>TSPC_L2CAP_2_33</td>
<td>False</td>
<td>Streaming Mode Source over AMP Support (C.12)</td>
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### Configurable Parameters

<table>
<thead>
<tr>
<th>Parameter Name</th>
<th>Selected</th>
<th>Description</th>
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</thead>
<tbody>
<tr>
<td>TSPC_L2CAP_3_1</td>
<td>True</td>
<td>Support of RTX timer (M)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_2</td>
<td>False</td>
<td>Support of ERTX timer (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_3</td>
<td>False</td>
<td>Support minimum MTU size 48 octets (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_4</td>
<td>False</td>
<td>Support MTU size larger than 48 octets (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_5</td>
<td>False</td>
<td>Support of flush timeout value for reliable channel (C.4)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_6</td>
<td>False</td>
<td>Support of flush timeout value for unreliable channel (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_7</td>
<td>False</td>
<td>Support of bi-directional quality of service (QoS) option field (C.1)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_8</td>
<td>False</td>
<td>Negotiate QoS service type (C.5)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_9</td>
<td>False</td>
<td>Negotiate and support service type 'No Traffic' (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_10</td>
<td>False</td>
<td>Negotiate and support service type 'Best effort' (C.3)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_11</td>
<td>False</td>
<td>Negotiate and support service type 'Guaranteed' (C.2)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_12</td>
<td>True</td>
<td>Support minimum MTU size 23 octets (C.6)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_13</td>
<td>False</td>
<td>Negotiate and support service type 'No traffic' for Extended Flow Specification (C.7)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_14</td>
<td>False</td>
<td>Negotiate and support service type 'Best Effort' for Extended Flow Specification (C.8)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_15</td>
<td>False</td>
<td>Negotiate and support service type 'Guaranteed' for Extended Flow Specification (C.9)</td>
</tr>
<tr>
<td>TSPC_L2CAP_3_16</td>
<td>True</td>
<td>Support Multiple Simultaneous LE Data Channels (C.10)</td>
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### Role

<table>
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<tr>
<th>Parameter Name</th>
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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_SM_1_1</td>
<td>True</td>
<td>Central Role (Initiator) (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_1_2</td>
<td>True</td>
<td>Peripheral Role (Responder) (C.2)</td>
</tr>
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Security Properties

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<tr>
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<th>Description</th>
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<tr>
<td>TSPC_SM_2_1</td>
<td>True</td>
<td>Authenticated MITM protection (O)</td>
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<tr>
<td>TSPC_SM_2_2</td>
<td>True</td>
<td>Unauthenticated no MITM protection (C.1)</td>
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<tr>
<td>TSPC_SM_2_3</td>
<td>True</td>
<td>No security requirements (M)</td>
</tr>
<tr>
<td>TSPC_SM_2_4</td>
<td>True</td>
<td>OOB supported (O)</td>
</tr>
<tr>
<td>TSPC_SM_2_5</td>
<td>True</td>
<td>LE Secure Connections (O)</td>
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Encryption Key Size

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<tr>
<td>TSPC_SM_3_1</td>
<td>True</td>
<td>Encryption Key Size (M)</td>
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Pairing Method

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<tr>
<td>TSPC_SM_4_1</td>
<td>True</td>
<td>Just Works (O)</td>
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<tr>
<td>TSPC_SM_4_2</td>
<td>True</td>
<td>Passkey Entry (C.1)</td>
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<tr>
<td>TSPC_SM_4_3</td>
<td>True</td>
<td>Out of Band (C.1)</td>
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Security Initiation

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<tr>
<td>TSPC_SM_5_1</td>
<td>True</td>
<td>Encryption Setup using STK (C.3)</td>
</tr>
<tr>
<td>TSPC_SM_5_2</td>
<td>True</td>
<td>Encryption Setup using LTK (O)</td>
</tr>
<tr>
<td>TSPC_SM_5_3</td>
<td>True</td>
<td>Peripheral Initiated Security (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_5_4</td>
<td>True</td>
<td>Peripheral Initiated Security – Central response (C.2)</td>
</tr>
<tr>
<td>TSPC_SM_5_5</td>
<td>False</td>
<td>Link Key Conversion Function h7 (C.4)</td>
</tr>
<tr>
<td>TSPC_SM_5_6</td>
<td>False</td>
<td>Link Key Conversion Function h6 (C.5)</td>
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Signing Algorithm

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<tr>
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<td>True</td>
<td>Signing Algorithm - Generation (O)</td>
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<tr>
<td>TSPC_SM_6_2</td>
<td>True</td>
<td>Signing Algorithm - Resolving (O)</td>
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Key Distribution

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<tr>
<td>TSPC_SM_7_1</td>
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<td>Encryption Key (C.1)</td>
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<tr>
<td>TSPC_SM_7_2</td>
<td>True</td>
<td>Identity Key (C.2)</td>
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<tr>
<td>TSPC_SM_7_3</td>
<td>True</td>
<td>Signing Key (C.3)</td>
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Cross-Transport Key Derivation

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<tr>
<td>TSPC_SM_8_1</td>
<td>False</td>
<td>Cross Transport Key Derivation Supported (C.1)</td>
</tr>
<tr>
<td>TSPC_SM_8_2</td>
<td>False</td>
<td>Derivation of LE LTK from BR/EDR Link Key (C.2)</td>
</tr>
<tr>
<td>TSPC_SM_8_3</td>
<td>False</td>
<td>Derivation of BR/EDR Link Key from LE LTK (C.2)</td>
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RFCOMM PICS  PTS version: 6.4
- different than PTS defaults
### Protocol Version

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<tr>
<td>TSPC_RFCOMM_0_1</td>
<td>False</td>
<td>RFCOMM 1.1 with TS 07.10</td>
</tr>
<tr>
<td>TSPC_RFCOMM_0_2</td>
<td>True (*)</td>
<td>RFCOMM 1.2 with TS 07.10</td>
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### Supported Procedures

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<th>Description</th>
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<tbody>
<tr>
<td>TSPC_RFCOMM_1_1</td>
<td>True (*)</td>
<td>Initialize RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_2</td>
<td>True (*)</td>
<td>Respond to Initialization of an RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_3</td>
<td>True</td>
<td>Shutdown RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_4</td>
<td>True</td>
<td>Respond to a Shutdown of an RFCOMM Session</td>
</tr>
<tr>
<td>TSPC_RFCOMM_1_5</td>
<td>True (*)</td>
<td>Establish DLC</td>
</tr>
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<td>TSPC_RFCOMM_1_9</td>
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<td>TSPC_RFCOMM_1_10</td>
<td>True</td>
<td>Initiate Transfer Information</td>
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<td>TSPC_RFCOMM_1_11</td>
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<td>React to Aggregate Flow Control</td>
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<td>Respond to RLS Command</td>
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<td>Closing Multiplexer by First Sending a DISC Command</td>
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<td>TSPC_RFCOMM_1_22</td>
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### MESH ICS

PTS version: 8.0.3

- **M** - mandatory
- **O** - optional

#### Major Profile Version (X.Y)

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#### Roles

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### Node Capabilities - Provisioning

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<td>Relay Feature (C.1)</td>
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<td>Network Message Cache (C.2)</td>
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### Node Capabilities – Lower Transport Layer

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### Node Capabilities – Upper Transport Layer

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### Node Capabilities – Access Layer

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### Node Capabilities – Security

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### Node Capabilities – Mesh Management

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<td>Key Refresh Procedure (M)</td>
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### Node Capabilities – Foundation Mesh Models

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<td>Health Server Model (M)</td>
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### Node Capabilities – Proxy

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<td>GATT Server (C.2)</td>
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<td>TSPC_MESH_12_3</td>
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<td>TSPC_MESH_12_4</td>
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### Mesh GATT Services

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### GATT Server Requirements

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<tr>
<td>TSPC_MESH_14_3</td>
<td>True</td>
<td>Write without Response (M)</td>
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<tr>
<td>TSPC_MESH_14_4</td>
<td>True</td>
<td>Notifications (M)</td>
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<tr>
<td>TSPC_MESH_14_5</td>
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<td>Write Characteristic Descriptors (M)</td>
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### GATT Client Requirements

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<td>Discover Primary Services by Service UUID (C.1)</td>
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DIS ICS  PTS version: 8.0.3
M - mandatory
O - optional

**Service Version**

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**Transport Requirements**

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**Service Requirements**

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<tr>
<td>TSPC_DIS_2_8</td>
<td>False</td>
<td>System ID Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_9</td>
<td>False</td>
<td>IEEE 11073-20601 Regulatory Certification Data List Characteristic (O)</td>
</tr>
<tr>
<td>TSPC_DIS_2_10</td>
<td>False</td>
<td>SDP Interoperability (C.1)</td>
</tr>
<tr>
<td>TSPC_DIS_2_11</td>
<td>True</td>
<td>PnP ID (O)</td>
</tr>
</tbody>
</table>

6.1.5 Bluetooth tools

This page lists and describes tools that can be used to assist during Bluetooth stack or application development in order to help, simplify and speed up the development process.

**Mobile applications**

It is often useful to make use of existing mobile applications to interact with hardware running Zephyr, to test functionality without having to write any additional code or requiring extra hardware.

The recommended mobile applications for interacting with Zephyr are:

- **Android:**
  - nRF Connect for Android
  - nRF Mesh for Android
  - LightBlue for Android

- **iOS:**
  - nRF Connect for iOS
  - nRF Mesh for iOS
  - LightBlue for iOS
Using BlueZ with Zephyr

The Linux Bluetooth Protocol Stack, BlueZ, comes with a very useful set of tools that can be used to debug and interact with Zephyr's BLE Host and Controller. In order to benefit from these tools you will need to make sure that you are running a recent version of the Linux Kernel and BlueZ:

- Linux Kernel 4.10+
- BlueZ 4.45+

Additionally, some of the BlueZ tools might not be bundled by default by your Linux distribution. If you need to build BlueZ from scratch to update to a recent version or to obtain all of its tools you can follow the steps below:

```
git clone git://git.kernel.org/pub/scm/bluetooth/bluez.git
cd bluez
./bootstrap-configure --disable-android --disable-midi
make
```

You can then find `btattach`, `btmgmt` and `btproxy` in the `tools/` folder and `btmon` in the `monitor/` folder.

You'll need to enable BlueZ's experimental features so you can access its most recent BLE functionality. Do this by editing the file `/lib/systemd/system/bluetooth.service` and making sure to include the `-E` option in the daemon's execution start line:

```
ExecStart=/usr/libexec/bluetooth/bluetoothd -E
```

Finally, reload and restart the daemon:

```
sudo systemctl daemon-reload
sudo systemctl restart bluetooth
```

Running on QEMU and Native POSIX

It's possible to run Bluetooth applications using either the QEMU emulator or Native POSIX. In either case, a Bluetooth controller needs to be exported from the host OS (Linux) to the emulator. For this purpose you will need some tools described in the Using BlueZ with Zephyr section.

Using the Host System Bluetooth Controller  The host OS's Bluetooth controller is connected in the following manner:

- To the second QEMU serial line using a UNIX socket. This socket gets used with the help of the QEMU option `-serial unix:/tmp/blt-server-bredr`. This option gets passed to QEMU through QEMU_EXTRA_FLAGS automatically whenever an application has enabled Bluetooth support.

- To a serial port in Native POSIX through the use of a command-line option passed to the Native POSIX executable: `--bt-dev=hci0`

On the host side, BlueZ allows you to export its Bluetooth controller through a so-called user channel for QEMU and Native POSIX to use.

**Note:** You only need to run `btproxy` when using QEMU. Native POSIX handles the UNIX socket proxying automatically.

If you are using QEMU, in order to make the Controller available you will need one additional step using `btproxy`:

1. Make sure that the Bluetooth controller is down
2. Use the `btproxy` tool to open the listening UNIX socket, type:
sudo tools/btproxy -u -i 0
Listening on /tmp/bt-server-bredr

You might need to replace -i 0 with the index of the Controller you wish to proxy.

If you see **Received unknown host packet type 0x00** when running QEMU, then add -z to the `btproxy` command line to ignore any null bytes transmitted at startup.

Once the hardware is connected and ready to use, you can then proceed to building and running a sample:

- Choose one of the Bluetooth sample applications located in `samples/bluetooth`.
- To run a Bluetooth application in QEMU, type:

  ```shell
  west build -b qemu_x86 samples/bluetooth/<sample>
  west build -t run
  ```

  Running QEMU now results in a connection with the second serial line to the `bt-server-bredr` UNIX socket, letting the application access the Bluetooth controller.

- To run a Bluetooth application in Native POSIX, first build it:

  ```shell
  west build -b native_posix samples/bluetooth/<sample>
  ```

  And then run it with:

  ```shell
  $ sudo ./build/zephyr/zephyr.exe --bt-dev=hci0
  ```

**Using a Zephyr-based BLE Controller** Depending on which hardware you have available, you can choose between two transports when building a single-mode, Zephyr-based BLE Controller:

- UART: Use the `hci_uart` sample and follow the instructions in `bluetooth-hci-uart-qemu-posix`.
- USB: Use the `hci_usb` sample and then treat it as a Host System Bluetooth Controller (see previous section)

**HCI Tracing** When running the Host on a computer connected to an external Controller, it is very useful to be able to see the full log of exchanges between the two, in the format of a *Host Controller Interface* log. In order to see those logs, you can use the built-in `btmon` tool from BlueZ:

```shell
$ btmon
```

**Using Zephyr-based Controllers with BlueZ**

If you want to test a Zephyr-powered BLE Controller using BlueZ's Bluetooth Host, you will need a few tools described in the *Using BlueZ with Zephyr* section. Once you have installed the tools you can then use them to interact with your Zephyr-based controller:

```shell
sudo tools/btmgmt --index 0
[hci0]# auto-power
[hci0]# find -1
```

You might need to replace `--index 0` with the index of the Controller you wish to manage. Additional information about `btmgmt` can be found in its manual pages.

---

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6.1.6 Developing Bluetooth Applications

Bluetooth applications are developed using the common infrastructure and approach that is described in the Application Development section of the documentation. Additional information that is only relevant to Bluetooth applications can be found in this page.

Hardware setup

This section describes the options you have when building and debugging Bluetooth applications with Zephyr. Depending on the hardware that is available to you, the requirements you have and the type of development you prefer you may pick one or another setup to match your needs.

There are 4 possible hardware setups to use with Zephyr and Bluetooth:

1. Embedded
2. QEMU with an external Controller
3. Native POSIX with an external Controller
4. Simulated nRF52 with BabbleSim

Embedded This setup relies on all software running directly on the embedded platform(s) that the application is targeting. All the Configurations and Build Types are supported but you might need to build Zephyr more than once if you are using a dual-chip configuration or if you have multiple cores in your SoC each running a different build type (e.g., one running the Host, the other the Controller).

To start developing using this setup follow the Getting Started Guide, choose one (or more if you are using a dual-chip solution) boards that support Bluetooth and then run the application).

Embedded HCI tracing When running both Host and Controller in actual Integrated Circuits, you will only see normal log messages on the console by default, without any way of accessing the HCI traffic between the Host and the Controller. However, there is a special Bluetooth logging mode that converts the console to use a binary protocol that interleaves both normal log messages as well as the HCI traffic.

Set the following Kconfig options to enable this protocol before building your application:

```bash
CONFIG_BT_DEBUG_MONITOR_UART=y
CONFIG_UART_CONSOLE=n
```

Setting `CONFIG_BT_DEBUG_MONITOR_UART` to `y` replaces the `CONFIG_BT_DEBUG_LOG` option, and setting `CONFIG_UART_CONSOLE` to `n` disables the default printk/printf hooks.

To decode the binary protocol that will now be sent to the console UART you need to use the btmon tool from BlueZ:

```bash
$ btmon --tty <console TTY> --tty-speed 115200
```

Host on Linux with an external Controller

Note: This is currently only available on GNU/Linux

This setup relies on a “dual-chip” configuration which is comprised of the following devices:

1. A Host-only application running in the QEMU emulator or the native_posix native port of Zephyr
2. A Controller, which can be one of two types:
   - A commercially available Controller
   - A Controller-only build of Zephyr
Warning: Certain external Controllers are either unable to accept the Host to Controller flow control parameters that Zephyr sets by default (Qualcomm), or do not transmit any data from the Controller to the Host (Realtek). If you see a message similar to:

```
<wrn> bt_hci_core: opcode 0x0c33 status 0x12
```

when booting your sample of choice (make sure you have enabled CONFIG_BT_DEBUG_LOG in your prj.conf before running the sample), or if there is no data flowing from the Controller to the Host, then you need to disable Host to Controller flow control. To do so, set CONFIG_BT_HCI_ACL_FLOW_CONTROL=n in your prj.conf.

QEMU You can run the Zephyr Host on the QEMU emulator and have it interact with a physical external Bluetooth Controller. Refer to Running on QEMU and Native POSIX for full instructions on how to build and run an application in this setup.

Native POSIX

Note: This is currently only available on GNU/Linux

The Native POSIX target builds your Zephyr application with the Zephyr kernel, and some minimal HW emulation as a native Linux executable. This executable is a normal Linux program, which can be debugged and instrumented like any other, and it communicates with a physical external Controller.

Refer to Running on QEMU and Native POSIX for full instructions on how to build and run an application in this setup.

Simulated nRF52 with BabbleSim

Note: This is currently only available on GNU/Linux

The nrf52_bsim board, is a simulated target board which emulates the necessary peripherals of a nrf52 SOC to be able to develop and test BLE applications. This board, uses:

- BabbleSim to simulate the nrf52 modem and the radio environment.
- The POSIX arch to emulate the processor.
- Models of the nrf52 HW

Just like with the native_posix target, the build result is a normal Linux executable. You can find more information on how to run simulations with one or several devices in this board's documentation.

Currently, only Combined builds are possible, as this board does not yet have any models of a UART, or USB which could be used for an HCI interface towards another real or simulated device.

Initialization

The Bluetooth subsystem is initialized using the bt_enable() function. The caller should ensure that function succeeds by checking the return code for errors. If a function pointer is passed to bt_enable(), the initialization happens asynchronously, and the completion is notified through the given function.

Bluetooth Application Example

A simple Bluetooth beacon application is shown below. The application initializes the Bluetooth Subsystem and enables non-connectable advertising, effectively acting as a Bluetooth Low Energy broadcaster.
/* Set Advertisement data. Based on the Eddystone specification:
 * https://github.com/google/eddystone/blob/master/protocol-specification.md
 * https://github.com/google/eddystone/tree/master/eddystone-url
 */

static const struct bt_data ad[] = {
    BT_DATA_BYTES(BT_DATA_FLAGS, BT_LE_AD_NO_BREDR),
    BT_DATA_BYTES(BT_DATA_UUID16_ALL, 0xaa, 0xfe),
    BT_DATA_BYTES(BT_DATA_SVC_DATA16,
        0xaa, 0xfe, /* Eddystone UUID */
        0x10, /* Eddystone-URL frame type */
        0x00, /* Calibrated Tx power at 0m */
        0x00, /* URL Scheme Prefix http://www. */
        'z', 'e', 'p', 'h', 'y', 'r',
        'p', 'r', 'o', 'j', 'e', 'c', 't',
        0x08) /* .org */
};

/* Set Scan Response data */

static const struct bt_data sd[] = {
    BT_DATA(BT_DATA_NAME_COMPLETE, DEVICE_NAME, DEVICE_NAME_LEN),
};

static void bt_ready(int err)
{
    char addr_s[BT_ADDR_LE_STR_LEN];
    bt_addr_le_t addr = {0};
    size_t count = 1;

    if (err) {
        printk("Bluetooth init failed (err %d)\n", err);
        return;
    }

    printk("Bluetooth initialized\n");

    /* Start advertising */
    err = bt_le_adv_start(BT_LE_ADV_NCONN.IDENTITY, ad, ARRAY_SIZE(ad),
        sd, ARRAY_SIZE(sd));
    if (err) {
        printk("Advertising failed to start (err %d)\n", err);
        return;
    }

    /* For connectable advertising you would use
     * bt_le_oob_get_local(). For non-connectable non-identity
     * advertising an non-resolvable private address is used;
     * there is no API to retrieve that.
     */

    bt_id_get(&addr, &count);
    bt_addr_le_to_str(&addr, addr_s, sizeof(addr_s));
    printk("Beacon started, advertising as %s\n", addr_s);
}
(continues on next page)
The key APIs employed by the beacon sample are `bt_enable()` that's used to initialize Bluetooth and then `bt_le_adv_start()` that's used to start advertising a specific combination of advertising and scan response data.

### 6.1.7 AutoPTS on Windows 10 with nRF52 board

**Overview**

This tutorial shows how to setup AutoPTS client and server to run both on Windows 10. We use WSL1 with Ubuntu only to build a Zephyr project to an elf file, because Zephyr SDK is not available on Windows yet. Tutorial covers only nRF52840dk.

**Update Windows and drivers**

Update Windows in:

* Start -> Settings -> Update & Security -> Windows Update

Update drivers, following the instructions from your hardware vendor.

**Install Python 3**

Download and install Python 3. Setup was tested with versions >=3.8. Let the installer add the Python installation directory to the PATH and disable the path length limitation.
Install Git

Download and install Git. During installation enable option: Enable experimental support for pseudo consoles. We will use Git Bash as Windows terminal.
Install PTS 8

Install latest PTS from https://www.bluetooth.org. Remember to install drivers from installation directory “C:/Program Files (x86)/Bluetooth SIG/Bluetooth PTS/PTS Driver/win64/CSRBlueCoreUSB.inf”

Note: Starting with PTS 8.0.1 the Bluetooth Protocol Viewer is no longer included. So to capture Bluetooth events, you have to download it separately.

Setup Zephyr project for Windows

Perform Windows setup from Getting Started Guide.

Install nrftools

Connect devices
**Flash board**

In Device Manager find COM port of your nrf board. In my case it is COM3.
In Git Bash, go to zephyrproject

```bash
cd ~/zephyrproject
```

Build the auto-pts tester app

```bash
west build -p auto -b nrf52840dk_nrf52840 zephyr/tests/bluetooth/tester/
```

You can display flashing options with:

```bash
west flash --help
```

and flash board with built earlier elf file:

```bash
west flash --skip-rebuild --board-dir /dev/ttyS2 --elf-file ~/zephyrproject/build/zephyr/zephyr.elf
```

Note that west does not accept COMs, so use /dev/ttyS2 as the COM3 equivalent, /dev/ttyS2 as the COM3 equivalent, etc. (/dev/ttyS + decremented COM number).

**Setup auto-pts project**

In Git Bash, clone project repo:

```bash
git clone https://github.com/intel/auto-pts.git
```

Go into the project folder:

```bash
cd auto-pts
```

Install required python modules:
pip3 install --user wheel
pip3 install --user -r autoptsserver_requirements.txt
pip3 install --user -r autoptsclient_requirements.txt

Install socat.exe

Download and extract socat.exe from https://sourceforge.net/projects/unix-utils/files/socat/1.7.3.2/ into folder ~/socat-1.7.3.2-1-x86_64/.

Add path to directory of socat.exe to PATH:
Running AutoPTS

Server and client by default will run on localhost address. Run server:

```bash
python ./autoptsserver.py -S 65000
```

**Note:** If the error “ImportError: No module named pywintypes” appeared after the fresh setup, uninstall and install the pywin32 module:

```bash
pip install --upgrade --force-reinstall pywin32
```

Run client:

```bash
python ./autoptsclient-zephyr.py zephyr-master ~/zephyrproject/build/zephyr/zephyr.˓→elf -t COM3 -b nrf52 -S 65000 -C 65001
```
At the first run, when Windows asks, enable connection through firewall:

---

Troubleshooting

- “When running actual hardware test mode, I have only BTP TIMEOUTs.”

This is a problem with connection between auto-pts client and board. There are many possible causes. Try:

- Clean your auto-pts and zephyr repos with

  Warning: This command will force the irreversible removal of all uncommitted files in the repo.

  ```
git clean -fdx
  ```

then build and flash tester elf again.
• If you have set up Windows on virtual machine, check if guest extensions are installed properly or change USB compatibility mode in VM settings to USB 2.0.
• Check, if firewall in not blocking python.exe or socat.exe.
• Check if board sends ready event after restart (hex 00 00 80 ff 00 00). Open serial connection to board with e.g. PuTTy with proper COM and baud rate. After board reset you should see some strings in console.
• Check if socat.exe creates tunnel to board. Run in console

```
socat.exe -x -v tcp-listen:65123 /dev/ttyS2,raw,b115200
```

where /dev/ttyS2 is the COM3 equivalent. Open PuTTy, set connection type to Raw, IP to 127.0.0.1, port to 65123. After board reset you should see some strings in console.

### 6.1.8 AutoPTS on Linux

#### Overview

This tutorial shows how to setup AutoPTS client on Linux with AutoPTS server running on Windows 10 virtual machine. Tested with Ubuntu 20.4 and Linux Mint 20.4.

You must have a Zephyr development environment set up. See [Getting Started Guide](#) for details.

Supported methods to test zephyr bluetooth host:

- Testing Zephyr Host Stack on QEMU
- Testing Zephyr Host Stack on native posix
- Testing Zephyr combined (controller + host) build on Real hardware (such as nRF52)

For running with QEMU or native posix, see [Running on QEMU and Native POSIX](#).

#### Setup Linux

**Install nrftools (only required in the actual hardware test mode)**

After you extract archive, you will see 2 .deb files, e.g.:

- JLink_Linux_V688a_x86_64.deb
- nRF-Command-Line-Tools_10_12_1_Linux-amd64.deb

and README.md. To install the tools, double click on each .deb file or follow instructions from README.md.

**Setup Windows 10 virtual machine**

Choose and install your hypervisor like VMWare Workstation(preferred) or VirtualBox. On VirtualBox could be some issues, if your host has fewer than 6 CPU.

Create Windows virtual machine instance. Make sure it has at least 2 cores and installed guest extensions. Setup tested with VirtualBox 6.1.18 and VMWare Workstation 16.1.1 Pro.

**Update Windows**  Update Windows in:  
Start -> Settings -> Update & Security -> Windows Update

**Setup static IP**

**VMWare Works**  On Linux, open Virtual Network Editor app and create network:
Open virtual machine network settings. Add custom adapter:

If you type 'ifconfig' in terminal, you should be able to find your host IP:
VirtualBox  Go to:
File -> Host Network Manager
and create network:

Open virtual machine network settings. On adapter 1 you will have created by default NAT. Add adapter 2:
Windows  Setup static IP on Windows virtual machine. Go to Settings -> Network & Internet -> Ethernet -> Unidentified network -> Edit and set:
Install Python 3  Download and install latest Python 3 on Windows. Let the installer add the Python installation directory to the PATH and disable the path length limitation.

Install Git  Download and install Git. During installation enable option: Enable experimental support for pseudo consoles. We will use Git Bash as Windows terminal.
Install PTS 8  On Windows virtual machine, install latest PTS from https://www.bluetooth.org. Remember to install drivers from installation directory “C:/Program Files (x86)/Bluetooth SIG/Bluetooth PTS/PTS Driver/win64/CSRBlueCoreUSB.inf”

Note: Starting with PTS 8.0.1 the Bluetooth Protocol Viewer is no longer included. So to capture Bluetooth events, you have to download it separately.

Connect PTS dongle  With VirtualBox there should be no problem. Just find dongle in Devices -> USB and connect.

With VMWare you might need to use some trick, if you cannot find dongle in VM -> Removable Devices. Type in Linux terminal:

`usb-devices`

and find in output your PTS Bluetooth USB dongle
Note Vendor and ProdID number. Close VMWare Workstation and open .vmx of your virtual machine (path similar to /home/codecoup/vmware/Windows 10/Windows 10.vmx) in text editor. Write anywhere in the file following line:

```
usb.autoConnect.device0 = "0x0a12:0x0001"
```

just replace 0xa12 with Vendor number and 0x0001 with ProdID number you found earlier.

Connect devices (only required in the actual hardware test mode)
Flash board (only required in the actual hardware test mode)

On Linux, go to ~/zephyrproject. There should be already ~/zephyrproject/build directory. Flash board:

```
west flash
```

Setup auto-pts project

AutoPTS client on Linux  Clone auto-pts project:
git clone https://github.com/intel/auto-pts.git

Install socat, that is used to transfer BTP data stream from UART’s tty file:

```bash
sudo apt-get install python-setuptools socat
```

Install required python modules:

```bash
cd auto-pts
pip3 install --user wheel
pip3 install --user -r autoptsclient_requirements.txt
```

**Autopts server on Windows virtual machine**  In Git Bash, clone auto-pts project repo:

```bash
git clone https://github.com/intel/auto-pts.git
```

Install required python modules:

```bash
cd auto-pts
pip3 install --user wheel
pip3 install --user -r autoptsserver_requirements.txt
```

Restart virtual machine.

**Running AutoPTS**

Server and client by default will run on localhost address. Run server:

```bash
python ./autoptsserver.py
```

Testing Zephyr Host Stack on QEMU:

```bash
# A Bluetooth controller needs to be mounted.
# For running with HCI UART, please visit: https://docs.zephyrproject.org/latest/
# samples/bluetooth/hci_uart/README.html#bluetooth-hci-uart
python ./autoptsclient-zephyr.py "C:\Users\USER_NAME\Documents\Profile Tuning Suite\PTS_PROJECT\PTS_PROJECT.pqw6" \
~/zephyrproject/build/zephyr/zephyr.elf -i SERVER_IP -l LOCAL_IP
```

Testing Zephyr Host Stack on native posix:

```bash
# A Bluetooth controller needs to be mounted.
# For running with HCI UART, please visit: https://docs.zephyrproject.org/latest/
# samples/bluetooth/hci_uart/README.html#bluetooth-hci-uart
west build -b native_posix zephyr/tests/bluetooth/tester/ -DOVERLAY_CONFIG=overlay-\n~native.conf
```

(continues on next page)
Testing Zephyr combined (controller + host) build on nRF52:

**Note:** If the error “ImportError: No module named pywintypes” appeared after the fresh setup, uninstall and install the pywin32 module:

```
pip install --upgrade --force-reinstall pywin32
```

Run client:

```
python ./autoptsclient-zephyr.py zephyr-master ~/zephyrproject/build/zephyr/zephyr.elf -t /dev/ACM0 -b nrf52 -l 192.168.2.1 -i 192.168.2.2
```

At the first run, when Windows asks, enable connection through firewall:
Troubleshooting

- “After running one test, I need to restart my Windows virtual machine to run another, because of fail verdict from APICOM in PTS logs.”

It means your virtual machine has not enough processor cores or memory. Try to add more in settings. Note that a host with 4 CPUs could be not enough with VirtualBox as hypervisor. In this case, choose rather VMWare Workstation.

- “I cannot start autoptsserver-zephyr.py. I always got error:"

One or more of the following steps should help:

- Close all PTS Windows.
- Replug PTS bluetooth dongle.
- Delete temporary workspace. You will find it in auto-pts-code/workspaces/zephyr/zephyr-master/ as temp_zephyr-master. Be careful, do not remove the original one zephyr-master.pqw6.
- Restart Windows virtual machine.

6.1.9 Bluetooth APIs

Attribute Protocol (ATT)

API Reference

**group bt_att**

Attribute Protocol (ATT)

**Defines**

- **BT_ATT_ERR_SUCCESS**
- **BT_ATT_ERR_INVALID_HANDLE**
- **BT_ATT_ERR_READ_NOT_PERMITTED**
BT_ATT_ERR_WRITE_NOT_PERMITTED
BT_ATT_ERR_INVALID_PDU
BT_ATT_ERR_AUTHENTICATION
BT_ATT_ERR_NOT_SUPPORTED
BT_ATT_ERR_INVALID_OFFSET
BT_ATT_ERR_AUTHORIZATION
BT_ATT_ERR_PREPARE_QUEUE_FULL
BT_ATT_ERR_ATTRIBUTE_NOT_FOUND
BT_ATT_ERR_ATTRIBUTE_NOT_LONG
BT_ATT_ERR_ENCRYPTION_KEY_SIZE
BT_ATT_ERR_INVALID_ATTRIBUTE_LEN
BT_ATT_ERR_UNLIKELY
BT_ATT_ERR_INSUFFICIENT_ENCRYPTION
BT_ATT_ERR_UNSUPPORTED_GROUP_TYPE
BT_ATT_ERR_INSUFFICIENT_RESOURCES
BT_ATT_ERR_DB_OUT_OF_SYNC
BT_ATT_ERR_VALUE_NOT_ALLOWED
BT_ATT_ERR_WRITE_REQ_REJECTED
BT_ATT_ERR_CCC_IMPROPER_CONF
BT_ATT_ERR_PROCEDURE_IN_PROGRESS
BT_ATT_ERR_OUT_OF_RANGE
BT_ATT_MAX_ATTRIBUTE_LEN
BT_ATT_FIRST_ATTRIBUTE_HANDLE
BT_ATT_FIRST_ATTRIBUTE_HANDLE

BT_ATT_LAST_ATTRIBUTE_HANDLE

BT_ATT_LAST_ATTRIBUTE_HANDLE

 Enums

 enum bt_att_chan_opt
     
     ATT channel option bit field values.

     **Note:** `BT_ATT_CHAN_OPT_UNENHANCED_ONLY` and `BT_ATT_CHAN_OPT_ENHANCED_ONLY` are mutually exclusive and both bits may not be set.

     Values:

     enumerator BT_ATT_CHAN_OPT_NONE = 0x0
         Both Enhanced and Unenhanced channels can be used

     enumerator BT_ATT_CHAN_OPT_UNENHANCED_ONLY = BIT(0)
         Only Unenhanced channels will be used

     enumerator BT_ATT_CHAN_OPT_ENHANCED_ONLY = BIT(1)
         Only Enhanced channels will be used

 Functions

 int bt_eatt_connect(struct bt_conn *conn, size_t num_channels)
     Connect Enhanced ATT channels.

     Sends a series of Credit Based Connection Requests to connect `num_channels` Enhanced ATT channels. The peer may have limited resources and fewer channels may be created.

     **Parameters**

     • conn – The connection to send the request on
     • num_channels – The number of Enhanced ATT beares to request. Must be in the range 1 - `CONFIG_BT_EATT_MAX`, inclusive.

     **Return values**

     • -EINVAL – if `num_channels` is not in the allowed range or `conn` is NULL.
     • -ENOMEM – if less than `num_channels` are allocated.
     • 0 – in case of success

     **Returns**

     0 in case of success or negative value in case of error.

 size_t bt_eatt_count(struct bt_conn *conn)
     Get number of EATT channels connected.

     **Parameters**

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• conn – The connection to get the number of EATT channels for.

**Returns**
The number of EATT channels connected. Returns 0 if conn is NULL or not connected.

**Bluetooth Audio**

**API Reference**

**group** bt_audio

Bluetooth Audio.

**Defines**

BT_AUDIO_BROADCAST_ID_SIZE

BT_AUDIO_CONTEXT_TYPE_ANY
    Any known context.

BT_AUDIO_UNICAST_ANNOUNCEMENT_GENERAL

BT_AUDIO_UNICAST_ANNOUNCEMENT_TARGETED

BROADCAST_SNK_STREAM_CNT

BROADCAST_SNK_SUBGROUP_CNT

BT_CODEC_DATA(_type, _bytes...)
    Helper to declare elements of bt_codec_data arrays.
    This macro is mainly for creating an array of struct bt_codec_data elements inside bt_codec
    which is then passed to the likes of bt_audio_stream_config or bt_audio_stream_reconfig.

**Parameters**

• _type – Type of advertising data field
• _bytes – Variable number of single-byte parameters

BT_CODEC(_id, _cid, _vid, _data, _meta)
    Helper to declare bt_codec structure.

**Parameters**

• _id – Codec ID
• _cid – Company ID
• _vid – Vendor ID
• _data – Codec Specific Data in IVT format
• _meta – Codec Specific Metadata in IVT format
BT_CODEC_QOS(interval, framing, phy, sdu, rtn, latency, pd)
Helper to declare elements of bt_codec_qos.

Parameters

- interval – SDU interval (usec)
- framing – Framing
- phy – Target PHY
- sdu – Maximum SDU Size
- rtn – Retransmission number
- latency – Maximum Transport Latency (msec)
- pd – Presentation Delay (usec)

BT_CODEC_QOS_UNFRAMED(interval, sdu, rtn, latency, pd)
Helper to declare Input Unframed bt_codec_qos.

Parameters

- interval – SDU interval (usec)
- sdu – Maximum SDU Size
- rtn – Retransmission number
- latency – Maximum Transport Latency (msec)
- pd – Presentation Delay (usec)

BT_CODEC_QOS_FRAMED(interval, sdu, rtn, latency, pd)
Helper to declare Input Framed bt_codec_qos.

Parameters

- interval – SDU interval (usec)
- sdu – Maximum SDU Size
- rtn – Retransmission number
- latency – Maximum Transport Latency (msec)
- pd – Presentation Delay (usec)

BT_CODEC_QOS_PREF(unframed_supported, phy, rtn, latency, pd_min, pd_max, pref_pd_min, pref_pd_max)
Helper to declare elements of bt_codec_qos_pref.

Parameters

- unframed_supported – Unframed PDUs supported
- phy – Preferred Target PHY
- rtn – Preferred Retransmission number
- latency – Preferred Maximum Transport Latency (msec)
- pd_min – Minimum Presentation Delay (usec)
- pd_max – Maximum Presentation Delay (usec)
- pref_pd_min – Preferred Minimum Presentation Delay (usec)
- pref_pd_max – Preferred Maximum Presentation Delay (usec)

BT_AUDIO_LC3_PRESET(codec, qos)
Helper to declare an LC3 preset structure
BT_AUDIO_LC3_UNICAST_PRESET_8_1_1(_loc, _stream_context)

Helper to declare LC3 Unicast 8_1_1 codec configuration.

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_8_2_1(_loc, _stream_context)

Helper to declare LC3 Unicast 8_2_1 codec configuration.

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_16_1_1(_loc, _stream_context)

Helper to declare LC3 Unicast 16_1_1 codec configuration.

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_16_2_1(_loc, _stream_context)

Helper to declare LC3 Unicast 16_2_1 codec configuration.

Mandatory to support as both unicast client and server

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_24_1_1(_loc, _stream_context)

Helper to declare LC3 Unicast 24_1_1 codec configuration.

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_24_2_1(_loc, _stream_context)

Helper to declare LC3 Unicast 24_2_1 codec configuration.

Mandatory to support as unicast server

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_32_1_1(_loc, _stream_context)

Helper to declare LC3 Unicast 32_1_1 codec configuration.

Parameters

• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_32_2_1(_loc, _stream_context)

Helper to declare LC3 Unicast 32_2_1 codec configuration.
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_441_1_1(_loc, _stream_context)
Helper to declare LC3 Unicast 441_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_441_2_1(_loc, _stream_context)
Helper to declare LC3 Unicast 441_2_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_1_1(_loc, _stream_context)
Helper to declare LC3 Unicast 48_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_2_1(_loc, _stream_context)
Helper to declare LC3 Unicast 48_2_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_3_1(_loc, _stream_context)
Helper to declare LC3 Unicast 48_3_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_4_1(_loc, _stream_context)
Helper to declare LC3 Unicast 48_4_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_5_1(_loc, _stream_context)
Helper to declare LC3 Unicast 8_5_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIOCONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_6_1(_loc, _stream_context)
Helper to declare LC3 Unicast 48_6_1 codec configuration.
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_8_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 8_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_8_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 8_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_16_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 16_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_16_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 16_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_24_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 24_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_24_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 24_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_32_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 32_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (`bt_audio_location`)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_32_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 32_2_2 codec configuration.
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_441_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 441_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_441_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 441_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_1_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_2_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_3_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_3_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_4_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_4_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_5_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_5_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_UNICAST_PRESET_48_6_2(_loc, _stream_context)
Helper to declare LC3 Unicast 48_6_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_8_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 8_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_8_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 8_2_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_16_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 16_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_16_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 16_2_1 codec configuration.
Mandatory to support as both broadcast source and sink

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_24_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 24_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_24_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 24_2_1 codec configuration.
Mandatory to support as broadcast sink

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_32_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 32_1_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)
BT_AUDIO_LC3_BROADCAST_PRESET_32_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 32_2_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_441_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 441_1_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_441_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 441_2_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_1_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_1_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_2_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_2_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_3_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_3_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_4_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_4_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_5_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_5_1 codec configuration.

Parameters
- _loc – Audio channel location bitfield (bt_audio_location)
- _stream_context – Stream context (BT_AUDIO_CONTEXT_*)
BT_AUDIO_LC3_BROADCAST_PRESET_48_6_1(_loc, _stream_context)
Helper to declare LC3 Broadcast 48_6_1 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_8_1_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 8_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_8_2_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 8_2_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_16_1_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 16_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_16_2_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 16_2_2 codec configuration.

Mandatory to support as both broadcast source and sink

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_24_1_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 24_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_24_2_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 24_2_2 codec configuration.

Mandatory to support as broadcast sink

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_32_1_2(_loc, _stream_context)
Helper to declare LC3 Broadcast 32_1_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_32_2_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 32_2_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_441_1_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 441_1_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_441_2_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 441_2_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_48_1_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 48_1_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_48_2_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 48_2_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_48_3_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 48_3_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_48_4_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 48_4_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (*bt_audio_location*)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

**BT_AUDIO_LC3_BROADCAST_PRESET_48_5_2(_loc, _stream_context)**

Helper to declare LC3 Broadcast 48_5_2 codec configuration.

**Parameters**
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

BT_AUDIO_LC3_BROADCAST_PRESET_48_6_2(_loc, _stream_context)

Helper to declare LC3 Broadcast 48_6_2 codec configuration.

Parameters
• _loc – Audio channel location bitfield (bt_audio_location)
• _stream_context – Stream context (BT_AUDIO_CONTEXT_*)

Enums

enum bt_audio_context

Audio Context Type for Generic Audio.
These values are defined by the Generic Audio Assigned Numbers, bluetooth.com

Values:

enumerator BT_AUDIO_CONTEXT_TYPE_PROHIBITED = 0
enumerator BT_AUDIO_CONTEXT_TYPE_UNSPECIFIED = BIT(0)
enumerator BT_AUDIO_CONTEXT_TYPE_CONVERSATIONAL = BIT(1)
enumerator BT_AUDIO_CONTEXT_TYPE_MEDIA = BIT(2)
enumerator BT_AUDIO_CONTEXT_TYPE_GAME = BIT(3)
enumerator BT_AUDIO_CONTEXT_TYPE_INSTRUCTIONAL = BIT(4)
enumerator BT_AUDIO_CONTEXT_TYPE_VOICE_ASSISTANTS = BIT(5)
enumerator BT_AUDIO_CONTEXT_TYPE_LIVE = BIT(6)
enumerator BT_AUDIO_CONTEXT_TYPE_SOUND_EFFECTS = BIT(7)
enumerator BT_AUDIO_CONTEXT_TYPE_NOTIFICATIONS = BIT(8)
enumerator BT_AUDIO_CONTEXT_TYPE_RINGTONE = BIT(9)
enumerator BT_AUDIO_CONTEXT_TYPE_ALERTS = BIT(10)
enumerator BT_AUDIO_CONTEXT_TYPE_EMERGENCY_ALARM = BIT(11)
enum bt_audio_parental_rating
    Parental rating defined by the Generic Audio assigned numbers (bluetooth.com).
The numbering scheme is aligned with Annex F of EN 300 707 v1.2.1 which defined parental rating for viewing.
Values:

enumerator BT_AUDIO_PARENTAL_RATING_NO_RATING = 0x00
enumerator BT_AUDIO_PARENTAL_RATING_AGE_ANY = 0x01
enumerator BT_AUDIO_PARENTAL_RATING_AGE_5_OR ABOVE = 0x02
enumerator BT_AUDIO_PARENTAL_RATING_AGE_6_OR ABOVE = 0x03
enumerator BT_AUDIO_PARENTAL_RATING_AGE_7_OR ABOVE = 0x04
enumerator BT_AUDIO_PARENTAL_RATING_AGE_8_OR ABOVE = 0x05
enumerator BT_AUDIO_PARENTAL_RATING_AGE_9_OR ABOVE = 0x06
enumerator BT_AUDIO_PARENTAL_RATING_AGE_10_OR ABOVE = 0x07
enumerator BT_AUDIO_PARENTAL_RATING_AGE_11_OR ABOVE = 0x08
enumerator BT_AUDIO_PARENTAL_RATING_AGE_12_OR ABOVE = 0x09
enumerator BT_AUDIO_PARENTAL_RATING_AGE_13_OR ABOVE = 0x0A
enumerator BT_AUDIO_PARENTAL_RATING_AGE_14_OR ABOVE = 0x0B
enumerator BT_AUDIO_PARENTAL_RATING_AGE_15_OR ABOVE = 0x0C
enumerator BT_AUDIO_PARENTAL_RATING_AGE_16_OR ABOVE = 0x0D
enumerator BT_AUDIO_PARENTAL_RATING_AGE_17_OR ABOVE = 0x0E
enumerator BT_AUDIO_PARENTAL_RATING_AGE_18_OR ABOVE = 0x0F

enum bt_audio_metadata_type
    Codec metadata type IDs.
    Metadata types defined by the Generic Audio assigned numbers (bluetooth.com).
    Values:
enumerator BT_AUDIO_METADATA_TYPE_PREF_CONTEXT = 0x01
Preferred audio context.

Bitfield of preferred audio contexts.
If 0, the context type is not a preferred use case for this codec configuration.
See the BT_AUDIO_CONTEXT_* for valid values.

enumerator BT_AUDIO_METADATA_TYPE_STREAM_CONTEXT = 0x02
Streaming audio context.

Bitfield of streaming audio contexts.
If 0, the context type is not a preferred use case for this codec configuration.
See the BT_AUDIO_CONTEXT_* for valid values.

enumerator BT_AUDIO_METADATA_TYPE_PROGRAM_INFO = 0x03
UTF-8 encoded title or summary of stream content

enumerator BT_AUDIO_METADATA_TYPE_STREAM_LANG = 0x04
Stream language.

3 octet lower case language code defined by ISO 639-3

enumerator BT_AUDIO_METADATA_TYPE_CCID_LIST = 0x05
Array of 8-bit CCID values

enumerator BT_AUDIO_METADATA_TYPE_PARENTAL_RATING = 0x06
Parental rating.

See @ref bt_audio_parental_rating for valid values.

enumerator BT_AUDIO_METADATA_TYPE_PROGRAM_INFO_URI = 0x07
UTF-8 encoded URI for additional Program information

enumerator BT_AUDIO_METADATA_TYPE_EXTENDED = 0xFE
Extended metadata

enumerator BT_AUDIO_METADATA_TYPE_VENDOR = 0xFF
Vendor specific metadata
enum bt_audio_location
{
    Location values for BT Audio.
    These values are defined by the Generic Audio Assigned Numbers, bluetooth.com

Values:

    enumerator BT_AUDIO_LOCATION_FRONT_LEFT = BIT(0)
    enumerator BT_AUDIO_LOCATION_FRONT_RIGHT = BIT(1)
    enumerator BT_AUDIO_LOCATION_FRONT_CENTER = BIT(2)
    enumerator BT_AUDIO_LOCATION_LOW_FREQ_EFFECTS_1 = BIT(3)
    enumerator BT_AUDIO_LOCATION_BACK_LEFT = BIT(4)
    enumerator BT_AUDIO_LOCATION_BACK_RIGHT = BIT(5)
    enumerator BT_AUDIO_LOCATION_FRONT_LEFT_OF_CENTER = BIT(6)
    enumerator BT_AUDIO_LOCATION_FRONT_RIGHT_OF_CENTER = BIT(7)
    enumerator BT_AUDIO_LOCATION_BACK_CENTER = BIT(8)
    enumerator BT_AUDIO_LOCATION_LOW_FREQ_EFFECTS_2 = BIT(9)
    enumerator BT_AUDIO_LOCATION_SIDE_LEFT = BIT(10)
    enumerator BT_AUDIO_LOCATION_SIDE_RIGHT = BIT(11)
    enumerator BT_AUDIO_LOCATION_TOP_FRONT_LEFT = BIT(12)
    enumerator BT_AUDIO_LOCATION_TOP_FRONT_RIGHT = BIT(13)
    enumerator BT_AUDIO_LOCATION_TOP_FRONT_CENTER = BIT(14)
    enumerator BT_AUDIO_LOCATION_TOP_CENTER = BIT(15)
    enumerator BT_AUDIO_LOCATION_TOP_BACK_LEFT = BIT(16)
    enumerator BT_AUDIO_LOCATION_TOP_BACK_RIGHT = BIT(17)
    enumerator BT_AUDIO_LOCATION_TOP_SIDE_LEFT = BIT(18)
    enumerator BT_AUDIO_LOCATION_TOP_SIDE_RIGHT = BIT(19)
enumerator BT_AUDIO_LOCATION_TOP_BACK_CENTER = \textit{BIT}(20)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_CENTER = \textit{BIT}(21)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_LEFT = \textit{BIT}(22)

enumerator BT_AUDIO_LOCATION_BOTTOM_FRONT_RIGHT = \textit{BIT}(23)

enumerator BT_AUDIO_LOCATION_FRONT_LEFT_WIDE = \textit{BIT}(24)

enumerator BT_AUDIO_LOCATION_FRONT_RIGHT_WIDE = \textit{BIT}(25)

enumerator BT_AUDIO_LOCATION_LEFT_SURROUND = \textit{BIT}(26)

enumerator BT_AUDIO_LOCATION_RIGHT_SURROUND = \textit{BIT}(27)

\begin{verbatim}
enum bt_audio_dir
    Audio Capability type.
    Values:
    
enumerator BT_AUDIO_DIR_SINK = 0x01
    enumerator BT_AUDIO_DIR_SOURCE = 0x02
\end{verbatim}

\begin{verbatim}
enum [anonymous]
    Codec QoS Framing.
    Values:
    
enumerator BT_CODEC_QOS_UNFRAMED = 0x00
    enumerator BT_CODEC_QOS_FRAMED = 0x01
\end{verbatim}

\begin{verbatim}
enum [anonymous]
    Codec QoS Preferred PHY.
    Values:
    
enumerator BT_CODEC_QOS_1M = \textit{BIT}(0)
    enumerator BT_CODEC_QOS_2M = \textit{BIT}(1)
    enumerator BT_CODEC_QOS_CODED = \textit{BIT}(2)
\end{verbatim}
Functions

```c
int bt_audio_unicast_client_register_cb(const struct bt_audio_unicast_client_cb *cb)
```
Register unicast client callbacks.

Only one callback structure can be registered, and attempting to registering more than one will result in an error.

**Parameters**
- `cb` – Unicast client callback structure.

**Returns**
- 0 in case of success or negative value in case of error.

```c
void bt_audio_stream_cb_register(struct bt_audio_stream *stream, struct bt_audio_stream_ops *ops)
```
Register Audio callbacks for a stream.

**Parameters**
- `stream` – Stream object.
- `ops` – Stream operations structure.

```c
struct bt_codec_data
#include <audio.h> Codec configuration structure.
```

```c
struct bt_codec
#include <audio.h> Codec structure.
```

**Public Members**

```c
uint8_t path_id
```
Data path ID

- `BT_ISO_DATA_PATH_HCI` for HCI path, or any other value for vendor specific ID.

```c
uint8_t id
```
Codec ID

```c
uint16_t cid
```
Codec Company ID

```c
uint16_t vid
```
Codec Company Vendor ID

```c
struct bt_audio_base_bis_data
#include <audio.h>
```

```c
struct bt_audio_base_subgroup
#include <audio.h>
```
Public Members

struct bt_codec codec
    Codec information for the subgroup
    If the data_count of the codec is 0, then codec specific data may be found for each BIS in the bis_data.

struct bt_audio_base
    #include <audio.h>

struct bt_codec_qos
    #include <audio.h> Codec QoS structure.

Public Members

uint8_t phy
    QoS PHY

uint8_t framing
    QoS Framing

uint8_t rtn
    QoS Retransmission Number

uint16_t sdu
    QoS SDU

uint16_t latency
    QoS Transport Latency

uint32_t interval
    QoS Frame Interval

uint32_t pd
    QoS Presentation Delay

struct bt_codec_qos_pref
    #include <audio.h> Audio Stream Quality of Service Preference structure.

Public Members

bool unframed_supported
    Unframed PDUs supported.
    Unlike the other fields, this is not a preference but whether the codec supports unframed ISOAL PDUs.
uint8_t phy
   Preferred PHY

uint8_t rtn
   Preferred Retransmission Number

uint16_t latency
   Preferred Transport Latency

uint32_t pd_min
   Minimum Presentation Delay.
   Unlike the other fields, this is not a preference but a minimum requirement.

uint32_t pd_max
   Maximum Presentation Delay.
   Unlike the other fields, this is not a preference but a maximum requirement.

uint32_t pref_pd_min
   Preferred minimum Presentation Delay.

uint32_t pref_pd_max
   Preferred maximum Presentation Delay

struct bt_audio_lc3_preset
   #include <audio.h> Struct to hold a BAP defined LC3 preset

Public Members

struct bt_codec codec
   The LC3 Codec

struct bt_codec_qos qos
   The BAP spec defined QoS values

struct bt_audio_stream
   #include <audio.h> Audio stream structure.
   Audio Streams represents a stream configuration of a Remote Endpoint and a Local Capability.

Note: Audio streams are unidirectional although its QoS can be configured to be bidirectional if stream are linked, in which case the QoS must be symmetric in both directions.

Public Members

struct bt_conn *conn
   Connection reference
struct bt_audio_ep *ep  
   Endpoint reference

cnst struct bt_codec *codec  
   Codec Configuration

struct bt_codec_qos *qos  
   QoS Configuration

struct bt_audio_stream_ops *ops  
   Audio stream operations

void *user_data  
   Stream user data

struct bt_audio_unicast_client_cb
   #include <audio.h> Unicast Client callback structure

**Public Members**

void (*location)(struct bt_conn *conn, enum bt_audio_dir dir, enum bt_audio_location loc)  
   Remote Unicast Server Audio Locations.
   This callback is called whenever the audio locations is read from the server or otherwise notified to the client.
   **Param conn**  
   Connection to the remote unicast server.
   **Param dir**  
   Direction of the location.
   **Param loc**  
   The location bitfield value.
   **Return**  
   0 in case of success or negative value in case of error.

void (*available_contexts)(struct bt_conn *conn, enum bt_audio_context snk_ctx, enum bt_audio_context src_ctx)  
   Remote Unicast Server Available Contexts.
   This callback is called whenever the available contexts are read from the server or otherwise notified to the client.
   **Param conn**  
   Connection to the remote unicast server.
   **Param snk_ctx**  
   The sink context bitfield value.
   **Param src_ctx**  
   The source context bitfield value.
   **Return**  
   0 in case of success or negative value in case of error.

struct bt_audio_unicast_server_cb
   #include <audio.h> Unicast Server callback structure
Public Members

int (*config)(struct bt_conn *conn, const struct bt_audio_ep *ep, enum bt_audio_dir dir, const struct bt_codec *codec, struct bt_audio_stream **stream, struct bt_codec_qos_pref *const pref)

Endpoint config request callback.
Config callback is called whenever an endpoint is requested to be configured

Param conn [in] Connection object.
Param ep [in] Local Audio Endpoint being configured.
Param dir [in] Direction of the endpoint.
Param codec [in] Codec configuration.
Param stream [out] Pointer to stream that will be configured for the endpoint.
Param pref [out] Pointer to a QoS preference object that shall be populated with values. Invalid values will reject the codec configuration request.
Return 0 in case of success or negative value in case of error.

int (*reconfig)(struct bt_audio_stream *stream, enum bt_audio_dir dir, const struct bt_codec *codec, struct bt_codec_qos_pref *const pref)

Stream reconfig request callback.
Reconfig callback is called whenever an Audio Stream needs to be reconfigured with different codec configuration.

Param stream [in] Stream object being reconfigured.
Param dir [in] Direction of the endpoint.
Param codec [in] Codec configuration.
Param pref [out] Pointer to a QoS preference object that shall be populated with values. Invalid values will reject the codec configuration request.
Return 0 in case of success or negative value in case of error.

int (*qos)(struct bt_audio_stream *stream, const struct bt_codec_qos *qos)

Stream QoS request callback.
QoS callback is called whenever an Audio Stream Quality of Service needs to be configured.

Param stream Stream object being reconfigured.
Param qos Quality of Service configuration.
Return 0 in case of success or negative value in case of error.

int (*enable)(struct bt_audio_stream *stream, const struct bt_codec_data *meta, size_t meta_count)

Stream Enable request callback.
Enable callback is called whenever an Audio Stream is requested to be enabled to stream.

- **Param stream**: Stream object being enabled.
- **Param meta**: Metadata entries
- **Param meta_count**: Number of metadata entries
- **Return**: 0 in case of success or negative value in case of error.

```c
int (*start)(struct bt_audio_stream *stream)
```

Start request callback.

Start callback is called whenever an Audio Stream is requested to start streaming.

- **Param stream**: Stream object.
- **Return**: 0 in case of success or negative value in case of error.

```c
int (*metadata)(struct bt_audio_stream *stream, const struct bt_codec_data *meta, size_t meta_count)
```

Metadata update request callback.

Metadata callback is called whenever an Audio Stream is requested to update its metadata.

- **Param stream**: Stream object.
- **Param meta**: Metadata entries
- **Param meta_count**: Number of metadata entries
- **Return**: 0 in case of success or negative value in case of error.

```c
int (*disable)(struct bt_audio_stream *stream)
```

Disable request callback.

Disable callback is called whenever an Audio Stream is requested to disable the stream.

- **Param stream**: Stream object being disabled.
- **Return**: 0 in case of success or negative value in case of error.

```c
int (*stop)(struct bt_audio_stream *stream)
```

Stop callback.

Stop callback is called whenever an Audio Stream is requested to stop streaming.

- **Param stream**: Stream object.
- **Return**: 0 in case of success or negative value in case of error.

```c
int (*release)(struct bt_audio_stream *stream)
```

Release callback.

Release callback is called whenever a new Audio Stream needs to be released and thus deallocated.
Param stream
  Stream object.

Return
  0 in case of success or negative value in case of error.

struct bt_audio_broadcast_sink_cb
#include <audio.h> Broadcast Audio Sink callback structure

Public Members

bool (*scan_recv)(const struct bt_le_scan_recv_info *info, struct net_buf_simple *ad, uint32_t broadcast_id)
  Scan receive callback. Scan receive callback is called whenever a broadcast source has been found.
  Param info
    Advertiser packet information.
  Param ad
    Buffer containing advertiser data.
  Param broadcast_id
    24-bit broadcast ID
  Return
    true to sync to the broadcaster, else false. Syncing to the broadcaster will stop the current scan.

void (*pa_synced)(struct bt_audio_broadcast_sink *sink, struct bt_le_per_adv_sync *sync, uint32_t broadcast_id)
  Periodic advertising sync callback. Called when synchronized to a periodic advertising. When synchronized a bt_audio_broadcast_sink structure is allocated for future use.
  Param sink
    Pointer to the allocated sink structure.
  Param sync
    Pointer to the periodic advertising sync.
  Param broadcast_id
    24-bit broadcast ID previously reported by scan_recv.

void (*base_recv)(struct bt_audio_broadcast_sink *sink, const struct bt_audio_base *base)
  Broadcast Audio Source Endpoint (BASE) received. Callback for when we receive a BASE from a broadcaster after syncing to the broadcaster's periodic advertising.
  Param sink
    Pointer to the sink structure.
  Param base
    Broadcast Audio Source Endpoint (BASE).

void (*syncable)(struct bt_audio_broadcast_sink *sink, bool encrypted)
  Broadcast sink is syncable. Called whenever a broadcast sink is not synchronized to audio, but the audio is synchronizable. This is inferred when a BIGInfo report is received.
  Once this callback has been called, it is possible to call bt_audio_broadcast_sink_sync() to synchronize to the audio stream(s).
**Param sink**
Pointer to the sink structure.

**Param encrypted**
Whether or not the broadcast is encrypted

```c
void (*scan_term)(int err)
Scan terminated callback.
```

Scan terminated callback is called whenever a scan started by `bt_audio_broadcast_sink_scan_start()` is terminated before `bt_audio_broadcast_sink_scan_stop()`.

Typical reasons for this are that the periodic advertising has synchronized (success criteria) or the scan timed out. It may also be called if the periodic advertising failed to synchronize.

**Param err**
0 in case of success or negative value in case of error.

```c
void (*pa_sync_lost)(struct bt_audio_broadcast_sink *sink)
Periodic advertising synchronization lost callback.
```

The periodic advertising synchronization lost callback is called if the periodic advertising sync is lost. If this happens, the sink object is deleted. To synchronize to the broadcaster again, `bt_audio_broadcast_sink_scan_start()` must be called.

**Param sink**
Pointer to the sink structure.

```c
#include <audio.h> Stream operation.
```

**Public Members**

```c
void (*started)(struct bt_audio_stream *stream)
Stream started callback.
```

Started callback is called whenever an Audio Stream has been started and will be usable for streaming.

**Param stream**
Stream object that has been started.

```c
void (*stopped)(struct bt_audio_stream *stream)
Stream stopped callback.
```

Stopped callback is called whenever an Audio Stream has been stopped.

**Param stream**
Stream object that has been stopped.

```
struct bt_audio_stream_ops
```

```
typedef void (*bt_audio_discover_func_t)(struct bt_conn *conn, struct bt_codec *codec, struct bt_audio_ep *ep, struct bt_audio_discover_params *params)
```

**Typedefs**

```c
typedef void (*bt_audio_discover_func_t)(struct bt_conn *conn, struct bt_codec *codec, struct bt_audio_ep *ep, struct bt_audio_discover_params *params)
```
Discover Audio capabilities and endpoints callback function.
If discovery procedure has complete both cap and ep are set to NULL.

**Functions**

```c
int bt_audio_discover(struct bt_conn *conn, struct bt_audio_discover_params *params)
```

Discover remote capabilities and endpoints.

This procedure is used by a client to discover remote capabilities and endpoints and notifies
via params callback.

**Note:** This procedure is asynchronous therefore the parameters need to remain valid while
it is active.

**Parameters**

- conn – Connection object
- params – Discover parameters

```c
int bt_audio_stream_config(struct bt_conn *conn, struct bt_audio_stream *stream, struct bt_audio_ep *ep, struct bt_codec *codec)
```

Configure Audio Stream.

This procedure is used by a client to configure a new stream using the remote endpoint, local
capability and codec configuration.

**Parameters**

- conn – Connection object
- stream – Stream object being configured
- ep – Remote Audio Endpoint being configured
- codec – Codec configuration

**Returns**

Allocated Audio Stream object or NULL in case of error.

```c
int bt_audio_stream_reconfig(struct bt_audio_stream *stream, const struct bt_codec *codec)
```

Reconfigure Audio Stream.

This procedure is used by a unicast client or unicast server to reconfigure a stream to use a
different local codec configuration.

This can only be done for unicast streams.

**Parameters**

- stream – Stream object being reconfigured
- codec – Codec configuration

**Returns**

0 in case of success or negative value in case of error.

```c
int bt_audio_stream_qos(struct bt_conn *conn, struct bt_audio_unicast_group *group)
```

Configure Audio Stream QoS.

This procedure is used by a client to configure the Quality of Service of streams in a unicast
group. All streams in the group for the specified conn will have the Quality of Service
configured. This shall only be used to configure unicast streams.
Parameters

- **conn** – Connection object
- **group** – Unicast group object

Returns

0 in case of success or negative value in case of error.

```c
int bt_audio_stream_enable(struct bt_audio_stream *stream, struct bt_codec_data *meta, size_t meta_count)
```

Enable Audio Stream.

This procedure is used by a client to enable a stream.

This shall only be called for unicast streams, as broadcast streams will always be enabled once created.

Parameters

- **stream** – Stream object
- **meta_count** – Number of metadata entries
- **meta** – Metadata entries

Returns

0 in case of success or negative value in case of error.

```c
int bt_audio_stream_metadata(struct bt_audio_stream *stream, struct bt_codec_data *meta, size_t meta_count)
```

Change Audio Stream Metadata.

This procedure is used by a unicast client or unicast server to change the metadata of a stream.

Parameters

- **stream** – Stream object
- **meta_count** – Number of metadata entries
- **meta** – Metadata entries

Returns

0 in case of success or negative value in case of error.

```c
int bt_audio_stream_disable(struct bt_audio_stream *stream)
```

Disable Audio Stream.

This procedure is used by a unicast client or unicast server to disable a stream.

This shall only be called for unicast streams, as broadcast streams will always be enabled once created.

Parameters

- **stream** – Stream object

Returns

0 in case of success or negative value in case of error.

```c
int bt_audio_stream_start(struct bt_audio_stream *stream)
```

Start Audio Stream.

This procedure is used by a unicast client or unicast server to make a stream start streaming.

This shall only be called for unicast streams. Broadcast sinks will always be started once synchronized, and broadcast source streams shall be started with `bt_audio_broadcast_source_start()`.

Parameters
• stream – Stream object

Returns
0 in case of success or negative value in case of error.

int bt_audio_stream_stop(struct bt_audio_stream *stream)
Stop Audio Stream.
This procedure is used by a client to make a stream stop streaming.
This shall only be called for unicast streams. Broadcast sinks cannot be stopped. Broadcast
sources shall be stopped with bt_audio_broadcast_source_stop().

Parameters
• stream – Stream object

Returns
0 in case of success or negative value in case of error.

int bt_audio_stream_release(struct bt_audio_stream *stream)
Release Audio Stream.
This procedure is used by a unicast client or unicast server to release a unicast stream.
Broadcast sink streams cannot be released, but can be deleted by
bt_audio_broadcast_sink_delete(). Broadcast source streams cannot be released, but can
be deleted by bt_audio_broadcast_source_delete().

Parameters
• stream – Stream object

Returns
0 in case of success or negative value in case of error.

int bt_audio_stream_send(struct bt_audio_stream *stream, struct net_buf *buf, uint16_t
seq_num, uint32_t ts)
Send data to Audio stream.
Send data from buffer to the stream.

Note: Data will not be sent to linked streams since linking is only consider for procedures
affecting the state machine.

Parameters
• stream – Stream object.
• buf – Buffer containing data to be sent.
• seq_num – Packet Sequence number. This value shall be incremented for each
call to this function and at least once per SDU interval for a specific channel.
• ts – Timestamp of the SDU in microseconds (us). This value can be used
to transmit multiple SDUs in the same SDU interval in a CIG or BIG. Can be
omitted by using BT_ISO_TIMESTAMP_NONE which will simply enqueue the
ISO SDU in a FIFO manner.

Returns
Bytes sent in case of success or negative value in case of error.

int bt_audio_unicast_group_create(struct bt_audio_unicast_group_param params[], size_t
num_param, struct bt_audio_unicast_group **unicast_group)
Create audio unicast group.

Create a new audio unicast group with one or more audio streams as a unicast client. Streams in a unicast group shall share the same interval, framing and latency (see `bt_codec_qos`).

**Parameters**

- `params` – `[in]` Array of stream parameters being used for the group.
- `num_param` – `[in]` Number of parameters in `params`.
- `unicast_group` – `[out]` Pointer to the unicast group created

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_audio_unicast_group_add_streams(
    struct bt_audio_unicast_group *unicast_group,
    struct bt_audio_unicast_group_param params[],
    size_t num_param)
```

Add streams to a unicast group as a unicast client.

This function can be used to add additional streams to a `bt_audio_unicast_group`.

This can be called at any time before any of the streams in the group has been started (see `bt_audio_stream_ops.started()`). This can also be called after the streams have been stopped (see `bt_audio_stream_ops.stopped()`).

Once a stream has been added to a unicast group, it cannot be removed. To remove a stream from a group, the group must be deleted with `bt_audio_unicast_group_delete()`, but this will require all streams in the group to be released first.

**Parameters**

- `unicast_group` – Pointer to the unicast group
- `params` – Array of stream parameters with streams being added to the group.
- `num_param` – Number of parameters in `params`.

**Returns**

0 in case of success or negative value in case of error.

```c
int bt_audio_unicast_group_delete(struct bt_audio_unicast_group *unicast_group)
```

Delete audio unicast group.

Delete a audio unicast group as a client. All streams in the group shall be in the idle or configured state.

**Parameters**

- `unicast_group` – Pointer to the unicast group to delete

**Returns**

Zero on success or (negative) error code otherwise.

```c
struct bt_audio_discover_params
    #include <audio.h>
```

**Public Members**

```c
enum bt_audio_dir dir
    Capabilities type
```
bt_audio_discover_func_t func
    Callback function

uint8_t num_caps
    Number of capabilities found

uint8_t num_eps
    Number of endpoints found

uint8_t err
    Error code.

struct bt_audio_unicast_group_param
    Parameter struct for the unicast group functions.
    Parameter struct for the bt_audio_unicast_group_create() and bt_audio_unicast_group_add_streams() functions.

Public Members

struct bt_audio_stream *stream
    Pointer to a stream object.

struct bt_codec_qos *qos
    The QoS settings for the bt_audio_unicast_group_param::stream.

enum bt_audio_dir dir
    The direction of the bt_audio_unicast_group_param::stream.
    If two streams are being used for the same ACL connection but in different directions, they may use the same CIS.

bt_audio_server

Functions

int bt_audio_unicast_server_register_cb(const struct bt_audio_unicast_server_cb *cb)
    Register unicast server callbacks.
    Only one callback structure can be registered, and attempting to registering more than one will result in an error.

    Parameters
    • cb – Unicast server callback structure.

    Returns
    0 in case of success or negative value in case of error.

int bt_audio_unicast_server_unregister_cb(const struct bt_audio_unicast_server_cb *cb)
    Unregister unicast server callbacks.
    May only unregister a callback structure that has previously been registered by bt_audio_unicast_server_register_cb().
Parameters

- cb – Unicast server callback structure.

Returns

0 in case of success or negative value in case of error.

group bt_audio_broadcast

Audio Broadcast APIs.

Functions

int bt_audio_broadcast_source_create(struct bt_audio_broadcast_source_create_param *param, struct bt_audio_broadcast_source **source)

Create audio broadcast source.

Create a new audio broadcast source with one or more audio streams.
The broadcast source will be visible for scanners once this has been called, and the device will advertise audio announcements.

No audio data can be sent until bt_audio_broadcast_source_start() has been called and no audio information (BIGInfo) will be visible to scanners (see bt_le_per_adv_sync_cb).

Parameters

- param – [in] Pointer to parameters used to create the broadcast source.
- source – [out] Pointer to the broadcast source created

Returns

Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_source_reconfig(struct bt_audio_broadcast_source *source, struct bt_codec *codec, struct bt_codec_qos *qos)

Reconfigure audio broadcast source.

Reconfigure an audio broadcast source with a new codec and codec quality of service parameters.

Parameters

- source – Pointer to the broadcast source
- codec – Codec configuration.
- qos – Quality of Service configuration

Returns

Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_source_start(struct bt_audio_broadcast_source *source, struct bt_le_ext_adv *adv)

Start audio broadcast source.

Start an audio broadcast source with one or more audio streams. The broadcast source will start advertising BIGInfo, and audio data can be streamed.

Parameters

- source – Pointer to the broadcast source
- adv – Pointer to an extended advertising set with periodic advertising configured.

Returns

Zero on success or (negative) error code otherwise.
int bt_audio_broadcast_source_stop(struct bt_audio_broadcast_source *source)
Stop audio broadcast source.

Stop an audio broadcast source. The broadcast source will stop advertising BIGInfo, and audio data can no longer be streamed.

Parameters
  • source – Pointer to the broadcast source

Returns
  Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_source_delete(struct bt_audio_broadcast_source *source)
Delete audio broadcast source.

Delete an audio broadcast source. The broadcast source will stop advertising entirely, and the source can no longer be used.

Parameters
  • source – Pointer to the broadcast source

Returns
  Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_source_get_id(const struct bt_audio_broadcast_source *source, uint32_t *const broadcast_id)
Get the broadcast ID of a broadcast source.

This will return the 3-octet broadcast ID that should be advertised in the extended advertising data with `BT_UUID_BROADCAST_AUDIO_VAL` as `BT_DATA_SVC_DATA16`.

See table 3.14 in the Basic Audio Profile v1.0.1 for the structure.

Parameters
  • source – [in] Pointer to the broadcast source.
  • broadcast_id – [out] Pointer to the 3-octet broadcast ID.

Returns
  int 0 if on success, errno on error.

int bt_audio_broadcast_source_get_base(struct bt_audio_broadcast_source *source, struct net_buf_simple *base_buf)
Get the Broadcast Audio Stream Endpoint of a broadcast source.

This will encode the BASE of a broadcast source into a buffer, that can be used for advertisement. The encoded BASE will thus be encoded as little-endian. The BASE shall be put into the periodic advertising data (see `bt_le_per_adv_set_data()`).

See table 3.15 in the Basic Audio Profile v1.0.1 for the structure.

Parameters
  • source – Pointer to the broadcast source.
  • base_buf – Pointer to a buffer where the BASE will be inserted.

Returns
  int 0 if on success, errno on error.

void bt_audio_broadcast_sink_register_cb(struct bt_audio_broadcast_sink_cb *cb)
Register Broadcast sink callbacks.

Parameters
  • cb – Broadcast sink callback structure.
int bt_audio_broadcast_sink_scan_start(const struct bt_le_scan_param *param)

Start scan for broadcast sources.

Starts a scan for broadcast sources. Scan results will be received by the scan_recv callback. Only reports from devices advertising broadcast audio support will be sent. Note that a broadcast source may advertise broadcast audio capabilities, but may not be streaming.

Parameters
• param – Scan parameters.

Returns
Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_sink_scan_stop(void)

Stop scan for broadcast sources.

Stops ongoing scanning for broadcast sources.

Returns
Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_sink_sync(struct bt_audio_broadcast_sink *sink, uint32_t indexes_bitfield, struct bt_audio_stream *streams[], const uint8_t broadcast_code[16])

Sync to a broadcaster's audio.

Parameters
• sink – Pointer to the sink object from the base_recv callback.
• indexes_bitfield – Bitfield of the BIS index to sync to. To sync to e.g. BIS index 1 and 2, this should have the value of BIT(1) | BIT(2).
• streams – Stream object pointers to be used for the receiver. If multiple BIS indexes shall be synchronized, multiple streams shall be provided.
• broadcast_code – The 16-octet broadcast code. Shall be supplied if the broadcast is encrypted (see the syncable callback).

Returns
0 in case of success or negative value in case of error.

int bt_audio_broadcast_sink_stop(struct bt_audio_broadcast_sink *sink)

Stop audio broadcast sink.

Stop an audio broadcast sink. The broadcast sink will stop receiving BIGInfo, and audio data can no longer be streamed.

Parameters
• sink – Pointer to the broadcast sink

Returns
Zero on success or (negative) error code otherwise.

int bt_audio_broadcast_sink_delete(struct bt_audio_broadcast_sink *sink)

Release a broadcast sink.

Once a broadcast sink has been allocated after the pa_synced callback, it can be deleted using this function. If the sink has synchronized to any broadcast audio streams, these must first be stopped using bt_audio_stream_stop.

Parameters
• sink – Pointer to the sink object to delete.

Returns
0 in case of success or negative value in case of error.
struct bt_audio_broadcast_source_stream_param
#include <audio.h>

Public Members

struct bt_audio_stream *stream
Audio stream

size_t data_count
The number of elements in the data array.
The BIS specific data may be omitted and this set to 0.

struct bt_codec_data *data
BIS Codec Specific Configuration

struct bt_audio_broadcast_source_subgroup_param
#include <audio.h>

Public Members

size_t params_count
The number of parameters in stream_params

struct bt_audio_broadcast_source_stream_param *params
Array of stream parameters

struct bt_codec *codec
Subgroup Codec configuration.

struct bt_audio_broadcast_source_create_param
#include <audio.h>

Public Members

size_t params_count
The number of parameters in subgroup_params

struct bt_audio_broadcast_source_subgroup_param *params
Array of stream parameters

struct bt_codec_qos *qos
Quality of Service configuration.

group bt_audio_codec_cfg
Audio codec Config APIs.
Functions to parse codec config data when formatted as LTV wrapped into bt_codec.
 Enums

enum bt_audio_codec_parse_err
   Codec parser error codes for Codec config parsing APIs.
   Values:

   enumerator BT_AUDIO_CODEC_PARSE_ERR_SUCCESS = 0
      The requested type is not present in the data set.

   enumerator BT_AUDIO_CODEC_PARSE_ERR_TYPE_NOT_FOUND = -1
      The requested type is not present in the data set.

   enumerator BT_AUDIO_CODEC_PARSE_ERR_INVALID_VALUE_FOUND = -2
      The value found is invalid.

   enumerator BT_AUDIO_CODEC_PARSE_ERR_INVALID_PARAM = -3
      The parameters specified to the function call are not valid.

 Functions

 int bt_codec_cfg_get_freq(const struct bt_codec *codec)
 Extract the frequency from a codec configuration.

   Parameters
      • codec – The codec configuration to extract data from.

   Returns
      The frequency in Hz if found else a negative value of type
      bt_audio_codec_parse_err.

 int bt_codec_cfg_get_frame_duration_us(const struct bt_codec *codec)
 Extract frame duration from BT codec config.

   Parameters
      • codec – The codec configuration to extract data from.

   Returns
      Frame duration in microseconds if value is found else a negative value of type
      bt_audio_codec_parse_err.

 int bt_codec_cfg_get_chan_allocation_val(const struct bt_codec *codec, uint32_t *chan_allocation)
 Extract channel allocation from BT codec config.

 The value returned is a bit field representing one or more audio locations
 as specified by bt_audio_location Shall match one or more of the bits set in
 BT_PAC_SNK_LOC/BT_PAC_SRC_LOC.

 Up to the configured BT_CODEC_LC3_CHAN_COUNT number of channels can be present.

   Parameters
      • codec – The codec configuration to extract data from.
      • chan_allocation – Pointer to the variable to store the extracted value in.
Returns

BT_AUDIO_CODEC_PARSE_SUCCESS if value is found and stored in the pointer provided else a negative value of type bt_audio_codec_parse_err.

int bt_codec_cfg_get_octets_per_frame(const struct bt_codec *codec)

Extract frame size in octets from BT codec config.

The overall SDU size will be octets_per_frame * blocks_per_sdu.

The Bluetooth specificationa are not clear about this value - it does not state that the codec shall use this SDU size only. A codec like LC3 supports variable bit-rate (per SDU) hence it might be allowed for an encoder to reduce the frame size below this value. Hence it is recommended to use the received SDU size and divide by blocks_per_sdu rather than relying on this octets_per_sdu value to be fixed.

Parameters

• codec – The codec configuration to extract data from.

Returns

Frame length in octets if value is found else a negative value of type bt_audio_codec_parse_err.

int bt_codec_cfg_get_frame_blocks_per_sdu(const struct bt_codec *codec, bool fallback_to_default)

Extract number of audio frame blocks in each SDU from BT codec config.

The overall SDU size will be octets_per_frame * frame_blocks_per_sdu * number-of-channels.

If this value is not present a default value of 1 shall be used.

A frame block is one or more frames that represents data for the same period of time but for different channels. If the stream have two audio channels and this value is two there will be four frames in the SDU.

Parameters

• codec – The codec configuration to extract data from.

• fallback_to_default – If true this function will return the default value of 1 if the type is not found. In this case the function will only fail if a NULL pointer is provided.

Returns

The count of codec frames in each SDU if value is found else a negative value of type bt_audio_codec_parse_err - unless when fallback_to_default is true then the value 1 is returned if frames per sdu is not found.

bool bt_codec_get_val(const struct bt_codec *codec, uint8_t type, const struct bt_codec_data **data)

Lookup a specific value based on type.

Depending on context bt_codec will be either codec capabilities, codec configuration or meta data.

Typically types used are: bt_codec_capability_type bt_codec_config_type bt_audio_metadata_type

Parameters

• codec – The codec data to search in.

• type – The type id to look for

• data – Pointer to the data-pointer to update when item is found

Returns

True if the type is found, false otherwise.
Connection Management

The Zephyr Bluetooth stack uses an abstraction called `bt_conn` to represent connections to other devices. The internals of this struct are not exposed to the application, but a limited amount of information (such as the remote address) can be acquired using the `bt_conn_get_info()` API. Connection objects are reference counted, and the application is expected to use the `bt_conn_ref()` API whenever storing a connection pointer for a longer period of time, since this ensures that the object remains valid (even if the connection would get disconnected). Similarly the `bt_conn_unref()` API is to be used when releasing a reference to a connection.

An application may track connections by registering a `bt_conn_cb` struct using the `bt_conn_cb_register()` or `BT_CONN_CB_DEFINE` APIs. This struct lets the application define callbacks for connection & disconnection events, as well as other events related to a connection such as a change in the security level or the connection parameters. When acting as a central the application will also get hold of the connection object through the return value of the `bt_conn_create_le()` API.

API Reference

group bt_conn

Connection management.

Defines

`BT_LE_CONN_PARAM_INIT(int_min, int_max, lat, to)`

Initialize connection parameters.

Parameters

- `int_min` – Minimum Connection Interval (N * 1.25 ms)
- `int_max` – Maximum Connection Interval (N * 1.25 ms)
- `lat` – Connection Latency
- `to` – Supervision Timeout (N * 10 ms)

`BT_LE_CONN_PARAM(int_min, int_max, lat, to)`

Helper to declare connection parameters inline

Parameters

- `int_min` – Minimum Connection Interval (N * 1.25 ms)
- `int_max` – Maximum Connection Interval (N * 1.25 ms)
- `lat` – Connection Latency
- `to` – Supervision Timeout (N * 10 ms)

`BT_LE_CONN_PARAM_DEFAULT`  
Default LE connection parameters: Connection Interval: 30-50 ms Latency: 0 Timeout: 4 s

`BT_CONN_LE_PHY_PARAM_INIT(_pref_tx_phy, _pref_rx_phy)`

Initialize PHY parameters

Parameters

- `_pref_tx_phy` – Bitmask of preferred transmit PHYs.
- `_pref_rx_phy` – Bitmask of preferred receive PHYs.
BT_CONN_LE_PHY_PARAM(_pref_tx_phy, _pref_rx_phy)
Helper to declare PHY parameters inline

Parameters
• _pref_tx_phy – Bitmask of preferred transmit PHYs.
• _pref_rx_phy – Bitmask of preferred receive PHYs.

BT_CONN_LE_PHY_PARAM_1M
Only LE 1M PHY

BT_CONN_LE_PHY_PARAM_2M
Only LE 2M PHY

BT_CONN_LE_PHY_PARAM_CODED
Only LE Coded PHY.

BT_CONN_LE_PHY_PARAM_ALL
All LE PHYs.

BT_CONN_LE_DATA_LEN_PARAM_INIT(_tx_max_len, _tx_max_time)
Initialize transmit data length parameters

Parameters
• _tx_max_len – Maximum Link Layer transmission payload size in bytes.
• _tx_max_time – Maximum Link Layer transmission payload time in us.

BT_CONN_LE_DATA_LEN_PARAM(_tx_max_len, _tx_max_time)
Helper to declare transmit data length parameters inline

Parameters
• _tx_max_len – Maximum Link Layer transmission payload size in bytes.
• _tx_max_time – Maximum Link Layer transmission payload time in us.

BT_LE_DATA_LEN_PARAM_DEFAULT
Default LE data length parameters.

BT_LE_DATA_LEN_PARAM_MAX
Maximum LE data length parameters.

BT_CONN_INTERVAL_TO_MS(interval)

BT_CONN_ROLE_MASTER
Connection role (central or peripheral)

BT_CONN_ROLE_SLAVE

BT_CONN_LE_CREATE_PARAM_INIT(_options, _interval, _window)
Initialize create connection parameters.

Parameters
• _options – Create connection options.
• _interval – Create connection scan interval (N * 0.625 ms).
• _window – Create connection scan window (N * 0.625 ms).

BT_CONN_LE_CREATE_PARAM(_options, _interval, _window)
Helper to declare create connection parameters inline

Parameters
• _options – Create connection options.
• _interval – Create connection scan interval (N * 0.625 ms).
• _window – Create connection scan window (N * 0.625 ms).

BT_CONN_LE_CREATE_CONN
Default LE create connection parameters. Scan continuously by setting scan interval equal to scan window.

BT_CONN_LE_CREATE_CONN_AUTO
Default LE create connection using filter accept list parameters. Scan window: 30 ms. Scan interval: 60 ms.

BT_CONN_CB_DEFINE(_name)
Register a callback structure for connection events.

Parameters
• _name – Name of callback structure.

BT_PASSKEY_INVALID
Special passkey value that can be used to disable a previously set fixed passkey.

BT_BR_CONN_PARAM_INIT(role_switch)
Initialize BR/EDR connection parameters.

Parameters
• role_switch – True if role switch is allowed

BT_BR_CONN_PARAM(role_switch)
Helper to declare BR/EDR connection parameters inline

Parameters
• role_switch – True if role switch is allowed

BT_BR_CONN_PARAM_DEFAULT
Default BR/EDR connection parameters: Role switch allowed

Enums

enum [anonymous]
Connection PHY options

Values:

enumerator BT_CONN_LE_PHY_OPT_NONE = 0
Convenience value when no options are specified.
enumerator BT_CONN_LE_PHY_OPT_CODED_S2 = \textit{BIT}(0)

LE Coded using S=2 coding preferred when transmitting.

denumerator BT_CONN_LE_PHY_OPT_CODED_S8 = \textit{BIT}(1)

LE Coded using S=8 coding preferred when transmitting.

\texttt{enum [anonymous]}

\texttt{Connection Type}

\texttt{Values:}

\texttt{enumerator BT_CONN_TYPE_LE = \textit{BIT}(0)}

LE Connection Type

\texttt{enumerator BT_CONN_TYPE_BR = \textit{BIT}(1)}

BR/EDR Connection Type

\texttt{enumerator BT_CONN_TYPE_SCO = \textit{BIT}(2)}

SCO Connection Type

\texttt{enumerator BT_CONN_TYPE_ISO = \textit{BIT}(3)}

ISO Connection Type

\texttt{enumerator BT_CONN_TYPE_ALL = BT_CONN_TYPE_LE | BT_CONN_TYPE_BR | BT_CONN_TYPE_SCO | BT_CONN_TYPE_ISO}

All Connection Type

\texttt{enum [anonymous]}

\texttt{Values:}

\texttt{enumerator BT_CONN_ROLE_CENTRAL = 0}

\texttt{enumerator BT_CONN_ROLE_PERIPHERAL = 1}

\texttt{enum bt_conn_state}

\texttt{Values:}

\texttt{enumerator BT_CONN_STATE_DISCONNECTED}

Channel disconnected

\texttt{enumerator BT_CONN_STATE_CONNECTING}

Channel in connecting state

\texttt{enumerator BT_CONN_STATE_CONNECTED}

Channel connected and ready for upper layer traffic on it

\texttt{enumerator BT_CONN_STATE_DISCONNECTING}

Channel in disconnecting state
enum bt_security_t
    Security level.
    Values:
    
    enumerator BT_SECURITY_L0
        Level 0: Only for BR/EDR special cases, like SDP
    
    enumerator BT_SECURITY_L1
        Level 1: No encryption and no authentication.
    
    enumerator BT_SECURITY_L2
        Level 2: Encryption and no authentication (no MITM).
    
    enumerator BT_SECURITY_L3
        Level 3: Encryption and authentication (MITM).
    
    enumerator BT_SECURITY_L4
        Level 4: Authenticated Secure Connections and 128-bit key.
    
    enumerator BT_SECURITY_FORCE_PAIR = BIT(7)
        Bit to force new pairing procedure, bit-wise OR with requested security level.

enum bt_security_flag
    Security Info Flags.
    Values:
    
    enumerator BT_SECURITY_FLAG_SC = BIT(0)
        Paired with Secure Connections.
    
    enumerator BT_SECURITY_FLAG_OOB = BIT(1)
        Paired with Out of Band method.

enum bt_conn_le_tx_power_phy
    Values:
    
    enumerator BT_CONN_LE_TX_POWER_PHY_NONE
        Convenience macro for when no PHY is set.
    
    enumerator BT_CONN_LE_TX_POWER_PHY_1M
        LE 1M PHY
    
    enumerator BT_CONN_LE_TX_POWER_PHY_2M
        LE 2M PHY
    
    enumerator BT_CONN_LE_TX_POWER_PHY_CODED_S8
        LE Coded PHY using S=8 coding.
enumerator BT_CONN_LE_TX_POWER_PHY_CODED_S2
   LE Coded PHY using S=2 coding.

enum [anonymous]
   Values:

   enumerator BT_CONN_LE_OPT_NONE = 0
      Convenience value when no options are specified.

   enumerator BT_CONN_LE_OPT_CODED = BIT(0)
      Enable LE Coded PHY.

      Enable scanning on the LE Coded PHY.

   enumerator BT_CONN_LE_OPT_NO_1M = BIT(1)
      Disable LE 1M PHY.

      Disable scanning on the LE 1M PHY.

      @note Requires @ref BT_CONN_LE_OPT_CODED.

enum bt_security_err
   Values:

   enumerator BT_SECURITY_ERR_SUCCESS
      Security procedure successful.

   enumerator BT_SECURITY_ERR_AUTH_FAIL
      Authentication failed.

   enumerator BT_SECURITY_ERR_PIN_OR_KEY_MISSING
      PIN or encryption key is missing.

   enumerator BT_SECURITY_ERR_OOB_NOT_AVAILABLE
      OOB data is not available.

   enumerator BT_SECURITY_ERR_AUTH_REQUIREMENT
      The requested security level could not be reached.

   enumerator BT_SECURITY_ERR_PAIR_NOT_SUPPORTED
      Pairing is not supported

   enumerator BT_SECURITY_ERR_PAIR_NOT_ALLOWED
      Pairing is not allowed.

   enumerator BT_SECURITY_ERR_INVALID_PARAM
      Invalid parameters.
enumerator BT_SECURITY_ERR_KEY_REJECTED
   Distributed Key Rejected

enumerator BT_SECURITY_ERR_UNSPECIFIED
   Pairing failed but the exact reason could not be specified.

Functions

struct bt_conn *bt_conn_ref(struct bt_conn *conn)
   Increment a connection's reference count.
   Increment the reference count of a connection object.

   Note: Will return NULL if the reference count is zero.

Parameters
• conn – Connection object.

Returns
Connection object with incremented reference count, or NULL if the reference count is zero.

void bt_conn_unref(struct bt_conn *conn)
   Decrement a connection's reference count.
   Decrement the reference count of a connection object.

Parameters
• conn – Connection object.

void bt_conn_foreach(int type, void (*func)(struct bt_conn *conn, void *data), void *data)
   Iterate through all existing connections.

Parameters
• type – Connection Type
• func – Function to call for each connection.
• data – Data to pass to the callback function.

struct bt_conn *bt_conn_lookup_addr_le(uint8_t id, const bt_addr_le_t *peer)
   Look up an existing connection by address.
   Look up an existing connection based on the remote address.
   The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.

Parameters
• id – Local identity (in most cases BT_ID_DEFAULT).
• peer – Remote address.

Returns
Connection object or NULL if not found.
const bt_addr_le_t *bt_conn_get_dst(const struct bt_conn *conn)
Get destination (peer) address of a connection.

Parameters
• conn – Connection object.

Returns
Destination address.

uint8_t bt_conn_index(const struct bt_conn *conn)
Get array index of a connection.
This function is used to map bt_conn to index of an array of connections. The array has
CONFIG_BT_MAX_CONN elements.

Parameters
• conn – Connection object.

Returns
Index of the connection object. The range of the returned value is
0..CONFIG_BT_MAX_CONN-1

int bt_conn_get_info(const struct bt_conn *conn, struct bt_conn_info *info)
Get connection info.

Parameters
• conn – Connection object.
• info – Connection info object.

Returns
Zero on success or (negative) error code on failure.

int bt_conn_get_remote_info(struct bt_conn *conn, struct bt_conn_remote_info *remote_info)
Get connection info for the remote device.

Note: In order to retrieve the remote version (version, manufacturer and subversion)
CONFIG_BT_REMOTE_VERSION must be enabled

Note: The remote information is exchanged directly after the connection has been es-
blished. The application can be notified about when the remote information is available
through the remote_info_available callback.

Parameters
• conn – Connection object.
• remote_info – Connection remote info object.

Returns
Zero on success or (negative) error code on failure.

Returns
-EBUSY The remote information is not yet available.

int bt_conn_le_get_tx_power_level(struct bt_conn *conn, struct bt_conn_le tx_power
*tx_power_level)
Get connection transmit power level.

Parameters
• conn – Connection object.
• tx_power_level – Transmit power level descriptor.

**Returns**

Zero on success or (negative) error code on failure.

**Returns**
- ENOBUSFS HCI command buffer is not available.

```c
int bt_conn_le_param_update(struct bt_conn *conn, const struct bt_le_conn_param *param)
```

Update the connection parameters.

If the local device is in the peripheral role then updating the connection parameters will be delayed. This delay can be configured by through the `CONFIG_BT_CONN_PARAM_UPDATE_TIMEOUT` option.

**Parameters**

• conn – Connection object.
• param – Updated connection parameters.

**Returns**

Zero on success or (negative) error code on failure.

```c
int bt_conn_le_data_len_update(struct bt_conn *conn, const struct bt_conn_le_data_len_param *param)
```

Update the connection transmit data length parameters.

**Parameters**

• conn – Connection object.
• param – Updated data length parameters.

**Returns**

Zero on success or (negative) error code on failure.

```c
int bt_conn_le_phy_update(struct bt_conn *conn, const struct bt_conn_le_phy_param *param)
```

Update the connection PHY parameters.

Update the preferred transmit and receive PHYs of the connection. Use `BT_GAP_LE_PHY_NONE` to indicate no preference.

**Parameters**

• conn – Connection object.
• param – Updated connection parameters.

**Returns**

Zero on success or (negative) error code on failure.

```c
int bt_conn_disconnect(struct bt_conn *conn, uint8_t reason)
```

Disconnect from a remote device or cancel pending connection.

Disconnect an active connection with the specified reason code or cancel pending outgoing connection.

The disconnect reason for a normal disconnect should be: `BT_HCI_ERR_REMOTE_USER_TERM_CONN`.

The following disconnect reasons are accepted:

• `BT_HCI_ERR_AUTH_FAIL`
• `BT_HCI_ERR_REMOTE_USER_TERM_CONN`
• `BT_HCI_ERR_REMOTE_LOW_RESOURCES`
• BT_HCI_ERR_REMOTE_POWER_OFF
• BT_HCI_ERR_UNSUPP_REMOTE_FEATURE
• BT_HCI_ERR_PAIRING_NOT_SUPPORTED
• BT_HCI_ERR_UNACCEPT_CONN_PARAM

Parameters
• conn – Connection to disconnect.
• reason – Reason code for the disconnection.

Returns
Zero on success or (negative) error code on failure.

int bt_conn_le_create(const bt_addr_le_t *peer, const struct bt_conn_le_create_param *create_param, const struct bt_le_conn_param *conn_param, struct bt_conn **conn)

Initiate an LE connection to a remote device.

Allows initiate new LE link to remote peer using its address.

The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.

This uses the General Connection Establishment procedure.

The application must disable explicit scanning before initiating a new LE connection.

When CONFIG_BT_PRIVACY enabled and peer is an identity address from a local bond, this API will connect to an advertisement with either:

• the address being an RPA resolved from the IRK obtained during bonding.
• the passed identity address, if the local identity is not in Network Privacy Mode.

Parameters
• peer – [in] Remote address.
• create_param – [in] Create connection parameters.
• conn_param – [in] Initial connection parameters.
• conn – [out] Valid connection object on success.

Returns
Zero on success or (negative) error code on failure.

int bt_conn_le_create_auto(const struct bt_conn_le_create_param *create_param, const struct bt_le_conn_param *conn_param)

Automatically connect to remote devices in the filter accept list..

This uses the Auto Connection Establishment procedure. The procedure will continue until a single connection is established or the procedure is stopped through bt_conn_create_auto_stop.

To establish connections to all devices in the the filter accept list the procedure should be started again in the connected callback after a new connection has been established.

Parameters
• create_param – Create connection parameters
• conn_param – Initial connection parameters.

Returns
Zero on success or (negative) error code on failure.
Returns
-ENOMEM No free connection object available.

int bt_conn_create_auto_stop(void)
Stop automatic connect creation.

Returns
Zero on success or (negative) error code on failure.

int bt_le_set_auto_conn(const bt_addr_le_t *addr, const struct bt_le_conn_param *param)
Automatically connect to remote device if it’s in range.
This function enables/disables automatic connection initiation. Every time the device loses the connection with peer, this connection will be re-established if connectable advertisement from peer is received.

Note: Auto connect is disabled during explicit scanning.

Parameters
• addr – Remote Bluetooth address.
• param – If non-NULL, auto connect is enabled with the given parameters. If NULL, auto connect is disabled.

Returns
Zero on success or error code otherwise.

int bt_conn_set_security(struct bt_conn *conn, bt_security_t sec)
Set security level for a connection.
This function enable security (encryption) for a connection. If the device has bond information for the peer with sufficiently strong key encryption will be enabled. If the connection is already encrypted with sufficiently strong key this function does nothing.
If the device has no bond information for the peer and is not already paired then the pairing procedure will be initiated. If the device has bond information or is already paired and the keys are too weak then the pairing procedure will be initiated.
This function may return error if required level of security is not possible to achieve due to local or remote device limitation (e.g., input output capabilities), or if the maximum number of paired devices has been reached.
This function may return error if the pairing procedure has already been initiated by the local device or the peer device.

Note: When CONFIG_BT_SMP_SC_ONLY is enabled then the security level will always be level 4.

Note: When CONFIG_BT_SMP_OOB_LEGACY_PAIR_ONLY is enabled then the security level will always be level 3.

Parameters
• conn – Connection object.
• sec – Requested security level.

Returns
0 on success or negative error
bt_security_t bt_conn_get_security(const struct bt_conn *conn)
    Get security level for a connection.

    Returns
    Connection security level

uint8_t bt_conn_enc_key_size(const struct bt_conn *conn)
    Get encryption key size.
    This function gets encryption key size. If there is no security (encryption) enabled 0 will be returned.

    Parameters
    • conn – Existing connection object.

    Returns
    Encryption key size.

void bt_conn_cb_register(struct bt_conn_cb *cb)
    Register connection callbacks.
    Register callbacks to monitor the state of connections.

    Parameters
    • cb – Callback struct. Must point to memory that remains valid.

void bt_set_bondable(bool enable)
    Enable/disable bonding.
    Set/clear the Bonding flag in the Authentication Requirements of SMP Pairing Request/Response data. The initial value of this flag depends on BT_BONDABLE Kconfig setting. For the vast majority of applications calling this function shouldn’t be needed.

    Parameters
    • enable – Value allowing/disallowing to be bondable.

void bt_set_oob_data_flag(bool enable)
    Allow/disallow remote OOB data to be used for pairing.
    Set/clear the OOB data flag for SMP Pairing Request/Response data. The initial value of this flag depends on BT_OOB_DATA_PRESENT Kconfig setting.

    Parameters
    • enable – Value allowing/disallowing remote OOB data.

int bt_le_oob_set_legacy_tk(struct bt_conn *conn, const uint8_t *tk)
    Set OOB Temporary Key to be used for pairing.
    This function allows to set OOB data for the LE legacy pairing procedure. The function should only be called in response to the oob_data_request() callback provided that the legacy method is user pairing.

    Parameters
    • conn – Connection object
    • tk – Pointer to 16 byte long TK array

    Returns
    Zero on success or -EINVAL if NULL

int bt_le_oob_set_sc_data(struct bt_conn *conn, const struct bt_le_oob_sc_data *oobd_local, const struct bt_le_oob_sc_data *oobd_remote)
Set OOB data during LE Secure Connections (SC) pairing procedure.

This function allows to set OOB data during the LE SC pairing procedure. The function should only be called in response to the `oob_data_request()` callback provided that LE SC method is used for pairing.

The user should submit OOB data according to the information received in the callback. This may yield three different configurations: with only local OOB data present, with only remote OOB data present or with both local and remote OOB data present.

**Parameters**

- `conn` – Connection object
- `oobd_local` – Local OOB data or NULL if not present
- `oobd_remote` – Remote OOB data or NULL if not present

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_le_oob_get_sc_data(struct bt_conn *conn, const struct bt_le_oob_sc_data **oobd_local, const struct bt_le_oob_sc_data **oobd_remote)
```

Get OOB data used for LE Secure Connections (SC) pairing procedure.

This function allows to get OOB data during the LE SC pairing procedure that were set by the `bt_le_oob_set_sc_data()` API.

---

**Note:** The OOB data will only be available as long as the connection object associated with it is valid.

**Parameters**

- `conn` – Connection object
- `oobd_local` – Local OOB data or NULL if not set
- `oobd_remote` – Remote OOB data or NULL if not set

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_passkey_set(unsigned int passkey)
```

Set a fixed passkey to be used for pairing.

This API is only available when the `CONFIG_BT_FIXED_PASSKEY` configuration option has been enabled.

Sets a fixed passkey to be used for pairing. If set, the `pairing_confirm()` callback will be called for all incoming pairings.

**Parameters**

- `passkey` – A valid passkey (0 - 999999) or `BT_PASSKEY_INVALID` to disable a previously set fixed passkey.

**Returns**

0 on success or a negative error code on failure.
int bt_conn_auth_cb_register(const struct bt_conn_auth_cb *cb)
Register authentication callbacks.
Register callbacks to handle authenticated pairing. Passing NULL unregisters a previous callbacks structure.

Parameters
  • cb – Callback struct.

Returns
Zero on success or negative error code otherwise

int bt_conn_auth_cb_overlay(struct bt_conn *conn, const struct bt_conn_auth_cb *cb)
Overlay authentication callbacks used for a given connection.
This function can be used only for Bluetooth LE connections. The CONFIG_BT_SMP must be enabled for this function.
The authentication callbacks for a given connection cannot be overlaid if security procedures in the SMP module have already started. This function can be called only once per connection.

Parameters
  • conn – Connection object.
  • cb – Callback struct.

Returns
Zero on success or negative error code otherwise

int bt_conn_auth_info_cb_register(struct bt_conn_auth_info_cb *cb)
Register authentication information callbacks.
Register callbacks to get authenticated pairing information. Multiple registrations can be done.

Parameters
  • cb – Callback struct.

Returns
Zero on success or negative error code otherwise

int bt_conn_auth_info_cb_unregister(struct bt_conn_auth_info_cb *cb)
Unregister authentication information callbacks.
Unregister callbacks to stop getting authenticated pairing information.

Parameters
  • cb – Callback struct.

Returns
Zero on success or negative error code otherwise

int bt_conn_auth_passkey_entry(struct bt_conn *conn, unsigned int passkey)
Reply with entered passkey.
This function should be called only after passkey_entry callback from bt_conn_auth_cb structure was called.

Parameters
  • conn – Connection object.
  • passkey – Entered passkey.

Returns
Zero on success or negative error code otherwise
int bt_conn_auth_cancel(struct bt_conn *conn)
   Cancel ongoing authenticated pairing.
   This function allows to cancel ongoing authenticated pairing.

   **Parameters**
   - conn – Connection object.

   **Returns**
   Zero on success or negative error code otherwise

int bt_conn_auth_passkey_confirm(struct bt_conn *conn)
   Reply if passkey was confirmed to match by user.
   This function should be called only after passkey_confirm callback from \textit{bt_conn_auth_cb} structure was called.

   **Parameters**
   - conn – Connection object.

   **Returns**
   Zero on success or negative error code otherwise

int bt_conn_auth_pairing_confirm(struct bt_conn *conn)
   Reply if incoming pairing was confirmed by user.
   This function should be called only after pairing_confirm callback from \textit{bt_conn_auth_cb} structure was called if user confirmed incoming pairing.

   **Parameters**
   - conn – Connection object.

   **Returns**
   Zero on success or negative error code otherwise

int bt_conn_auth_pincode_entry(struct bt_conn *conn, const char *pin)
   Reply with entered PIN code.
   This function should be called only after PIN code callback from \textit{bt_conn_auth_cb} structure was called. It's for legacy 2.0 devices.

   **Parameters**
   - conn – Connection object.
   - pin – Entered PIN code.

   **Returns**
   Zero on success or negative error code otherwise

struct bt_conn * bt_conn_create_br(const bt_addr_t *peer, const struct bt_br_conn_param *param)
   Initiate an BR/EDR connection to a remote device.
   Allows initiate new BR/EDR link to remote peer using its address.
   The caller gets a new reference to the connection object which must be released with \textit{bt_conn_unref()} once done using the object.

   **Parameters**
   - peer – Remote address.
   - param – Initial connection parameters.

   **Returns**
   Valid connection object on success or NULL otherwise.
struct bt_conn *bt_conn_create_sco(const bt_addr_t *peer)
Initiate an SCO connection to a remote device.
Allows initiate new SCO link to remote peer using its address.
The caller gets a new reference to the connection object which must be released with bt_conn_unref() once done using the object.

Parameters
- peer – Remote address.

Returns
Valid connection object on success or NULL otherwise.

struct bt_le_conn_param
#include <conn.h> Connection parameters for LE connections

struct bt_conn_le_phy_info
#include <conn.h> Connection PHY information for LE connections

Public Members

uint8_t rx_phy
Connection transmit PHY

struct bt_conn_le_phy_param
#include <conn.h> Preferred PHY parameters for LE connections

Public Members

uint8_t pref_tx_phy
Connection PHY options.

uint8_t pref_rx_phy
Bitmask of preferred transmit PHYs

struct bt_conn_le_data_len_info
#include <conn.h> Connection data length information for LE connections

Public Members

uint16_t tx_max_len
Maximum Link Layer transmission payload size in bytes.

uint16_t tx_max_time
Maximum Link Layer transmission payload time in us.

uint16_t rx_max_len
Maximum Link Layer reception payload size in bytes.
uint16_t rx_max_time
    Maximum Link Layer reception payload time in us.

struct bt_conn_le_data_len_param
    #include <conn.h> Connection data length parameters for LE connections

Public Members

uint16_t tx_max_len
    Maximum Link Layer transmission payload size in bytes.

uint16_t tx_max_time
    Maximum Link Layer transmission payload time in us.

struct bt_conn_le_info
    #include <conn.h> LE Connection Info Structure

Public Members

const bt_addr_le_t *src
    Source (Local) Identity Address

const bt_addr_le_t *dst
    Destination (Remote) Identity Address or remote Resolvable Private Address (RPA) before identity has been resolved.

const bt_addr_le_t *local
    Local device address used during connection setup.

const bt_addr_le_t *remote
    Remote device address used during connection setup.

uint16_t latency
    Connection interval

uint16_t timeout
    Connection peripheral latency

const struct bt_conn_le_phy_info *phy
    Connection supervision timeout

struct bt_conn_br_info
    #include <conn.h> BR/EDR Connection Info Structure

struct bt_security_info
    #include <conn.h> Security Info Structure.
Public Members

\textit{bt\_security\_t} \_level

Security Level.

\textit{uint8\_t} \_enc\_key\_size

Encryption Key Size.

\textit{enum} \textit{bt\_security\_flag} \_flags

Flags.

\textbf{struct} \textit{bt\_conn\_info}

\textit{#include <conn.h>} Connection Info Structure

Public Members

\textit{uint8\_t} \_type

Connection Type.

\textit{uint8\_t} \_role

Connection Role.

\textit{uint8\_t} \_id

Which local identity the connection was created with

\textbf{struct} \textit{bt\_conn\_le\_info} \_le

LE Connection specific Info.

\textbf{struct} \textit{bt\_conn\_br\_info} \_br

BR/EDR Connection specific Info.

\textbf{union} \textit{bt\_conn\_info} \_\[anonymous\] \_\[anonymous\]

Connection Type specific Info.

\textit{enum} \textit{bt\_conn\_state} \_state

Connection state.

\textbf{struct} \textit{bt\_security\_info} \_security

Security specific info.

\textbf{struct} \textit{bt\_conn\_le\_remote\_info}

\textit{#include <conn.h>} LE Connection Remote Info Structure

Public Members

\textit{const uint8\_t} \_\*features

Remote LE feature set (bitmask).
struct bt_conn_br_remote_info
#include <conn.h> BR/EDR Connection Remote Info structure

Public Members

const uint8_t *features
  Remote feature set (pages of bitmasks).

uint8_t num_pages
  Number of pages in the remote feature set.

struct bt_conn_remote_info
#include <conn.h> Connection Remote Info Structure.

Note: The version, manufacturer and subversion fields will only contain valid data if CONFIG_BT_REMOTE_VERSION is enabled.

Public Members

uint8_t type
  Connection Type

uint8_t version
  Remote Link Layer version

uint16_t manufacturer
  Remote manufacturer identifier

uint16_t subversion
  Per-manufacturer unique revision

struct bt_conn_le_remote_info le
  LE connection remote info

struct bt_conn_br_remote_info br
  BR/EDR connection remote info

struct bt_conn_le_tx_power
#include <conn.h> LE Transmit Power Level Structure

Public Members

uint8_t phy
  Input: 1M, 2M, Coded S2 or Coded S8
```
int8_t current_level
    Output: current transmit power level

int8_t max_level
    Output: maximum transmit power level

struct bt_conn_le_create_param
    #include <conn.h>

Public Members

uint32_t options
    Bit-field of create connection options.

uint16_t interval
    Scan interval (N * 0.625 ms)

uint16_t window
    Scan window (N * 0.625 ms)

uint16_t interval_coded
    Scan interval LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan interval

uint16_t window_coded
    Scan window LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan window.

uint16_t timeout
    Connection initiation timeout (N * 10 MS)
    Set zero to use the default CONFIG_BT_CREATE_CONN_TIMEOUT timeout.

Note: Unused in bt_conn_le_create_auto

struct bt_conn_cb
    #include <conn.h> Connection callback structure.
    This structure is used for tracking the state of a connection. It is registered with the help of the bt_conn_cb_register() API. It's permissible to register multiple instances of this bt_conn_cb type, in case different modules of an application are interested in tracking the connection state. If a callback is not of interest for an instance, it may be set to NULL and will as a consequence not be used for that instance.

Public Members
```

6.1. Bluetooth
void (*connected)(struct bt_conn *conn, uint8_t err)
A new connection has been established.
This callback notifies the application of a new connection. In case the err parameter is
non-zero it means that the connection establishment failed.

err can mean either of the following:
• BT_HCI_ERR_UNKNOWN_CONN_ID Creating the connection started by
  bt_conn_le_create was canceled either by the user through bt_conn_disconnect
  or by the timeout in the host through bt_conn_le_create_param timeout parameter,
  which defaults to CONFIG_BT_CREATE_CONN_TIMEOUT seconds.
• BT_HCI_ERR_ADV_TIMEOUT High duty cycle directed connectable advertiser started by
  bt_le_adv_start failed to be connected within the timeout.

Note: If the connection was established from an advertising set then the advertising set
cannot be restarted directly from this callback. Instead use the connected callback of the
advertising set.

Param conn
    New connection object.
Param err
    HCI error. Zero for success, non-zero otherwise.

void (*disconnected)(struct bt_conn *conn, uint8_t reason)
A connection has been disconnected.
This callback notifies the application that a connection has been disconnected.
When this callback is called the stack still has one reference to the connection object. If
the application in this callback tries to start either a connectable advertiser or create a
new connection this might fail because there are no free connection objects available. To
avoid this issue it is recommended to either start connectable advertise or create a new
connection using k_work_submit or increase CONFIG_BT_MAX_CONN.

Param conn
    Connection object.
Param reason
    BT_HCI_ERR_* reason for the disconnection.

bool (*le_param_req)(struct bt_conn *conn, struct bt_le_conn_param *param)
LE connection parameter update request.
This callback notifies the application that a remote device is requesting to update the
connection parameters. The application accepts the parameters by returning true, or
rejects them by returning false. Before accepting, the application may also adjust the
parameters to better suit its needs.

It is recommended for an application to have just one of these callbacks for simplicity.
However, if an application registers multiple it needs to manage the potentially different
requirements for each callback. Each callback gets the parameters as returned by previous
callbacks, i.e. they are not necessarily the same ones as the remote originally sent.
If the application does not have this callback then the default is to accept the parameters.

Param conn
    Connection object.
Param param
    Proposed connection parameters.
Return
    true to accept the parameters, or false to reject them.
void (*le_param_updated)(struct bt_conn *conn, uint16_t interval, uint16_t latency, uint16_t timeout)

The parameters for an LE connection have been updated.

This callback notifies the application that the connection parameters for an LE connection have been updated.

**Param conn**
Connection object.

**Param interval**
Connection interval.

**Param latency**
Connection latency.

**Param timeout**
Connection supervision timeout.

void (*identity_resolved)(struct bt_conn *conn, const bt_addr_le_t *rpa, const bt_addr_le_t *identity)

Remote Identity Address has been resolved.

This callback notifies the application that a remote Identity Address has been resolved.

**Param conn**
Connection object.

**Param rpa**
Resolvable Private Address.

**Param identity**
Identity Address.

void (*security_changed)(struct bt_conn *conn, bt_security_t level, enum bt_security_err err)

The security level of a connection has changed.

This callback notifies the application that the security of a connection has changed.

The security level of the connection can either have been increased or remain unchanged. An increased security level means that the pairing procedure has been performed or the bond information from a previous connection has been applied. If the security level remains unchanged this means that the encryption key has been refreshed for the connection.

**Param conn**
Connection object.

**Param level**
New security level of the connection.

**Param err**

void (*remote_info_available)(struct bt_conn *conn, struct bt_conn_remote_info *remote_info)

Remote information procedures has completed.

This callback notifies the application that the remote information has been retrieved from the remote peer.

**Param conn**
Connection object.

**Param remote_info**
Connection information of remote device.

void (*le_phy_updated)(struct bt_conn *conn, struct bt_conn_le_phy_info *param)

The PHY of the connection has changed.
This callback notifies the application that the PHY of the connection has changed.

**Param conn**
Connection object.

**Param info**
Connection LE PHY information.

```c
void (*le_data_len_updated)(struct bt_conn *conn, struct bt_conn_le_data_len_info *info)
```

The data length parameters of the connection has changed.

This callback notifies the application that the maximum Link Layer payload length or transmission time has changed.

**Param conn**
Connection object.

**Param info**
Connection data length information.

```c
struct bt_conn_oob_info
```

```
#include <conn.h> Info Structure for OOB pairing
```

**Public Types**

```c
eenum [anonymous]
    Type of OOB pairing method

    Values:

    enumerator BT_CONN_OOB_LE_LEGACY
        LE legacy pairing

    enumerator BT_CONN_OOB_LE_SC
        LE SC pairing
```

**Public Members**

```c
eenum bt_conn_oob_info.[anonymous].type
    Type of OOB pairing method

eenum bt_conn_oob_info.[anonymous].[anonymous].[anonymous].oob_config
    OOB data configuration

struct bt_conn_oob_info.[anonymous].[anonymous].lesc
    LE Secure Connections OOB pairing parameters
```

```c
struct bt_conn_pairing_feat
```

```
#include <conn.h> Pairing request and pairing response info structure.
```

This structure is the same for both smp_pairing_req and smp_pairing_rsp and a subset of the packet data, except for the initial Code octet. It is documented in Core Spec. Vol. 3, Part H, 3.5.1 and 3.5.2.
Public Members

uint8_t io_capability
   IO Capability, Core Spec. Vol 3, Part H, 3.5.1, Table 3.4

uint8_t oob_data_flag
   OOB data flag, Core Spec. Vol 3, Part H, 3.5.1, Table 3.5

uint8_t auth_req
   AuthReq, Core Spec. Vol 3, Part H, 3.5.1, Fig. 3.3

uint8_t max_enc_key_size
   Maximum Encryption Key Size, Core Spec. Vol 3, Part H, 3.5.1

uint8_t init_key_dist
   Initiator Key Distribution/Generation, Core Spec. Vol 3, Part H, 3.6.1, Fig. 3.11

uint8_t resp_key_dist
   Responder Key Distribution/Generation, Core Spec. Vol 3, Part H 3.6.1, Fig. 3.11

struct bt_conn_auth_cb
   #include <conn.h> Authenticated pairing callback structure

Public Members

enum bt_security_err (*pairing_accept)(struct bt_conn *conn, const struct
   bt_conn_pairing_feat *const feat)
   Query to proceed incoming pairing or not.
   On any incoming pairing req/rsp this callback will be called for the application to decide
   whether to allow for the pairing to continue.
   The pairing info received from the peer is passed to assist making the decision.
   As this callback is synchronous the application should return a response value immedi-
   ately. Otherwise it may affect the timing during pairing. Hence, this information should
   not be conveyed to the user to take action.
   The remaining callbacks are not affected by this, but do notice that other callbacks can
   be called during the pairing. Eg. if pairing_confirm is registered both will be called for
   Just-Works pairings.
   This callback may be unregistered in which case pairing continues as if the Kconfig flag
   was not set.
   This callback is not called for BR/EDR Secure Simple Pairing (SSP).
   
   Param conn
      Connection where pairing is initiated.
   
   Param feat
      Pairing req/resp info.

   void (*passkey_display)(struct bt_conn *conn, unsigned int passkey)
      Display a passkey to the user.
When called the application is expected to display the given passkey to the user, with the expectation that the passkey will then be entered on the peer device. The passkey will be in the range of 0 - 999999, and is expected to be padded with zeroes so that six digits are always shown. E.g. the value 37 should be shown as 000037.

This callback may be set to NULL, which means that the local device lacks the ability to display a passkey. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop displaying the passkey.

**Param conn**  
Connection where pairing is currently active.

**Param passkey**  
Passkey to show to the user.

```c
void (*passkey_entry)(struct bt_conn *conn)
```

Request the user to enter a passkey.

When called the user is expected to enter a passkey. The passkey must be in the range of 0 - 999999, and should be expected to be zero-padded, as that's how the peer device will typically be showing it (e.g. 37 would be shown as 000037).

Once the user has entered the passkey its value should be given to the stack using the `bt_conn_auth_passkey_entry()` API.

This callback may be set to NULL, which means that the local device lacks the ability to enter a passkey. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop requesting the user to enter a passkey.

**Param conn**  
Connection where pairing is currently active.

```c
void (*passkey_confirm)(struct bt_conn *conn, unsigned int passkey)
```

Request the user to confirm a passkey.

When called the user is expected to confirm that the given passkey is also shown on the peer device. The passkey will be in the range of 0 - 999999, and should be zero-padded to always be six digits (e.g. 37 would be shown as 000037).

Once the user has confirmed the passkey to match, the `bt_conn_auth_passkey_confirm()` API should be called. If the user concluded that the passkey doesn't match the `bt_conn_auth_cancel()` API should be called.

This callback may be set to NULL, which means that the local device lacks the ability to confirm a passkey. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop requesting the user to confirm a passkey.

**Param conn**  
Connection where pairing is currently active.

**Param passkey**  
Passkey to be confirmed.

```c
void (*oob_data_request)(struct bt_conn *conn, struct bt_conn_oob_info *info)
```

Request the user to provide Out of Band (OOB) data.

When called the user is expected to provide OOB data. The required data are indicated by the information structure.

For LE Secure Connections OOB pairing, the user should provide local OOB data, remote OOB data or both depending on their availability. Their value should be given to the stack using the `bt_le_oob_set_sc_data()` API.

This callback must be set to non-NULL in order to support OOB pairing.
**Param conn**
Connection where pairing is currently active.

**Param info**
OOB pairing information.

```c
void (*cancel)(struct bt_conn *conn)
```
Cancel the ongoing user request.

This callback will be called to notify the application that it should cancel any previous user request (passkey display, entry or confirmation).

This may be set to NULL, but must always be provided whenever the passkey_display, passkey_entry passkey_confirm or pairing_confirm callback has been provided.

**Param conn**
Connection where pairing is currently active.

```c
void (*pairing_confirm)(struct bt_conn *conn)
```
Request confirmation for an incoming pairing.

This callback will be called to confirm an incoming pairing request where none of the other user callbacks is applicable.

If the user decides to accept the pairing the `bt_conn_auth_pairing_confirm()` API should be called. If the user decides to reject the pairing the `bt_conn_auth_cancel()` API should be called.

This callback may be set to NULL, which means that the local device lacks the ability to confirm a pairing request. If set to non-NULL the cancel callback must also be provided, since this is the only way the application can find out that it should stop requesting the user to confirm a pairing request.

**Param conn**
Connection where pairing is currently active.

```c
void (*pincode_entry)(struct bt_conn *conn, bool highsec)
```
Request the user to enter a passkey.

This callback will be called for a BR/EDR (Bluetooth Classic) connection where pairing is being performed. Once called the user is expected to enter a PIN code with a length between 1 and 16 digits. If the `highsec` parameter is set to true the PIN code must be 16 digits long.

Once entered, the PIN code should be given to the stack using the `bt_conn_auth_pincode_entry()` API.

This callback may be set to NULL, however in that case pairing over BR/EDR will not be possible. If provided, the cancel callback must be provided as well.

**Param conn**
Connection where pairing is currently active.

**Param highsec**
true if 16 digit PIN is required.

```c
struct bt_conn_auth_info_cb
#include <conn.h> Authenticated pairing information callback structure
```

**Public Members**

```c
void (*pairing_complete)(struct bt_conn *conn, bool bonded)
```
This callback notifies the application that the pairing procedure has been completed.

**Param conn**
Connection object.

**Param bonded**
Bond information has been distributed during the pairing procedure.

```c
void (*pairing_failed)(struct bt_conn *conn, enum bt_security_err reason)
```

notify that pairing process has failed.

**Param conn**
Connection object.

**Param reason**
Pairing failed reason

```c
void (*bond_deleted)(uint8_t id, const bt_addr_le_t *peer)
```

Notify that bond has been deleted.

This callback notifies the application that the bond information for the remote peer has been deleted

**Param id**
Which local identity had the bond.

**Param peer**
Remote address.

```c
sys_snode_t node
```
Internally used field for list handling

```c
#include <conn.h> Connection parameters for BR/EDR connections
```

**Bluetooth Controller**

**API Reference**

**group bt_ctrl**
Bluetooth Controller.

**Functions**

```c
void bt_ctlr_set_public_addr(const uint8_t *addr)
```
Set public address for controller.

Should be called before `bt_enable()`.

**Parameters**

- `addr` – Public address
group bt_gatt_csip
  Coordinated Set Identification Profile (CSIP)
  Copyright (c) 2021-2022 Nordic Semiconductor ASA
  SPDX-License-Identifier: Apache-2.0

  • [Experimental] Users should note that the APIs can change as a part of ongoing development.

Defines

BT_CSIP_SET_COORDINATOR_DISCOVER_TIMER_VALUE
  Recommended timer for member discovery

BT_CSIP_SET_COORDINATOR_MAX_CSIS_INSTANCES

BT_CSIP_READ_SIRK_REQ_RSP_ACCEPT
  Accept the request to read the SIRK as plaintext

BT_CSIP_READ_SIRK_REQ_RSP_ACCEPT_ENC
  Accept the request to read the SIRK, but return encrypted SIRK

BT_CSIP_READ_SIRK_REQ_RSP_REJECT
  Reject the request to read the SIRK

BT_CSIP_READ_SIRK_REQ_RSP_OOB_ONLY
  SIRK is available only via an OOB procedure

BT_CSIP_SET_SIRK_SIZE
  Size of the Set Identification Resolving Key (SIRK)

BT_CSIP_RSI_SIZE
  Size of the Resolvable Set Identifier (RSI)

BT_CSIP_ERROR_LOCK_DENIED
  Service is already locked

BT_CSIP_ERROR_LOCK_RELEASE_DENIED
  Service is not locked

BT_CSIP_ERROR_LOCK_INVAL_VALUE
  Invalid lock value

BT_CSIP_ERROR_SIRK_OOB_ONLY
  SIRK only available out-of-band

BT_CSIP_ERROR_LOCK_ALREADY_GRANTED
  Client is already owner of the lock

6.1. Bluetooth
Helper to declare `bt_data` array including RSI.

This macro is mainly for creating an array of struct `bt_data` elements which is then passed to e.g. `bt_le_ext_adv_start()`.

**Parameters**

• `_rsi` – Pointer to the RSI value

**Typedefs**

typedef void (*bt_csip_set_coordinator_discover_cb)(struct bt_conn *conn, const struct bt_csip_set_coordinator_set_member *member, int err, size_t set_count)

Callback for discovering Coordinated Set Identification Services.

**Param conn**

Pointer to the remote device.

**Param member**

Pointer to the set member.

**Param err**

0 on success, or an errno value on error.

**Param set_count**

Number of sets on the member.

typedef void (*bt_csip_set_coordinator_lock_set_cb)(int err)

Callback for locking a set across one or more devices.

**Param err**

0 on success, or an errno value on error.

typedef void (*bt_csip_set_coordinator_lock_changed_cb)(struct bt_csip_set_coordinator_csis_inst *inst, bool locked)

Callback when the lock value on a set of a connected device changes.

**Param inst**

The Coordinated Set Identification Service instance that was changed.

**Param locked**

Whether the lock is locked or release.

**Return**

int Return 0 on success, or an errno value on error.

typedef void (*bt_csip_set_coordinator_ordered_access_cb_t)(const struct bt_csip_set_coordinator_set_info *set_info, int err, bool locked, struct bt_csip_set_coordinator_set_member *member)

Callback for `bt_csip_set_coordinator_ordered_access()`

If any of the set members supplied to `bt_csip_set_coordinator_ordered_access()` is in the locked state, this will be called with `locked` true and `member` will be the locked member, and the ordered access procedure is cancelled. Likewise, if any error occurs, the procedure will also be aborted.

**Param set_info**

Pointer to the a specific `set_info` struct.

**Param err**

Error value. 0 on success, GATT error or errno on fail.
**Param locked**
Whether the lock is locked or release.

**Param member**
The locked member if `locked` is true, otherwise NULL.

typedef bool (*bt_csip_set_coordinator_ordered_access_t)(const struct bt_csip_set_coordinator_set_info *set_info, struct bt_csip_set_coordinator_set_member *members[], size_t count)

Callback function definition for `bt_csip_set_coordinator_ordered_access()`

**Param set_info**
Pointer to the a specific set_info struct.

**Param members**
Array of members ordered by rank. The procedure shall be done on the members in ascending order.

**Param count**
Number of members in `members`.

**Return**
true if the procedures can be successfully done, or false to stop the procedure.

### Functions

```c
void *bt_csip_set_member_svc_decl_get(const struct bt_csip_set_member_svc_inst *svc_inst)
```

Get the service declaration attribute.

The first service attribute can be included in any other GATT service.

**Parameters**

- `svc_inst` – Pointer to the Coordinated Set Identification Service.

**Returns**

The first CSIS attribute instance.

```c
int bt_csip_set_member_register(const struct bt_csip_set_member_register_param *param, struct bt_csip_set_member_svc_inst **svc_inst)
```

Register a Coordinated Set Identification Service instance.

This will register and enable the service and make it discoverable by clients.

This shall only be done as a server.

**Parameters**

- `param` – Coordinated Set Identification Service register parameters.
- `svc_inst` – [out] Pointer to the registered Coordinated Set Identification Service.

**Returns**

0 if success, errno on failure.

```c
void bt_csip_set_member_print_sirk(const struct bt_csip_set_member_svc_inst *svc_inst)
```

Print the SIRK to the debug output.

**Parameters**

- `svc_inst` – Pointer to the Coordinated Set Identification Service.
int bt_csip_set_member_generate_rsi(const struct bt_csip_set_member_svc_inst *svc_inst, uint8_t rsi[6])

Generate the Resolvable Set Identifier (RSI) value.
This will generate RSI for given svc_inst instance.

Parameters
• svc_inst – Pointer to the Coordinated Set Identification Service.
• rsi – Pointer to the 6-octet newly generated RSI data.

Returns
int 0 if on success, errno on error.

int bt_csip_set_member_lock(struct bt_csip_set_member_svc_inst *svc_inst, bool lock, bool force)

Locks a specific Coordinated Set Identification Service instance on the server.

Parameters
• svc_inst – Pointer to the Coordinated Set Identification Service.
• lock – If true lock the set, if false release the set.
• force – This argument only have meaning when lock is false (release) and will force release the lock, regardless of who took the lock.

Returns
0 on success, GATT error on error.

int bt_csip_set_coordinator_discover(struct bt_conn *conn)

Initialise the csip_set_coordinator instance for a connection. This will do a discovery on the device and prepare the instance for following commands.

Parameters
• conn – Pointer to remote device to perform discovery on.

Returns
int Return 0 on success, or an errno value on error.

bool bt_csip_set_coordinator_is_set_member(const uint8_t set_sirk[16], struct bt_data *data)

Check if advertising data indicates a set member.

Parameters
• set_sirk – The SIRK of the set to check against
• data – The advertising data

Returns
true if the advertising data indicates a set member, false otherwise

int bt_csip_set_coordinator_register_cb(struct bt_csip_set_coordinator_cb *cb)

Registers callbacks for csip_set_coordinator.

Parameters
• cb – Pointer to the callback structure.

Returns
Return 0 on success, or an errno value on error.

int bt_csip_set_coordinator_ordered_access(const struct bt_csip_set_coordinator_set_member *members[], uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info, bt_csip_set_coordinator_ordered_access_t cb)
Access Coordinated Set devices in an ordered manner as a client.

This function will read the lock state of all devices and if all devices are in the unlocked state, then cb will be called with the same members as provided by members, but where the members are ordered by rank (if present). Once this procedure is finished or an error occurs, bt_csip_set_coordinator_cb::ordered_access will be called.

This procedure only works if all the members have the lock characteristic, and all either has rank = 0 or unique ranks.

If any of the members are in the locked state, the procedure will be cancelled.

This can only be done on members that are bonded.

**Parameters**

- `members` – Array of set members to access.
- `count` – Number of set members in `members`.
- `set_info` – Pointer to the a specific set_info struct, as a member may be part of multiple sets.
- `cb` – The callback function to be called for each member.

```c
int bt_csip_set_coordinator_lock(const struct bt_csip_set_coordinator_set_member **members, uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info)
```

Lock an array of set members.

The members will be locked starting from lowest rank going up.

TODO: If locking fails, the already locked members will not be unlocked.

**Parameters**

- `members` – Array of set members to lock.
- `count` – Number of set members in `members`.
- `set_info` – Pointer to the a specific set_info struct, as a member may be part of multiple sets.

**Returns**

Return 0 on success, or an errno value on error.

```c
int bt_csip_set_coordinator_release(const struct bt_csip_set_coordinator_set_member **members, uint8_t count, const struct bt_csip_set_coordinator_set_info *set_info)
```

Release an array of set members.

The members will be released starting from highest rank going down.

**Parameters**

- `members` – Array of set members to lock.
- `count` – Number of set members in `members`.
- `set_info` – Pointer to the a specific set_info struct, as a member may be part of multiple sets.

**Returns**

Return 0 on success, or an errno value on error.

```c
struct bt_csip_set_member_cb

#include <csip.h> Callback structure for the Coordinated Set Identification Service
```

6.1. Bluetooth
Public Members

void (*lock_changed)(struct bt_conn *conn, struct bt_csip_set_member_svc_inst *svc_inst, bool locked)

Callback whenever the lock changes on the server.

- **Param conn**
  The connection to the client that changed the lock. NULL if server changed it, either by calling `bt_csip_set_member_lock()` or by timeout.

- **Param svc_inst**
  Pointer to the Coordinated Set Identification Service.

- **Param locked**
  Whether the lock was locked or released.

uint8_t (*sirk_read_req)(struct bt_conn *conn, struct bt_csip_set_member_svc_inst *svc_inst)

Request from a peer device to read the sirk.

- **Param conn**
  The connection to the client that requested to read the SIRK.

- **Param svc_inst**
  Pointer to the Coordinated Set Identification Service.

- **Return**
  A BT_CSIP_READ_SIRK_REQ_RSP_* response code.

#include <csip.h>

Register structure for Coordinated Set Identification Service

Public Members

uint8_t set_size

Size of the set.

If set to 0, the set size characteristic won't be initialized.

uint8_t set_sirk[16]

The unique Set Identity Resolving Key (SIRK)

This shall be unique between different sets, and shall be the same for each set member for each set.

bool lockable

Boolean to set whether the set is lockable by clients.

Setting this to false will disable the lock characteristic.

uint8_t rank

Rank of this device in this set.

If the lockable parameter is set to true, this shall be > 0 and <= to the set_size. If the lockable parameter is set to false, this may be set to 0 to disable the rank characteristic.

struct bt_csip_set_member_cb *cb

Pointer to the callback structure.
struct bt_csip_set_coordinator_set_info
#include <csip.h> Information about a specific set

**Public Members**

uint8_t set_sirk[16]
The 16 octet set Set Identity Resolving Key (SIRK)
The Set SIRK may not be exposed by the server over Bluetooth, and may require an out-of-band solution.

uint8_t set_size
The size of the set.
Will be 0 if not exposed by the server.

uint8_t rank
The rank of the set on on the remote device.
Will be 0 if not exposed by the server.

struct bt_csip_set_coordinator_csis_inst
#include <csip.h> Struct representing a coordinated set instance on a remote device.
The values in this struct will be populated during discovery of sets (bt_csip_set_coordinator_discover()).

**Public Members**

void *svc_inst
Internally used pointer value

struct bt_csip_set_coordinator_set_member
#include <csip.h> Struct representing a remote device as a set member

**Public Members**

struct bt_csip_set_coordinator_csis_inst insts[0]
Array of Coordinated Set Identification Service instances for the remote device

Cryptography

API Reference

group bt_crypto
Cryptography.
Functions

int bt_rand(void *buf, size_t len)

Generate random data.

A random number generation helper which utilizes the Bluetooth controller's own RNG.

Parameters

• buf – Buffer to insert the random data
• len – Length of random data to generate

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error

int bt_encrypt_le(const uint8_t key[16], const uint8_t plaintext[16], uint8_t enc_data[16])

AES encrypt little-endian data.

An AES encrypt helper is used to request the Bluetooth controller's own hardware to encrypt the plaintext using the key and returns the encrypted data.

Parameters

• key – 128 bit LS byte first key for the encryption of the plaintext
• plaintext – 128 bit LS byte first plaintext data block to be encrypted
• enc_data – 128 bit LS byte first encrypted data block

Returns

Zero on success or error code otherwise.

int bt_encrypt_be(const uint8_t key[16], const uint8_t plaintext[16], uint8_t enc_data[16])

AES encrypt big-endian data.

An AES encrypt helper is used to request the Bluetooth controller's own hardware to encrypt the plaintext using the key and returns the encrypted data.

Parameters

• key – 128 bit MS byte first key for the encryption of the plaintext
• plaintext – 128 bit MS byte first plaintext data block to be encrypted
• enc_data – 128 bit MS byte first encrypted data block

Returns

Zero on success or error code otherwise.

int bt_ccm_decrypt(const uint8_t key[16], uint8_t nonce[13], const uint8_t *enc_data, size_t len, const uint8_t *aad, size_t aad_len, uint8_t *plaintext, size_t mic_size)

Decrypt big-endian data with AES-CCM.

Decrypts and authorizes enc_data with AES-CCM, as described in https://tools.ietf.org/html/rfc3610.

Assumes that the MIC follows directly after the encrypted data.

Parameters

• key – 128 bit MS byte first key
• nonce – 13 byte MS byte first nonce
• enc_data – Encrypted data
• len – Length of the encrypted data
• aad – Additional input data
• aad_len – Additional input data length
• plaintext – Plaintext buffer to place result in
• mic_size – Size of the trailing MIC (in bytes)

Return values
• 0 – Successfully decrypted the data.
• -EINVAL – Invalid parameters.
• -EBADMSG – Authentication failed.

int bt_ccm_encrypt(const uint8_t key[16], uint8_t nonce[13], const uint8_t *plaintext, size_t len, const uint8_t *aad, size_t aad_len, uint8_t *enc_data, size_t mic_size)

Encrypt big-endian data with AES-CCM.
Encrypts and generates a MIC from plaintext with AES-CCM, as described in https://tools.ietf.org/html/rfc3610.
Places the MIC directly after the encrypted data.

Parameters
• key – 128 bit MS byte first key
• nonce – 13 byte MS byte first nonce
• plaintext – Plaintext buffer to encrypt
• len – Length of the encrypted data
• aad – Additional input data
• aad_len – Additional input data length
• enc_data – Buffer to place encrypted data in
• mic_size – Size of the trailing MIC (in bytes)

Return values
• 0 – Successfully encrypted the data.
• -EINVAL – Invalid parameters.

Data Buffers

API Reference

group bt_buf

Data buffers.

Defines

BT_BUF_RESERVE

BT_BUF_SIZE(size)
Helper to include reserved HCI data in buffer calculations

BT_BUF_ACL_SIZE(size)
Helper to calculate needed buffer size for HCI ACL packets

BT_BUF_EVT_SIZE(size)
Helper to calculate needed buffer size for HCI Event packets.
BT_BUF_CMD_SIZE(size)
    Helper to calculate needed buffer size for HCI Command packets.

BT_BUF_ISO_SIZE(size)
    Helper to calculate needed buffer size for HCI ISO packets.

BT_BUF_ACL_RX_SIZE
    Data size needed for HCI ACL RX buffers

BT_BUF_EVT_RX_SIZE
    Data size needed for HCI Event RX buffers

BT_BUF_ISO_RX_SIZE

BT_BUF_ISO_RX_COUNT

BT_BUF_RX_SIZE
    Data size needed for HCI ACL, HCI ISO or Event RX buffers

BT_BUF_RX_COUNT
    Buffer count needed for HCI ACL, HCI ISO or Event RX buffers

BT_BUF_CMD_TX_SIZE
    Data size needed for HCI Command buffers.

Enums

define bt_buf_type
    Possible types of buffers passed around the Bluetooth stack

    Values:

    enumerator BT_BUF_CMD
        HCI command

    enumerator BT_BUF_EVT
        HCI event

    enumerator BT_BUF_ACL_OUT
        Outgoing ACL data

    enumerator BT_BUF_ACL_IN
        Incoming ACL data

    enumerator BT_BUF_ISO_OUT
        Outgoing ISO data

    enumerator BT_BUF_ISO_IN
        Incoming ISO data
enumerator BT_BUF_H4
H:4 data

Functions

struct net_buf *bt_buf_get_rx(enum bt_buf_type type, k_timeout_t timeout)
Allocate a buffer for incoming data
This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_recv_prio().

Parameters
• type – Type of buffer. Only BT_BUF.EVT, BT_BUF_ACL_IN and
  BT_BUF_ISO_IN are allowed.
• timeout – Non-negative waiting period to obtain a buffer or one of the special
  values K_NO_WAIT and K_FOREVER.

Returns
A new buffer.

struct net_buf *bt_buf_get_tx(enum bt_buf_type type, k_timeout_t timeout, const void *data,
  size_t size)
Allocate a buffer for outgoing data
This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_send().

Parameters
• type – Type of buffer. Only BT_BUF_CMD, BT_BUF_ACL_OUT or BT_BUF_H4,
  when operating on H:4 mode, are allowed.
• timeout – Non-negative waiting period to obtain a buffer or one of the special
  values K_NO_WAIT and K_FOREVER.
• data – Initial data to append to buffer.
• size – Initial data size.

Returns
A new buffer.

struct net_buf *bt_buf_get_cmd_complete(k_timeout_t timeout)
Allocate a buffer for an HCI Command Complete/Status Event
This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_recv_prio().

Parameters
• timeout – Non-negative waiting period to obtain a buffer or one of the special
  values K_NO_WAIT and K_FOREVER.

Returns
A new buffer.

struct net_buf *bt_buf_get_evt(uint8_t evt, bool discardable, k_timeout_t timeout)
Allocate a buffer for an HCI Event
This will set the buffer type so bt_buf_set_type() does not need to be explicitly called before bt_recv_prio() or bt_recv().

Parameters
• evt – HCI event code
• discardable – Whether the driver considers the event discardable.
• timeout – Non-negative waiting period to obtain a buffer or one of the special values K_NO_WAIT and K_FOREVER.

Returns
A new buffer.

static inline void bt_buf_set_type(struct net_buf *buf, enum bt_buf_type type)
Set the buffer type

Parameters
• buf – Bluetooth buffer
• type – The BT_* type to set the buffer to

static inline enum bt_buf_type bt_buf_get_type(struct net_buf *buf)
Get the buffer type

Parameters
• buf – Bluetooth buffer

Returns
The BT_* type to of the buffer

struct bt_buf_data
#include <buf.h> This is a base type for bt_buf user data.

Generic Access Profile (GAP)

API Reference

group bt_gap
Generic Access Profile.

Defines

BT_ID_DEFAULT
Convenience macro for specifying the default identity. This helps make the code more readable, especially when only one identity is supported.

BT_DATA(_type, _data, _data_len)
Helper to declare elements of bt_data arrays.
This macro is mainly for creating an array of struct bt_data elements which is then passed to e.g. bt_le_adv_start().

Parameters
• _type – Type of advertising data field
• _data – Pointer to the data field payload
• _data_len – Number of bytes behind the _data pointer
BT_DATA_BYTES(_type, _bytes...)
Helper to declare elements of bt_data arrays.
This macro is mainly for creating an array of struct bt_data elements which is then passed to e.g. bt_le_adv_start().

Parameters
- _type – Type of advertising data field
- _bytes – Variable number of single-byte parameters

BT_LE_ADV_PARAM_INIT(_options, _int_min, _int_max, _peer)
Initialize advertising parameters.

Parameters
- _options – Advertising Options
- _int_min – Minimum advertising interval
- _int_max – Maximum advertising interval
- _peer – Peer address, set to NULL for undirected advertising or address of peer for directed advertising.

BT_LE_ADV_PARAM(_options, _int_min, _int_max, _peer)
Helper to declare advertising parameters inline.

Parameters
- _options – Advertising Options
- _int_min – Minimum advertising interval
- _int_max – Maximum advertising interval
- _peer – Peer address, set to NULL for undirected advertising or address of peer for directed advertising.

BT_LE_ADV_CONN_DIR(_peer)

BT_LE_ADV_CONN

BT_LE_ADV_CONN_NAME

BT_LE_ADV_CONN_NAME_AD

BT_LE_ADV_CONN_DIR_LOW_DUTY(_peer)

BT_LE_ADV_NCONN
Non-connectable advertising with private address

BT_LE_ADV_NCONN_NAME
Non-connectable advertising with BT_LE_ADV_OPT_USE_NAME

BT_LE_ADV_NCONN_IDENTITY
Non-connectable advertising with BT_LE_ADV_OPT_USE_IDENTITY

BT_LE_EXT_ADV_CONN_NAME
Connectable extended advertising with BT_LE_ADV_OPT_USE_NAME
**BT_LE_EXT_ADV_SCAN_NAME**
Scannable extended advertising with **BT_LE_ADV_OPT_USE_NAME**

**BT_LE_EXT_ADV_NCONN**
Non-connectable extended advertising with private address

**BT_LE_EXT_ADV_NCONN_NAME**
Non-connectable extended advertising with **BT_LE_ADV_OPT_USE_NAME**

**BT_LE_EXT_ADV_NCONN_IDENTITY**
Non-connectable extended advertising with **BT_LE_ADV_OPT_USE_IDENTITY**

**BT_LE_EXT_ADV_CODED_NCONN**
Non-connectable extended advertising on coded PHY with private address

**BT_LE_EXT_ADV_CODED_NCONN_NAME**
Non-connectable extended advertising on coded PHY with **BT_LE_ADV_OPT_USE_NAME**

**BT_LE_EXT_ADV_CODED_NCONN_IDENTITY**
Non-connectable extended advertising on coded PHY with **BT_LE_ADV_OPT_USE_IDENTITY**

**BT_LE_EXT_ADV_START_PARAM_INIT**(_timeout, _n_evts)
Helper to initialize extended advertising start parameters inline

**Parameters**
- _timeout – Advertiser timeout
- _n_evts – Number of advertising events

**BT_LE_EXT_ADV_START_PARAM**(_timeout, _n_evts)
Helper to declare extended advertising start parameters inline

**Parameters**
- _timeout – Advertiser timeout
- _n_evts – Number of advertising events

**BT_LE_EXT_ADV_START_DEFAULT**

**BT_LE_PER_ADV_PARAM_INIT**(_int_min, _int_max, _options)
Helper to declare periodic advertising parameters inline

**Parameters**
- _int_min – Minimum periodic advertising interval
- _int_max – Maximum periodic advertising interval
- _options – Periodic advertising properties bitfield.

**BT_LE_PER_ADV_PARAM**(_int_min, _int_max, _options)
Helper to declare periodic advertising parameters inline

**Parameters**
- _int_min – Minimum periodic advertising interval
- _int_max – Maximum periodic advertising interval
- _options – Periodic advertising properties bitfield.
**BT_LE_PER_ADV_DEFAULT**

**BT_LE_SCAN_OPT_FILTER_WHITELIST**

**BT_LE_SCAN_PARAM_INIT(_type, _options, _interval, _window)**
Initialize scan parameters.

**Parameters**
- `_type` – Scan Type, `BT_LE_SCAN_TYPE_ACTIVE` or `BT_LE_SCAN_TYPE_PASSIVE`.
- `_options` – Scan options
- `_interval` – Scan Interval (N * 0.625 ms)
- `_window` – Scan Window (N * 0.625 ms)

**BT_LE_SCAN_PARAM(_type, _options, _interval, _window)**
Helper to declare scan parameters inline.

**Parameters**
- `_type` – Scan Type, `BT_LE_SCAN_TYPE_ACTIVE` or `BT_LE_SCAN_TYPE_PASSIVE`.
- `_options` – Scan options
- `_interval` – Scan Interval (N * 0.625 ms)
- `_window` – Scan Window (N * 0.625 ms)

**BT_LE_SCAN_ACTIVE**
Helper macro to enable active scanning to discover new devices.

**BT_LE_SCAN_PASSIVE**
Helper macro to enable passive scanning to discover new devices.

This macro should be used if information required for device identification (e.g., UUID) are known to be placed in Advertising Data.

**BT_LE_SCAN_CODED_ACTIVE**
Helper macro to enable active scanning to discover new devices. Include scanning on Coded PHY in addition to 1M PHY.

**BT_LE_SCAN_CODED_PASSIVE**
Helper macro to enable passive scanning to discover new devices. Include scanning on Coded PHY in addition to 1M PHY.

This macro should be used if information required for device identification (e.g., UUID) are known to be placed in Advertising Data.

**Typedefs**

typedef void (*bt_ready_cb_t)(int err)
Callback for notifying that Bluetooth has been enabled.

**Param err**
zero on success or (negative) error code otherwise.
typedef void bt_le_scan_cb_t(const bt_addr_le_t *addr, int8_t rssi, uint8_t adv_type, struct net_buf_simple *buf)

Callback type for reporting LE scan results.
A function of this type is given to the bt_le_scan_start() function and will be called for any discovered LE device.

**Param addr**
Advertiser LE address and type.

**Param rssi**
Strength of advertiser signal.

**Param adv_type**
Type of advertising response from advertiser. Uses the BT_GAP_ADV_TYPE_ values.

**Param buf**
Buffer containing advertiser data.

typedef void bt_br_discovery_cb_t(struct bt_br_discovery_result *results, size_t count)

Callback type for reporting BR/EDR discovery (inquiry) results.
A callback of this type is given to the bt_br_discovery_start() function and will be called at the end of the discovery with information about found devices populated in the results array.

**Param results**
Storage used for discovery results

**Param count**
Number of valid discovery results.

**Enums**

eenum [anonymous]
Advertising options

Values:

enumerator BT_LE_ADV_OPT_NONE = 0
Convenience value when no options are specified.

eenumerator BT_LE_ADV_OPT_CONNECTABLE = BIT(0)
Advertise as connectable.
Advertise as connectable. If not connectable then the type of advertising is determined by providing scan response data. The advertiser address is determined by the type of advertising and/or enabling privacy CONFIG_BT_PRIVACY.

eenumerator BT_LE_ADV_OPT_ONE_TIME = BIT(1)
Advertise one time.

Don't try to resume connectable advertising after a connection. This option is only meaningful when used together with BT_LE_ADV_OPT_CONNECTABLE. If set the advertising will be stopped when bt_le_adv_stop() is called or when an incoming (peripheral) connection happens. If this option is not set the stack will take care of keeping advertising enabled even as connections occur. If Advertising directed or the advertiser was started with bt_le_ext_adv_start then this behavior is the default behavior and this flag has no effect.
enumerator BT_LE_ADV_OPT_USE_IDENTITY = BIT(2)
Advertise using identity address.
Advertise using the identity address as the advertiser address.

**Note:** The address used for advertising will not be the same as returned by `bt_le_oob_get_local`, instead `bt_id_get` should be used to get the LE address.

**Warning:** This will compromise the privacy of the device, so care must be taken when using this option.

enumerator BT_LE_ADV_OPT_USE_NAME = BIT(3)
Advertise using GAP device name.

Include the GAP device name automatically when advertising. By default the GAP device name is put at the end of the scan response data.
When advertising using @ref BT_LE_ADV_OPT_EXT_ADV and not @ref BT_LE_ADV_OPT_SCANNABLE then it will be put at the end of the advertising data.
If the GAP device name does not fit into advertising data it will be converted to a shortened name if possible.
@ref BT_LE_ADV_OPT_FORCE_NAME_IN_AD can be used to force the device name to appear in the advertising data of an advert with scan response data.

The application can set the device name itself by including the following in the advertising data.

@code
 BT_DATA(BT_DATA_NAME_COMPLETE, name, sizeof(name) - 1)
@endcode

enumerator BT_LE_ADV_OPT_DIR_MODE_LOW_DUTY = BIT(4)
Low duty cycle directed advertising.

Use low duty directed advertising mode, otherwise high duty mode will be used.

enumerator BT_LE_ADV_OPT_DIR_ADDR_RPA = BIT(5)
Directed advertising to privacy-enabled peer.

Enable use of Resolvable Private Address (RPA) as the target address in directed advertisements. This is required if the remote device is privacy-enabled and supports address resolution of the target address in directed advertisement. It is the responsibility of the application to check that the remote device supports address resolution of directed advertisements by reading its Central Address Resolution characteristic.

enumerator BT_LE_ADV_OPT_FILTER_SCAN_REQ = BIT(6)
Use filter accept list to filter devices that can request scan response data.

enumerator BT_LE_ADV_OPT_FILTER_CONN = BIT(7)
Use filter accept list to filter devices that can connect.
enumerator BT_LE_ADV_OPT_NOTIFY_SCAN_REQ = BIT(8)
    Notify the application when a scan response data has been sent to an active scanner.

enumerator BT_LE_ADV_OPT_SCANNABLE = BIT(9)
    Support scan response data.
    When used together with BT_LE_ADV_OPT_EXT_ADV then this option cannot be used together with the BT_LE_ADV_OPT_CONNECTABLE option. When used together with BT_LE_ADV_OPT_EXT_ADV then scan response data must be set.

enumerator BT_LE_ADV_OPT_EXT_ADV = BIT(10)
    Advertise with extended advertising.
    This options enables extended advertising in the advertising set. In extended advertising the advertising set will send a small header packet on the three primary advertising channels. This small header points to the advertising data packet that will be sent on one of the 37 secondary advertising channels. The advertiser will send primary advertising on LE 1M PHY, and secondary advertising on LE 2M PHY. Connections will be established on LE 2M PHY.
    Without this option the advertiser will send advertising data on the three primary advertising channels.

    **Note:** Enabling this option requires extended advertising support in the peer devices scanning for advertisement packets.

enumerator BT_LE_ADV_OPT_NO_2M = BIT(11)
    Disable use of LE 2M PHY on the secondary advertising channel.
    Disabling the use of LE 2M PHY could be necessary if scanners don't support the LE 2M PHY. The advertiser will send primary advertising on LE 1M PHY, and secondary advertising on LE 1M PHY. Connections will be established on LE 1M PHY.

    **Note:** Cannot be set if BT_LE_ADV_OPT_CODED is set.

    **Note:** Requires BT_LE_ADV_OPT_EXT_ADV.

enumerator BT_LE_ADV_OPT_CODED = BIT(12)
    Advertise on the LE Coded PHY (Long Range).
    The advertiser will send both primary and secondary advertising on the LE Coded PHY. This gives the advertiser increased range with the trade-off of lower data rate and higher power consumption. Connections will be established on LE Coded PHY.

    **Note:** Requires BT_LE_ADV_OPT_EXT_ADV

enumerator BT_LE_ADV_OPT_ANONYMOUS = BIT(13)
    Advertise without a device address (identity or RPA).

    **Note:** Requires BT_LE_ADV_OPT_EXT_ADV
enumerator BT_LE_ADV_OPT_USE_TX_POWER = BIT(14)
Advertise with transmit power.

Note: Requires BT_LE_ADV_OPT_EXT_ADV

enumerator BT_LE_ADV_OPT_DISABLE_CHAN_37 = BIT(15)
Disable advertising on channel index 37.

enumerator BT_LE_ADV_OPT_DISABLE_CHAN_38 = BIT(16)
Disable advertising on channel index 38.

enumerator BT_LE_ADV_OPT_DISABLE_CHAN_39 = BIT(17)
Disable advertising on channel index 39.

enumerator BT_LE_ADV_OPT_FORCE_NAME_IN_AD = BIT(18)
Put GAP device name into advert data.
Will place the GAP device name into the advertising data rather than the scan response data.

Note: Requires BT_LE_ADV_OPT_USE_NAME

enum [anonymous]
Periodic Advertising options

Values:

enumerator BT_LE_PER_ADV_OPT_NONE = 0
Convenience value when no options are specified.

enumerator BT_LE_PER_ADV_OPT_USE_TX_POWER = BIT(1)
Advertise with transmit power.

Note: Requires BT_LE_ADV_OPT_EXT_ADV

enumerator BT_LE_PER_ADV_OPT_INCLUDE_ADI = BIT(2)
Advertise with included AdvDataInfo (ADI).

Note: Requires BT_LE_ADV_OPT_EXT_ADV

enum [anonymous]
Periodic advertising sync options

Values:

enumerator BT_LE_PER_ADV_SYNC_OPT_NONE = 0
Convenience value when no options are specified.
enumerator BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST = BIT(0)
    Use the periodic advertising list to sync with advertiser.
    When this option is set, the address and SID of the parameters are ignored.

enumerator BT_LE_PER_ADV_SYNC_OPT_REPORTING_INITIALLY_DISABLED = BIT(1)
    Disables periodic advertising reports.
    No advertisement reports will be handled until enabled.

enumerator BT_LE_PER_ADV_SYNC_OPT_FILTER_DUPLICATE = BIT(2)
    Filter duplicate Periodic Advertising reports

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOA = BIT(3)
    Sync with Angle of Arrival (AoA) constant tone extension

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOD_1US = BIT(4)
    Sync with Angle of Departure (AoD) 1 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_OPT_DONT_SYNC_AOD_2US = BIT(5)
    Sync with Angle of Departure (AoD) 2 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_OPT_SYNC_ONLY_CONST_TONE_EXT = BIT(6)
    Do not sync to packets without a constant tone extension

enum [anonymous]
    Periodic Advertising Sync Transfer options

Values:

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_NONE = 0
    Convenience value when no options are specified.

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOA = BIT(0)
    No Angle of Arrival (AoA)
    Do not sync with Angle of Arrival (AoA) constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOD_1US = BIT(1)
    No Angle of Departure (AoD) 1 us.
    Do not sync with Angle of Departure (AoD) 1 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_NO_AOD_2US = BIT(2)
    No Angle of Departure (AoD) 2.
    Do not sync with Angle of Departure (AoD) 2 us constant tone extension

enumerator BT_LE_PER_ADV_SYNC_TRANSFER_OPT_SYNC_ONLY_CTE = BIT(3)
    Only sync to packets with constant tone extension

enum [anonymous]
    Values:
enumerator BT_LE_SCAN_OPT_NONE = 0
    Convenience value when no options are specified.

enumerator BT_LE_SCAN_OPT_FILTER_DUPLICATE = BIT(0)
    Filter duplicates.

enumerator BT_LE_SCAN_OPT_FILTER_ACCEPT_LIST = BIT(1)
    Filter using filter accept list.

enumerator BT_LE.Scan_OPT_CODED = BIT(2)
    Enable scan on coded PHY (Long Range).

enumerator BT_LE_SCAN_OPT_NO_1M = BIT(3)
    Disable scan on 1M phy.

    **Note:** Requires `BT_LE_SCAN_OPT_CODED`.

enum [anonymous]

    Values:

enumerator BT.LE_SCAN_TYPE_PASSIVE = 0x00
    Scan without requesting additional information from advertisers.

enumerator BT_LE_SCAN_TYPE_ACTIVE = 0x01
    Scan and request additional information from advertisers.

    Using this scan type will automatically send scan requests to all devices. Scan responses
    are received in the same manner and using the same callbacks as advertising reports.

Functions

int bt_enable(bt_ready_cb_t cb)

    Enable Bluetooth.

    Enable Bluetooth. Must be the called before any calls that require communication with the
    local Bluetooth hardware.

    When `CONFIG_BT_SETTINGS` is enabled, the application must load the Bluetooth settings after
    this API call successfully completes before Bluetooth APIs can be used. Loading the settings be-
    fore calling this function is insufficient. Bluetooth settings can be loaded with `settings_load()`
    or `settings_load_subtree()` with argument “bt”. The latter selectively loads only Bluetooth set-
    tings and is recommended if `settings_load()` has been called earlier.

    **Parameters**

    • `cb` – Callback to notify completion or NULL to perform the enabling syn-
        chronously.

    **Returns**

    Zero on success or (negative) error code otherwise.
int bt_disable(void)
Disable Bluetooth.
Disable Bluetooth. Can't be called before bt_enable has completed.
Close and release HCI resources. Result is architecture dependent.

Returns
Zero on success or (negative) error code otherwise.

bool bt_is_ready(void)
Check if Bluetooth is ready.

Returns
true when Bluetooth is ready, false otherwise

int bt_set_name(const char *name)
Set Bluetooth Device Name.
Set Bluetooth GAP Device Name.
When advertising with device name in the advertising data the name should be updated by calling bt_le_adv_update_data or bt_le_ext_adv_set_data.

Parameters
• name – New name

Returns
Zero on success or (negative) error code otherwise.

const char *bt_get_name(void)
Get Bluetooth Device Name.
Get Bluetooth GAP Device Name.

Returns
Bluetooth Device Name

uint16_t bt_get_appearance(void)
Get local Bluetooth appearance.
Bluetooth Appearance is a description of the external appearance of a device in terms of an Appearance Value.

See also:
https://specificationrefs.bluetooth.com/assigned-values/Appearance%20Values.pdf

Returns
Appearance Value of local Bluetooth host.

int bt_set_appearance(uint16_t new_appearance)
Set local Bluetooth appearance.
Automatically preserves the new appearance across reboots if CONFIG_BT_SETTINGS is enabled.
This symbol is linkable if CONFIG_BT_DEVICE_APPEARANCE_DYNAMIC is enabled.

Parameters
• new_appearance – Appearance Value

Return values
• 0 – Success.
• other – Persistent storage failed. Appearance was not updated.

```c
void bt_id_get(bt_addr_le_t *addrs, size_t *count)
```

Get the currently configured identities.

Returns an array of the currently configured identity addresses. To make sure all available identities can be retrieved, the number of elements in the `addrs` array should be `CONFIG_BT_ID_MAX`. The identity identifier that some APIs expect (such as advertising parameters) is simply the index of the identity in the `addrs` array.

If `addrs` is passed as NULL, then returned `count` contains the count of all available identities that can be retrieved with a subsequent call to this function with non-NULL `addrs` parameter.

---

**Note:** Deleted identities may show up as `BT_ADDR_LE_ANY` in the returned array.

---

### Parameters

- `addrs` – Array where to store the configured identities.
- `count` – Should be initialized to the array size. Once the function returns it will contain the number of returned identities.

```c
int bt_id_create(bt_addr_le_t *addr, uint8_t *irk)
```

Create a new identity.

Create a new identity using the given address and IRK. This function can be called before calling `bt_enable()`, in which case it can be used to override the controller’s public address (in case it has one). However, the new identity will only be stored persistently in flash when this API is used after `bt_enable()`. The reason is that the persistent settings are loaded after `bt_enable()` and would therefore cause potential conflicts with the stack blindly overwriting what’s stored in flash. The identity will also not be written to flash in case a pre-defined address is provided, since in such a situation the app clearly has some place it got the address from and will be able to repeat the procedure on every power cycle, i.e. it would be redundant to also store the information in flash.

Generating random static address or random IRK is not supported when calling this function before `bt_enable()`.

If the application wants to have the stack randomly generate identities and store them in flash for later recovery, the way to do it would be to first initialize the stack (using `bt_enable`), then call `settings_load()`, and after that check with `bt_id_get()` how many identities were recovered. If an insufficient amount of identities were recovered the app may then call `bt_id_create()` to create new ones.

### Parameters

- `addr` – Address to use for the new identity. If NULL or initialized to `BT_ADDR_LE_ANY` the stack will generate a new random static address for the identity and copy it to the given parameter upon return from this function (in case the parameter was non-NULL).
- `irk` – Identity Resolving Key (16 bytes) to be used with this identity. If set to all zeroes or NULL, the stack will generate a random IRK for the identity and copy it back to the parameter upon return from this function (in case the parameter was non-NULL). If privacy `CONFIG_BT_PRIVACY` is not enabled this parameter must be NULL.

### Returns

Identity identifier (>= 0) in case of success, or a negative error code on failure.
Reset/reclaim an identity for reuse.

The semantics of the `addr` and `irk` parameters of this function are the same as with `bt_id_create()`. The difference is the first `id` parameter that needs to be an existing identity (if it doesn't exist this function will return an error). When given an existing identity this function will disconnect any connections created using it, remove any pairing keys or other data associated with it, and then create a new identity in the same slot, based on the `addr` and `irk` parameters.

**Note:** the default identity (BT_ID_DEFAULT) cannot be reset, i.e. this API will return an error if asked to do that.

**Parameters**

- `id` – Existing identity identifier.
- `addr` – Address to use for the new identity. If NULL or initialized to BT_ADDR_LE_ANY the stack will generate a new static random address for the identity and copy it to the given parameter upon return from this function (in case the parameter was non-NULL).
- `irk` – Identity Resolving Key (16 bytes) to be used with this identity. If set to all zeroes or NULL, the stack will generate a random IRK for the identity and copy it back to the parameter upon return from this function (in case the parameter was non-NULL). If privacy CONFIG_BT_PRIVACY is not enabled this parameter must be NULL.

**Returns**

Identity identifier (>= 0) in case of success, or a negative error code on failure.

Delete an identity.

When given a valid identity this function will disconnect any connections created using it, remove any pairing keys or other data associated with it, and then flag it as deleted, so that it can not be used for any operations. To take back into use the slot the identity was occupying the `bt_id_reset()` API needs to be used.

**Note:** the default identity (BT_ID_DEFAULT) cannot be deleted, i.e. this API will return an error if asked to do that.

**Parameters**

- `id` – Existing identity identifier.

**Returns**

0 in case of success, or a negative error code on failure.

Start advertising.

Set advertisement data, scan response data, advertisement parameters and start advertising.

When the advertisement parameter peer address has been set the advertising will be directed to the peer. In this case advertisement data and scan response data parameters are ignored. If the mode is high duty cycle the timeout will be `BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT`. 

```c
int bt_id_reset(uint8_t id, bt_addr_le_t *addr, uint8_t *irk)
```

```c
int bt_id_delete(uint8_t id)
```

```c
int bt_le_adv_start(const struct bt_le_adv_param *param, const struct bt_data *ad, size_t ad_len, const struct bt_data *sd, size_t sd_len)
```
Parameters

- `param` – Advertising parameters.
- `ad` – Data to be used in advertisement packets.
- `ad_len` – Number of elements in ad
- `sd` – Data to be used in scan response packets.
- `sd_len` – Number of elements in sd

Returns

Zero on success or (negative) error code otherwise.

Returns

-ENOMEM No free connection objects available for connectable advertiser.
-CONNREFUSED When connectable advertising is requested and there is already maximum number of connections established in the controller. This error code is only guaranteed when using Zephyr controller, for other controllers code returned in this case may be -EIO.

```c
int bt_le_adv_update_data(const struct bt_data *ad, size_t ad_len, const struct bt_data *sd, size_t sd_len)
```

Update advertising.
Update advertisement and scan response data.

Parameters

- `ad` – Data to be used in advertisement packets.
- `ad_len` – Number of elements in ad
- `sd` – Data to be used in scan response packets.
- `sd_len` – Number of elements in sd

Returns

Zero on success or (negative) error code otherwise.

```c
int bt_le_adv_stop(void)
```

Stop advertising.

Stop ongoing advertising.

Returns

Zero on success or (negative) error code otherwise.

```c
int bt_le_ext_adv_create(const struct bt_le_adv_param *param, const struct bt_le_ext_adv_cb *cb, struct bt_le_ext_adv **adv)
```

Create advertising set.

Create a new advertising set and set advertising parameters. Advertising parameters can be updated with `bt_le_ext_adv_update_param`.

Parameters

- `cb` – [in] Callback struct to notify about advertiser activity. Can be NULL. Must point to valid memory during the lifetime of the advertising set.
- `adv` – [out] Valid advertising set object on success.

Returns

Zero on success or (negative) error code otherwise.
int bt_le_ext_adv_start(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_start_param *param)
Start advertising with the given advertising set.

If the advertiser is limited by either the timeout or number of advertising events the application will be notified by the advertiser sent callback once the limit is reached. If the advertiser is limited by both the timeout and the number of advertising events then the limit that is reached first will stop the advertiser.

Parameters
• adv – Advertising set object.
• param – Advertise start parameters.

int bt_le_ext_adv_stop(struct bt_le_ext_adv *adv)
Stop advertising with the given advertising set.

Stop advertising with a specific advertising set. When using this function the advertising sent callback will not be called.

Parameters
• adv – Advertising set object.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_set_data(struct bt_le_ext_adv *adv, const struct bt_data *ad, size_t ad_len, const struct bt_data *sd, size_t sd_len)
Set an advertising set's advertising or scan response data.

Set advertisement data or scan response data. If the advertising set is currently advertising then the advertising data will be updated in subsequent advertising events.

When both BT_LE_ADV_OPT_EXT_ADV and BT_LE_ADV_OPT_SCANNABLE are enabled then advertising data is ignored. When BT_LE_ADV_OPT_SCANNABLE is not enabled then scan response data is ignored.

If the advertising set has been configured to send advertising data on the primary advertising channels then the maximum data length is BT_GAP_ADV_MAX_ADV_DATA_LEN bytes. If the advertising set has been configured for extended advertising, then the maximum data length is defined by the controller with the maximum possible of BT_GAP_ADV_MAX_EXT_ADV_DATA_LEN bytes.

Note: Not all scanners support extended data length advertising data.

Note: When updating the advertising data while advertising the advertising data and scan response data length must be smaller or equal to what can be fit in a single advertising packet. Otherwise the advertiser must be stopped.

Parameters
• adv – Advertising set object.
• ad – Data to be used in advertisement packets.
• ad_len – Number of elements in ad
• sd – Data to be used in scan response packets.
• sd_len – Number of elements in sd

Returns
Zero on success or (negative) error code otherwise.
int bt_le_ext_adv_update_param(struct bt_le_ext_adv *adv, const struct bt_le_adv_param *param)

Update advertising parameters.

Update the advertising parameters. The function will return an error if the advertiser set is currently advertising. Stop the advertising set before calling this function.

**Note:** When changing the option `BT_LE_ADV_OPT_USE_NAME` then `bt_le_ext_adv_set_data` needs to be called in order to update the advertising data and scan response data.

**Parameters**
- `adv` – Advertising set object.
- `param` – Advertising parameters.

**Returns**
Zero on success or (negative) error code otherwise.

int bt_le_ext_adv_delete(struct bt_le_ext_adv *adv)
Delete advertising set.

Delete advertising set. This will free up the advertising set and make it possible to create a new advertising set.

**Returns**
Zero on success or (negative) error code otherwise.

uint8_t bt_le_ext_adv_get_index(struct bt_le_ext_adv *adv)
Get array index of an advertising set.

This function is used to map bt_adv to index of an array of advertising sets. The array has `CONFIG_BT_EXT_ADV_MAX_ADV_SET` elements.

**Parameters**
- `adv` – Advertising set.

**Returns**
Index of the advertising set object. The range of the returned value is 0..`CONFIG_BT_EXT_ADV_MAX_ADV_SET-1`

int bt_le_ext_adv_get_info(const struct bt_le_ext_adv *adv, struct bt_le_ext_adv_info *info)
Get advertising set info.

**Parameters**
- `adv` – Advertising set object
- `info` – Advertising set info object

**Returns**
Zero on success or (negative) error code on failure.

int bt_le_per_adv_set_param(struct bt_le_ext_adv *adv, const struct bt_le_per_adv_param *param)
Set or update the periodic advertising parameters.

The periodic advertising parameters can only be set or updated on an extended advertisement set which is neither scannable, connectable nor anonymous.

**Parameters**
- `adv` – Advertising set object.
- `param` – Advertising parameters.
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Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_set_data(const struct bt_le_ext_adv *adv, const struct bt_data *ad, size_t ad_len)
Set or update the periodic advertising data.
The periodic advertisement data can only be set or updated on an extended advertisement set which is neither scannable, connectable nor anonymous.

Parameters
• adv – Advertising set object.
• ad – Advertising data.
• ad_len – Advertising data length.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_start(struct bt_le_ext_adv *adv)
Starts periodic advertising.
Enabling the periodic advertising can be done independently of extended advertising, but both periodic advertising and extended advertising shall be enabled before any periodic advertising data is sent. The periodic advertising and extended advertising can be enabled in any order.
Once periodic advertising has been enabled, it will continue advertising until bt_le_per_adv_stop() has been called, or if the advertising set is deleted by bt_le_ext_adv_delete(). Calling bt_le_ext_adv_stop() will not stop the periodic advertising.

Parameters
• adv – Advertising set object.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_stop(struct bt_le_ext_adv *adv)
Stops periodic advertising.
Disabling the periodic advertising can be done independently of extended advertising. Disabling periodic advertising will not disable extended advertising.

Parameters
• adv – Advertising set object.

Returns
Zero on success or (negative) error code otherwise.

uint8_t bt_le_per_adv_sync_get_index(struct bt_le_per_adv_sync *per_adv_sync)
Get array index of an periodic advertising sync object.
This function is get the index of an array of periodic advertising sync objects. The array has CONFIG_BT_PER_ADV_SYNC_MAX elements.

Parameters
• per_adv_sync – The periodic advertising sync object.

Returns
Index of the periodic advertising sync object. The range of the returned value is 0..CONFIG_BT_PER_ADV_SYNC_MAX-1
struct bt_le_per_adv_sync *bt_le_per_adv_sync_lookup_index(uint8_t index)
Get a periodic advertising sync object from the array index.

This function is to get the periodic advertising sync object from the array index. The array has CONFIG_BT_PER_ADV_SYNC_MAX elements.

Parameters
• index – The index of the periodic advertising sync object. The range of the index value is 0..CONFIG_BT_PER_ADV_SYNC_MAX-1

Returns
The periodic advertising sync object of the array index or NULL if invalid index.

int bt_le_per_adv_sync_get_info(struct bt_le_per_adv_sync *per_adv_sync, struct bt_le_per_adv_sync_info *info)
Get periodic adv sync information.

Parameters
• per_adv_sync – Periodic advertising sync object.
• info – Periodic advertising sync info object

Returns
Zero on success or (negative) error code on failure.

struct bt_le_per_adv_sync *bt_le_per_adv_sync_lookup_addr(const bt_addr_le_t *adv_addr, uint8_t sid)
Look up an existing periodic advertising sync object by advertiser address.

Parameters
• adv_addr – Advertiser address.
• sid – The advertising set ID.

Returns
Periodic advertising sync object or NULL if not found.

int bt_le_per_adv_sync_create(const struct bt_le_per_adv_sync_param *param, struct bt_le_per_adv_sync **out_sync)
Create a periodic advertising sync object.

Create a periodic advertising sync object that can try to synchronize to periodic advertising reports from an advertiser. Scan shall either be disabled or extended scan shall be enabled.

Parameters
• param – [in] Periodic advertising sync parameters.
• out_sync – [out] Periodic advertising sync object on.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_delete(struct bt_le_per_adv_sync *per_adv_sync)
Delete periodic advertising sync.

Delete the periodic advertising sync object. Can be called regardless of the state of the sync. If the syncing is currently syncing, the syncing is cancelled. If the sync has been established, it is terminated. The periodic advertising sync object will be invalidated afterwards.

If the state of the sync object is syncing, then a new periodic advertising sync object may not be created until the controller has finished canceling this object.

Parameters
• per_adv_sync – The periodic advertising sync object.
Returns
Zero on success or (negative) error code otherwise.

void bt_le_per_adv_sync_cb_register(struct bt_le_per_adv_sync_cb *cb)
Register periodic advertising sync callbacks.
Adds the callback structure to the list of callback structures for periodic advertising syncs.
This callback will be called for all periodic advertising sync activity, such as synced, terminated
and when data is received.

Parameters
• cb – Callback struct. Must point to memory that remains valid.

int bt_le_per_adv_sync_recv_enable(struct bt_le_per_adv_sync *per_adv_sync)
Enables receiving periodic advertising reports for a sync.
If the sync is already receiving the reports, -EALREADY is returned.

Parameters
• per_adv_sync – The periodic advertising sync object.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_recv_disable(struct bt_le_per_adv_sync *per_adv_sync)
Disables receiving periodic advertising reports for a sync.
If the sync report receiving is already disabled, -EALREADY is returned.

Parameters
• per_adv_sync – The periodic advertising sync object.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_transfer(const struct bt_le_per_adv_sync *per_adv_sync, const struct
bt_conn *conn, uint16_t service_data)
Transfer the periodic advertising sync information to a peer device.
This will allow another device to quickly synchronize to the same periodic advertising train
that this device is currently synced to.

Parameters
• per_adv_sync – The periodic advertising sync to transfer.
• conn – The peer device that will receive the sync information.
• service_data – Application service data provided to the remote host.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_set_info_transfer(const struct bt_le_ext_adv *adv, const struct bt_conn
*conn, uint16_t service_data)
Transfer the information about a periodic advertising set.
This will allow another device to quickly synchronize to periodic advertising set from this
device.

Parameters
• adv – The periodic advertising set to transfer info of.
• conn – The peer device that will receive the information.
• service_data – Application service data provided to the remote host.
Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_transfer_subscribe(const struct bt_conn *conn, const struct bt_le_per_adv_sync_transfer_param *param)
Subscribe to periodic advertising sync transfers (PASTs).
Sets the parameters and allow other devices to transfer periodic advertising syncs.

Parameters
• conn – The connection to set the parameters for. If NULL default parameters for all connections will be set. Parameters set for specific connection will always have precedence.
• param – The periodic advertising sync transfer parameters.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_sync_transfer.unsubscribe(const struct bt_conn *conn)
Unsubscribe from periodic advertising sync transfers (PASTs).
Remove the parameters that allow other devices to transfer periodic advertising syncs.

Parameters
• conn – The connection to remove the parameters for. If NULL default parameters for all connections will be removed. Unsubscribing for a specific device, will still allow other devices to transfer periodic advertising syncs.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_list_add(const bt_addr_le_t *addr, uint8_t sid)
Add a device to the periodic advertising list.
Add peer device LE address to the periodic advertising list. This will make it possibly to automatically create a periodic advertising sync to this device.

Parameters
• addr – Bluetooth LE identity address.
• sid – The advertising set ID. This value is obtained from the \texttt{bt\_le\_scan\_recv\_info} in the scan callback.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_list_remove(const bt_addr_le_t *addr, uint8_t sid)
Remove a device from the periodic advertising list.
Removes peer device LE address from the periodic advertising list.

Parameters
• addr – Bluetooth LE identity address.
• sid – The advertising set ID. This value is obtained from the \texttt{bt\_le\_scan\_recv\_info} in the scan callback.

Returns
Zero on success or (negative) error code otherwise.

int bt_le_per_adv_list_clear(void)
Clear the periodic advertising list.
Clears the entire periodic advertising list.

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Returns
Zero on success or (negative) error code otherwise.

```c
int bt_le_scan_start(const struct bt_le_scan_param *param, bt_le_scan_cb_t cb)
```
Start (LE) scanning.
Start LE scanning with given parameters and provide results through the specified callback.

Note: The LE scanner by default does not use the Identity Address of the local device when CONFIG_BT_PRIVACY is disabled. This is to prevent the active scanner from disclosing the identity information when requesting additional information from advertisers. In order to enable directed advertiser reports then CONFIG_BT_SCAN_WITH_IDENTITY must be enabled.

Parameters
- **param** – Scan parameters.
- **cb** – Callback to notify scan results. May be NULL if callback registration through `bt_le_scan_cb_register` is preferred.

Returns
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_le_scan_stop(void)
```
Stop (LE) scanning.
Stops ongoing LE scanning.

Returns
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
void bt_le_scan_cb_register(struct bt_le_scan_cb *cb)
```
Register scanner packet callbacks.
Adds the callback structure to the list of callback structures that monitors scanner activity.
This callback will be called for all scanner activity, regardless of what API was used to start the scanner.

Parameters
- **cb** – Callback struct. Must point to memory that remains valid.

```c
void bt_le_scan_cb_unregister(struct bt_le_scan_cb *cb)
```
Unregister scanner packet callbacks.
Remove the callback structure from the list of scanner callbacks.

Parameters
- **cb** – Callback struct. Must point to memory that remains valid.

```c
int bt_le_filter_accept_list_add(const bt_addr_le_t *addr)
```
Add device (LE) to filter accept list.
Add peer device LE address to the filter accept list.

Note: The filter accept list cannot be modified when an LE role is using the filter accept list, i.e. advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.
6.1. Bluetooth

Parameters

- addr – Bluetooth LE identity address.

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
static inline int bt_le_whitelist_add(const bt_addr_le_t *addr)
int bt_le_filter_accept_list_remove(const bt_addr_le_t *addr)
    Remove device (LE) from filter accept list.
    Remove peer device LE address from the filter accept list.
```

Note: The filter accept list cannot be modified when an LE role is using the filter accept list, i.e., advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.

Parameters

- addr – Bluetooth LE identity address.

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
static inline int bt_le_whitelist_rem(const bt_addr_le_t *addr)
int bt_le_filter_accept_list_clear(void)
    Clear filter accept list.
    Clear all devices from the filter accept list.
```

Note: The filter accept list cannot be modified when an LE role is using the filter accept list, i.e., advertiser or scanner using a filter accept list or automatic connecting to devices using filter accept list.

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
static inline int bt_le_whitelist_clear(void)
int bt_le_set_chan_map(uint8_t chan_map[5])
    Set (LE) channel map.
```

Parameters

- chan_map – Channel map.

Returns

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

```c
int bt_le_set_rpa_timeout(uint16_t new_rpa_timeout)
    Set the Resolvable Private Address timeout in runtime.
    The new RPA timeout value will be used for the next RPA rotation and all subsequent rotations until another override is scheduled with this API.
```
Initially, the if CONFIG_BT_RPA_TIMEOUT is used as the RPA timeout.
This symbol is linkable if CONFIG_BT_RPA_TIMEOUT_DYNAMIC is enabled.

**Parameters**
- `new_rpa_timeout` – Resolvable Private Address timeout in seconds

**Return values**
- 0 – Success.
- -EINVAL – RPA timeout value is invalid. Valid range is 1s - 3600s.

```c
void bt_data_parse(struct net_buf_simple *ad, bool (*func)(struct bt_data *data, void *user_data), void *user_data)
```
A helper for parsing advertising (or EIR or OOB) data.

**Warning:** This helper function will consume `ad` when parsing. The user should make a copy if the original data is to be used afterwards

**Parameters**
- `ad` – Advertising data as given to the bt_le_scan_cb_t callback.
- `func` – Callback function which will be called for each element that’s found in the data. The callback should return true to continue parsing, or false to stop parsing.
- `user_data` – User data to be passed to the callback.

```c
int bt_le_oob_get_local(uint8_t id, struct bt_le_oob *oob)
```
Get local LE Out of Band (OOB) information.

This function allows to get local information that are useful for Out of Band pairing or connection creation.

If privacy CONFIG_BT_PRIVACY is enabled this will result in generating new Resolvable Private Address (RPA) that is valid for CONFIG_BT_RPA_TIMEOUT seconds. This address will be used for advertising started by `bt_le_adv_start`, active scanning and connection creation.

**Note:** If privacy is enabled the RPA cannot be refreshed in the following cases:
- Creating a connection in progress, wait for the connected callback. In addition when extended advertising CONFIG_BT_EXT_ADV is not enabled or not supported by the controller:
- Advertiser is enabled using a Random Static Identity Address for a different local identity.
- The local identity conflicts with the local identity used by other roles.

**Parameters**
- `id` – [in] Local identity, in most cases BT_ID_DEFAULT.
- `oob` – [out] LE OOB information

**Returns**
Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.
int bt_le_ext_adv_oob_get_local(struct bt_le_ext_adv *adv, struct bt_le_oob *oob)
Get local LE Out of Band (OOB) information.

This function allows to get local information that are useful for Out of Band pairing or connection creation.

If privacy CONFIG_BT_PRIVACY is enabled this will result in generating new Resolvable Private Address (RPA) that is valid for CONFIG_BT_RPA_TIMEOUT seconds. This address will be used by the advertising set.

**Note:** When generating OOB information for multiple advertising set all OOB information needs to be generated at the same time.

**Note:** If privacy is enabled the RPA cannot be refreshed in the following cases:

- Creating a connection in progress, wait for the connected callback.

**Parameters**

- **adv** – [in] The advertising set object
- **oob** – [out] LE OOB information

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

int bt_br_discovery_start(const struct bt_br_discovery_param *param, struct bt_br_discovery_result *results, size_t count, bt_br_discovery_cb_t cb)
Start BR/EDR discovery.

Start BR/EDR discovery (inquiry) and provide results through the specified callback. When bt_br_discovery_cb_t is called it indicates that discovery has completed. If more inquiry results were received during session than fits in provided result storage, only ones with highest RSSI will be reported.

**Parameters**

- **param** – Discovery parameters.
- **results** – Storage for discovery results.
- **count** – Number of results in storage. Valid range: 1-255.
- **cb** – Callback to notify discovery results.

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.

int bt_br_discovery_stop(void)
Stop BR/EDR discovery.

Stops ongoing BR/EDR discovery. If discovery was stopped by this call results won’t be reported.

**Returns**

Zero on success or error code otherwise, positive in case of protocol error or negative (POSIX) in case of stack internal error.
int bt_br_oob_get_local(struct bt_br_oob *oob)
Get BR/EDR local Out Of Band information.

This function allows to get local controller information that are useful for Out Of Band pairing or connection creation process.

Parameters
• oob – Out Of Band information

int bt_br_set_discoverable(bool enable)
Enable/disable set controller in discoverable state.

Allows make local controller to listen on INQUIRY SCAN channel and responds to devices making general inquiry. To enable this state it’s mandatory to first be in connectable state.

Parameters
• enable – Value allowing/disallowing controller to become discoverable.

Returns
Negative if fail set to requested state or requested state has been already set. Zero if done successfully.

int bt_br_set_connectable(bool enable)
Enable/disable set controller in connectable state.

Allows make local controller to be connectable. It means the controller start listen to devices requests on PAGE SCAN channel. If disabled also resets discoverability if was set.

Parameters
• enable – Value allowing/disallowing controller to be connectable.

Returns
Negative if fail set to requested state or requested state has been already set. Zero if done successfully.

int bt_unpair(uint8_t id, const bt_addr_le_t *addr)
Clear pairing information.

Parameters
• id – Local identity (mostly just BT_ID_DEFAULT).
• addr – Remote address, NULL or BT_ADDR_LE_ANY to clear all remote devices.

Returns
0 on success or negative error value on failure.

void bt_foreach_bond(uint8_t id, void (*func)(const struct bt_bond_info *info, void *user_data), void *user_data)
Iterate through all existing bonds.

Parameters
• id – Local identity (mostly just BT_ID_DEFAULT).
• func – Function to call for each bond.
• user_data – Data to pass to the callback function.

int bt_configure_data_path(uint8_t dir, uint8_t id, uint8_t vs_config_len, const uint8_t *vs_config)
Configure vendor data path.

Request the Controller to configure the data transport path in a given direction between the Controller and the Host.
Parameters

- dir – Direction to be configured, BT_HCI_DATAPATH_DIR_HOST_TO_CTLR or BT_HCI_DATAPATH_DIR_CTLR_TO_HOST
- id – Vendor specific logical transport channel ID, range [BT_HCI_DATAPATH_ID_VS..BT_HCI_DATAPATH_ID_VS_END]
- vs_config_len – Length of additional vendor specific configuration data
- vs_config – Pointer to additional vendor specific configuration data

Returns

0 in case of success or negative value in case of error.

```c
struct bt_le_ext_adv_sent_info
    #include <bluetooth.h>

Public Members

uint8_t num_sent
    The number of advertising events completed.
```

```c
struct bt_le_ext_adv_connected_info
    #include <bluetooth.h>

Public Members

struct bt_conn *conn
    Connection object of the new connection
```

```c
struct bt_le_ext_adv_scanned_info
    #include <bluetooth.h>

Public Members

bt_addr_le_t *addr
    Active scanner LE address and type
```

```c
struct bt_le_ext_adv_cb
    #include <bluetooth.h>

Public Members

void (*sent)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_sent_info *info)
    The advertising set has finished sending adv data.
    This callback notifies the application that the advertising set has finished sending advertising data. The advertising set can either have been stopped by a timeout or because the specified number of advertising events has been reached.
```
void (*connected)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_connected_info *info)
The advertising set has accepted a new connection.

Param adv
  The advertising set object.

Param info
  Information about the sent event.

void (*scanned)(struct bt_le_ext_adv *adv, struct bt_le_ext_adv_scanned_info *info)
The advertising set has sent scan response data.

Param adv
  The advertising set object.

Param addr
  Information about the scanned event.

struct bt_data
  #include <bluetooth.h> Bluetooth data.
  
Description of different data types that can be encoded into advertising data. Used to form arrays that are passed to the bt_le_adv_start() function.

struct bt_le_adv_param
  #include <bluetooth.h> LE Advertising Parameters.

Public Members

uint8_t id
  Local identity.
  
Note: When extended advertising CONFIG_BT_EXT_ADV is not enabled or not supported by the controller it is not possible to scan and advertise simultaneously using two different random addresses.

uint8_t sid
  Advertising Set Identifier, valid range 0x00 - 0x0f.
  
Note: Requires BT_LE_ADV_OPT_EXT_ADV

uint8_t secondary_max_skip
  Secondary channel maximum skip count.
Maximum advertising events the advertiser can skip before it must send advertising data on the secondary advertising channel.

**Note:** Requires `BT_LE_ADV_OPT_EXT_ADV`

```c
uint32_t options
    Bit-field of advertising options

uint32_t interval_min
    Minimum Advertising Interval (N * 0.625 milliseconds) Minimum Advertising Interval shall be less than or equal to the Maximum Advertising Interval. The Minimum Advertising Interval and Maximum Advertising Interval should not be the same value (as stated in Bluetooth Core Spec 5.2, section 7.8.5) Range: 0x0020 to 0x4000

uint32_t interval_max
    Maximum Advertising Interval (N * 0.625 milliseconds) Minimum Advertising Interval shall be less than or equal to the Maximum Advertising Interval. The Minimum Advertising Interval and Maximum Advertising Interval should not be the same value (as stated in Bluetooth Core Spec 5.2, section 7.8.5) Range: 0x0020 to 0x4000

const bt_addr_le_t *peer
    Directed advertising to peer.
    When this parameter is set the advertiser will send directed advertising to the remote device.
    The advertising type will either be high duty cycle, or low duty cycle if the `BT_LE_ADV_OPT_DIR_MODE_LOW_DUTY` option is enabled. When using `BT_LE_ADV_OPT_EXT_ADV` then only low duty cycle is allowed.
    In case of connectable high duty cycle if the connection could not be established within the timeout the connected() callback will be called with the status set to `BT_HCI_ERR_ADV_TIMEOUT`.

struct bt_le_per_adv_param
    #include <bluetooth.h>

Public Members

uint16_t interval_min
    Minimum Periodic Advertising Interval (N * 1.25 ms)
    Shall be greater or equal to `BT_GAP_PER_ADV_MIN_INTERVAL` and less or equal to `interval_max`.

uint16_t interval_max
    Maximum Periodic Advertising Interval (N * 1.25 ms)
    Shall be less or equal to `BT_GAP_PER_ADV_MAX_INTERVAL` and greater or equal to `interval_min`.

uint32_t options
    Bit-field of periodic advertising options
struct bt_le_ext_adv_start_param
#include <bluetooth.h>

Public Members

uint16_t timeout
Advertiser timeout (N * 10 ms).
Application will be notified by the advertiser sent callback. Set to zero for no timeout.
When using high duty cycle directed connectable advertising then this parameters must be set to a non-zero value less than or equal to the maximum of BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT.
If privacy CONFIG_BT_PRIVACY is enabled then the timeout must be less than CONFIG_BT_RPA_TIMEOUT.

uint8_t num_events
Number of advertising events.
Application will be notified by the advertiser sent callback. Set to zero for no limit.

struct bt_le_ext_adv_info
#include <bluetooth.h> Advertising set info structure.

Public Members

int8_t tx_power
Currently selected Transmit Power (dBM).

const bt_addr_le_t *addr
Current local advertising address used.

struct bt_le_per_adv_sync_synced_info
#include <bluetooth.h>

Public Members

const bt_addr_le_t *addr
Advertiser LE address and type.

uint8_t sid
Advertiser SID

uint16_t interval
Periodic advertising interval (N * 1.25 ms)

uint8_t phy
Advertiser PHY
bool recv_enabled  
True if receiving periodic advertisements, false otherwise.

uint16_t service_data  
Service Data provided by the peer when sync is transferred.
Will always be 0 when the sync is locally created.

struct bt_conn *conn  
Peer that transferred the periodic advertising sync.
Will always be 0 when the sync is locally created.

struct bt_le_per_adv_sync_term_info  
#include <bluetooth.h>

Public Members

const bt_addr_le_t *addr  
Advertiser LE address and type.

uint8_t sid  
Advertiser SID

uint8_t reason  
Cause of periodic advertising termination

struct bt_le_per_adv_sync_recv_info  
#include <bluetooth.h>

Public Members

const bt_addr_le_t *addr  
Advertiser LE address and type.

uint8_t sid  
Advertiser SID

int8_t tx_power  
The TX power of the advertisement.

int8_t rssi  
The RSSI of the advertisement excluding any CTE.

uint8_t cte_type  
The Constant Tone Extension (CTE) of the advertisement (bt_df_cte_type)

struct bt_le_per_adv_sync_state_info  
#include <bluetooth.h>
Public Members

bool recv_enabled
    True if receiving periodic advertisements, false otherwise.

struct bt_le_per_adv_sync_cb
    #include <bluetooth.h>

Public Members

void (*synced)(struct bt_le_per_adv_sync *sync, struct bt_le_per_adv_sync_synced_info *info)
    The periodic advertising has been successfully synced.
    This callback notifies the application that the periodic advertising set has been successfully
    synced, and will now start to receive periodic advertising reports.
    Param sync
        The periodic advertising sync object.
    Param info
        Information about the sync event.

void (*term)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_term_info *info)
    The periodic advertising sync has been terminated.
    This callback notifies the application that the periodic advertising sync has been termi-
    nated, either by local request, remote request or because due to missing data, e.g. by
    being out of range or sync.
    Param sync
        The periodic advertising sync object.

void (*recv)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_recv_info *info, struct net_buf_simple *buf)
    Periodic advertising data received.
    This callback notifies the application of an periodic advertising report.
    Param sync
        The advertising set object.
    Param info
        Information about the periodic advertising event.
    Param buf
        Buffer containing the periodic advertising data.

void (*state_changed)(struct bt_le_per_adv_sync *sync, const struct bt_le_per_adv_sync_state_info *info)
    The periodic advertising sync state has changed.
    This callback notifies the application about changes to the sync state. Initialize sync and
    termination is handled by their individual callbacks, and won’t be notified here.
    Param sync
        The periodic advertising sync object.
    Param info
        Information about the state change.
void (*biginfo)(struct bt_le_per_adv_sync *sync, const struct bt_iso_biginfo *biginfo)
BIGInfo advertising report received.
This callback notifies the application of a BIGInfo advertising report. This is received if the advertiser is broadcasting isochronous streams in a BIG. See iso.h for more information.

   **Param sync**
   The advertising set object.

   **Param biginfo**
   The BIGInfo report.

void (*cte_report_cb)(struct bt_le_per_adv_sync *sync, struct bt_df_per_adv_sync_iq_samples_report const *info)
Callback for IQ samples report collected when sampling CTE received with periodic advertising PDU.

   **Param sync**
   The periodic advertising sync object.

   **Param info**
   Information about the sync event.

struct bt_le_per_adv_sync_param
#include <bluetooth.h>

**Public Members**

*bt_addr_le_t* addr
Periodic Advertiser Address.

Only valid if not using the periodic advertising list (BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST)

*uint8_t* sid
Advertiser SID.

Only valid if not using the periodic advertising list (BT_LE_PER_ADV_SYNC_OPT_USE_PER_ADV_LIST)

*uint32_t* options
Bit-field of periodic advertising sync options.

*uint16_t* skip
Maximum event skip.

Maximum number of periodic advertising events that can be skipped after a successful receive. Range: 0x0000 to 0x01F3

*uint16_t* timeout
Synchronization timeout (N * 10 ms)
Synchronization timeout for the periodic advertising sync. Range 0x000A to 0x4000 (100 ms to 163840 ms)

*struct bt_le_per_adv_sync_info*
#include <bluetooth.h> Advertising set info structure.
Public Members

`bt_addr_le_t addr`
Periodic Advertiser Address

`uint8_t sid`
Advertiser SID

`uint16_t interval`
Periodic advertising interval (N * 1.25 ms)

`uint8_t phy`
Advertiser PHY

```c
struct bt_le_per_adv_sync_transfer_param
#include <bluetooth.h>
```

Public Members

`uint16_t skip`
Maximum event skip.
The number of periodic advertising packets that can be skipped after a successful receive.

`uint16_t timeout`
Synchronization timeout (N * 10 ms)
Synchronization timeout for the periodic advertising sync. Range 0x000A to 0x4000 (100 ms to 163840 ms)

`uint32_t options`
Periodic Advertising Sync Transfer options

```c
struct bt_le_scan_param
#include <bluetooth.h>
```
LE scan parameters

Public Members

`uint8_t type`
Scan type (BT_LE_SCAN_TYPE_ACTIVE or BT_LE_SCAN_TYPE_PASSIVE)

`uint32_t options`
Bit-field of scanning options.

`uint16_t interval`
Scan interval (N * 0.625 ms)

`uint16_t window`
Scan window (N * 0.625 ms)
uint16_t timeout
    Scan timeout (N * 10 ms)
    Application will be notified by the scan timeout callback. Set zero to disable timeout.

uint16_t interval_coded
    Scan interval LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan interval.

uint16_t window_coded
    Scan window LE Coded PHY (N * 0.625 MS)
    Set zero to use same as LE 1M PHY scan window.

struct bt_le_scan_recv_info
    #include <bluetooth.h> LE advertisement and scan response packet information

Public Members

const bt_addr_le_t *addr
    Advertiser LE address and type.
    If advertiser is anonymous then this address will be BT_ADDR_LE_ANY.

uint8_t sid
    Advertising Set Identifier.

int8_t rssi
    Strength of advertiser signal.

int8_t tx_power
    Transmit power of the advertiser.

uint8_t adv_type
    Advertising packet type.
    Uses the BT_GAP_ADV_TYPE_* value.
    May indicate that this is a scan response if the type is BT_GAP_ADV_TYPE_SCAN_RSP.

uint16_t adv_props
    Advertising packet properties bitfield.
    Uses the BT_GAP_ADV_PROP_* values. May indicate that this is a scan response if the value contains the BT_GAP_ADV_PROP_SCAN_RESPONSE bit.

uint16_t interval
    Periodic advertising interval.
    If 0 there is no periodic advertising.

uint8_t primary_phy
    Primary advertising channel PHY.
uint8_t secondary_phy
Secondary advertising channel PHY.

struct bt_le_scan_cb
#include <bluetooth.h> Listener context for (LE) scanning.

Public Members

void (*recv)(const struct bt_le_scan_recv_info *info, struct net_buf_simple *buf)
Advertisement packet and scan response received callback.

Param info
Advertiser packet and scan response information.

Param buf
Buffer containing advertiser data.

void (*timeout)(void)
The scanner has stopped scanning after scan timeout.

struct bt_le_oob_sc_data
#include <bluetooth.h> LE Secure Connections pairing Out of Band data.

Public Members

uint8_t r[16]
Random Number.

uint8_t c[16]
Confirm Value.

struct bt_le_oob
#include <bluetooth.h> LE Out of Band information.

Public Members

bt_addr_le_t addr
LE address. If privacy is enabled this is a Resolvable Private Address.

struct bt_le_oob_sc_data le_sc_data
LE Secure Connections pairing Out of Band data.

struct bt_br_discovery_result
#include <bluetooth.h> BR/EDR discovery result structure.

Public Members
bt_addr_t addr
    Remote device address

int8_t rssi
    RSSI from inquiry

tUint8_t cod[3]
    Class of Device

tUint8_t eir[240]
    Extended Inquiry Response

struct bt_br_discovery_param
    #include <bluetooth.h> BR/EDR discovery parameters

Public Members

uint8_t length
    Maximum length of the discovery in units of 1.28 seconds. Valid range is 0x01 - 0x30.

bool limited
    True if limited discovery procedure is to be used.

struct bt_br_oob
    #include <bluetooth.h>

Public Members

bt_addr_t addr
    BR/EDR address.

struct bt_bond_info
    #include <bluetooth.h> Information about a bond with a remote device.

Public Members

bt_addr_le_t addr
    Address of the remote device.

group bt_addr
    Bluetooth device address definitions and utilities.

Defines

BT_ADDR_LE_PUBLIC


```
BT_ADDR_LE_RANDOM

BT_ADDR_LE_PUBLIC_ID

BT_ADDR_LE_RANDOM_ID

BT_ADDR_LE_UNRESOLVED

BT_ADDR_LE_ANONYMOUS

BT_ADDR_SIZE
   Length in bytes of a standard Bluetooth address

BT_ADDR_LE_SIZE
   Length in bytes of an LE Bluetooth address. Not packed, so no sizeof()

BT_ADDR_ANY
   Bluetooth device “any” address, not a valid address

BT_ADDR_NONE
   Bluetooth device “none” address, not a valid address

BT_ADDR_LE_ANY
   Bluetooth LE device “any” address, not a valid address

BT_ADDR_LE_NONE
   Bluetooth LE device “none” address, not a valid address

BT_ADDR_IS_RPA(a)
   Check if a Bluetooth LE random address is resolvable private address.

BT_ADDR_IS_NRPA(a)
   Check if a Bluetooth LE random address is a non-resolvable private address.

BT_ADDR_IS_STATIC(a)
   Check if a Bluetooth LE random address is a static address.

BT_ADDR_SET_RPA(a)
   Set a Bluetooth LE random address as a resolvable private address.

BT_ADDR_SET_NRPA(a)
   Set a Bluetooth LE random address as a non-resolvable private address.

BT_ADDR_SET_STATIC(a)
   Set a Bluetooth LE random address as a static address.

BT_ADDR_STR_LEN
   Recommended length of user string buffer for Bluetooth address.
   The recommended length guarantee the output of address conversion will not lose valuable
   information about address being processed.
```
BT_ADDR_LE_STR_LEN

Recommended length of user string buffer for Bluetooth LE address.

The recommended length guarantee the output of address conversion will not lose valuable information about address being processed.

Functions

static inline int bt_addr_cmp(const bt_addr_t *a, const bt_addr_t *b)

Compare Bluetooth device addresses.

Parameters

• a – First Bluetooth device address to compare
• b – Second Bluetooth device address to compare

Returns

negative value if $a < b$, 0 if $a == b$, else positive

static inline int bt_addr_le_cmp(const bt_addr_le_t *a, const bt_addr_le_t *b)

Compare Bluetooth LE device addresses.

See also:

bt_addr_le_eq

Parameters

• a – First Bluetooth LE device address to compare
• b – Second Bluetooth LE device address to compare

Returns

negative value if $a < b$, 0 if $a == b$, else positive

static inline bool bt_addr_le_eq(const bt_addr_le_t *a, const bt_addr_le_t *b)

Determine equality of two Bluetooth LE device addresses.

The Bluetooth LE addresses are equal iff both the types and the 48-bit addresses are numerically equal.

Return values

• true – if the two addresses are equal
• false – otherwise

static inline void bt_addr_copy(bt_addr_t *dst, const bt_addr_t *src)

Copy Bluetooth device address.

Parameters

• dst – Bluetooth device address destination buffer.
• src – Bluetooth device address source buffer.

static inline void bt_addr_le_copy(bt_addr_le_t *dst, const bt_addr_le_t *src)

Copy Bluetooth LE device address.

Parameters

• dst – Bluetooth LE device address destination buffer.
• src – Bluetooth LE device address source buffer.
int bt_addr_le_create_nrpa(bt_addr_le_t *addr)
Create a Bluetooth LE random non-resolvable private address.

int bt_addr_le_create_static(bt_addr_le_t *addr)
Create a Bluetooth LE random static address.

static inline bool bt_addr_le_is_rpa(const bt_addr_le_t *addr)
Check if a Bluetooth LE address is a random private resolvable address.

Parameters
• addr – Bluetooth LE device address.

Returns
true if address is a random private resolvable address.

static inline bool bt_addr_le_is_identity(const bt_addr_le_t *addr)
Check if a Bluetooth LE address is valid identity address.

Valid Bluetooth LE identity addresses are either public address or random static address.

Parameters
• addr – Bluetooth LE device address.

Returns
true if address is a valid identity address.

static inline int bt_addr_to_str(const bt_addr_t *addr, char *str, size_t len)
Converts binary Bluetooth address to string.

Parameters
• addr – Address of buffer containing binary Bluetooth address.
• str – Address of user buffer with enough room to store formatted string containing binary address.
• len – Length of data to be copied to user string buffer. Refer to BT_ADDR_STR_LEN about recommended value.

Returns
Number of successfully formatted bytes from binary address.

static inline int bt_addr_le_to_str(const bt_addr_le_t *addr, char *str, size_t len)
Converts binary LE Bluetooth address to string.

Parameters
• addr – Address of buffer containing binary LE Bluetooth address.
• str – Address of user buffer with enough room to store formatted string containing binary LE address.
• len – Length of data to be copied to user string buffer. Refer to BT_ADDR_LE_STR_LEN about recommended value.

Returns
Number of successfully formatted bytes from binary address.

int bt_addr_from_str(const char *str, bt_addr_t *addr)
Convert Bluetooth address from string to binary.

Parameters
• str – [in] The string representation of a Bluetooth address.
• addr – [out] Address of buffer to store the Bluetooth address
Returns
Zero on success or (negative) error code otherwise.

int bt_addr_le_from_str(const char *str, const char *type, bt_addr_le_t *addr)
Convert LE Bluetooth address from string to binary.

Parameters
• str – [in] The string representation of an LE Bluetooth address.
• type – [in] The string representation of the LE Bluetooth address type.
• addr – [out] Address of buffer to store the LE Bluetooth address

Returns
Zero on success or (negative) error code otherwise.

Variables

const bt_addr_t bt_addr_any

const bt_addr_t bt_addr_none

const bt_addr_le_t bt_addr_le_any

const bt_addr_le_t bt_addr_le_none

struct bt_addr_t
#include <addr.h> Bluetooth Device Address

struct bt_addr_le_t
#include <addr.h> Bluetooth LE Device Address

group bt_gap_defines
Bluetooth Generic Access Profile defines and Assigned Numbers.

Defines

BT_COMP_ID_LF
Company Identifiers (see Bluetooth Assigned Numbers)

BT_DATA_FLAGS
EIR/AD data type definitions

BT_DATA_UUID16_SOME

BT_DATA_UUID16_ALL

BT_DATA_UUID32_SOME

BT_DATA_UUID32_ALL
BT_DATA_UUID128_SOME
BT_DATA_UUID128_ALL
BT_DATA_NAME_SHORTENED
BT_DATA_NAME_COMPLETE
BT_DATA_TX_POWER
BT_DATA_SM_TK_VALUE
BT_DATA_SM_OOB_FLAGS
BT_DATA_PERIPHERAL_INT_RANGE
BT_DATA_SOLICIT16
BT_DATA_SOLICIT128
BT_DATA_SVC_DATA16
BT_DATA_PUB_TARGET_ADDR
BT_DATA_RAND_TARGET_ADDR
BT_DATA_GAP_APPEARANCE
BT_DATA_ADV_INT
BT_DATA_LE_BT_DEVICE_ADDRESS
BT_DATA_LE_ROLE
BT_DATA_SIMPLE_PAIRING_HASH
BT_DATA_SIMPLE_PAIRING_RAND
BT_DATA_SOLICIT32
BT_DATA_SVC_DATA32
BT_DATA_SVC_DATA128
BT_DATA_LE_SC_CONFIRM_VALUE
BT_DATA_LE_SC_RANDOM_VALUE

BT_DATA_URI

BT_DATA_INDOOR_POS

BT_DATA_TRANS_DISCOVER_DATA

BT_DATA_LE_SUPPORTED_FEATURES

BT_DATA_CHANNEL_MAP_UPDATE_IND

BT_DATA_MESH_PROV

BT_DATA_MESH_MESSAGE

BT_DATA_MESH_BEACON

BT_DATA_BIG_INFO

BT_DATA_BROADCAST_CODE

BT_DATA_CSIS_RSI

BT_DATA_ADV_INT_LONG

BT_DATA_BROADCAST_NAME

BT_DATA_3D_INFO

BT_DATA_MANUFACTURER_DATA

BT_LE_AD_LIMITED

BT_LE_AD_GENERAL

BT_LE_AD_NO_BREDR

BT_GAP_SCAN_FAST_INTERVAL

BT_GAP_SCAN_FAST_WINDOW

BT_GAP_SCAN_SLOW_INTERVAL_1

BT_GAP_SCAN_SLOW_WINDOW_1
Maximum advertising data length.

Maximum extended advertising data length.

Note: The maximum advertising data length that can be sent by an extended advertiser is defined by the controller.
BT_GAP_SID_INVALID

BT_GAP_NO_TIMEOUT

BT_GAP_ADV_HIGH_DUTY_CYCLE_MAX_TIMEOUT

BT_GAP_DATA_LEN_DEFAULT

BT_GAP_DATA_LEN_MAX

BT_GAP_DATA_TIME_DEFAULT

BT_GAP_DATA_TIME_MAX

BT_GAP_SID_MAX

BT_GAP_PER_ADV_MAX_SKIP

BT_GAP_PER_ADV_MIN_TIMEOUT

BT_GAP_PER_ADV_MAX_TIMEOUT

BT_GAP_PER_ADV_INTERVAL_TO_MS(interval)
Minimum Periodic Advertising Interval (N * 1.25 ms)

Maximum Periodic Advertising Interval (N * 1.25 ms)

Convert periodic advertising interval (N * 1.25 ms) to milliseconds.
5 / 4 represents 1.25 ms unit.

BT_LE_SUPP_FEAT_40_ENCODE(w64)
Encode 40 least significant bits of 64-bit LE Supported Features into array values in little-endian format.

Helper macro to encode 40 least significant bits of 64-bit LE Supported Features value into advertising data. The number of bits that are encoded is a number of LE Supported Features defined by BT 5.3 Core specification.

Example of how to encode the 0x000000DFF00DF00D into advertising data.

\[
\text{BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_40_ENCODE(0x000000DFF00DF00D))}
\]

**Parameters**

- `w64` – LE Supported Features value (64-bits)

**Returns**

The comma separated values for LE Supported Features value that may be used directly as an argument for `BT_DATA_BYTES`.
BT_LE_SUPP_FEAT_32_ENCODE(w64)

Encode 4 least significant bytes of 64-bit LE Supported Features into 4 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 4 least significant bytes into advertising data. Other 4 bytes are not encoded.

Example of how to encode the 0x000000DFF00DF00D into advertising data.

```
BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_32_ENCODE(0x000000DFF00DF00D))
```

**Parameters**

- `w64` – LE Supported Features value (64-bits)

**Returns**

The comma separated values for LE Supported Features value that may be used directly as an argument for `BT_DATA_BYTES`.

BT_LE_SUPP_FEAT_24_ENCODE(w64)

Encode 3 least significant bytes of 64-bit LE Supported Features into 3 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 3 least significant bytes into advertising data. Other 5 bytes are not encoded.

Example of how to encode the 0x000000DFF00DF00D into advertising data.

```
BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_24_ENCODE(0x000000DFF00DF00D))
```

**Parameters**

- `w64` – LE Supported Features value (64-bits)

**Returns**

The comma separated values for LE Supported Features value that may be used directly as an argument for `BT_DATA_BYTES`.

BT_LE_SUPP_FEAT_16_ENCODE(w64)

Encode 2 least significant bytes of 64-bit LE Supported Features into 2 bytes long array of values in little-endian format.

Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes 3 least significant bytes into advertising data. Other 6 bytes are not encoded.

Example of how to encode the 0x000000DFF00DF00D into advertising data.

```
BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_16_ENCODE(0x000000DFF00DF00D))
```

**Parameters**

- `w64` – LE Supported Features value (64-bits)
Returns
The comma separated values for LE Supported Features value that may be used directly as an argument for `BT_DATA_BYTES`.

`BT_LE_SUPP_FEAT_8_ENCODE(w64)`
Encode the least significant byte of 64-bit LE Supported Features into single byte long array.
Helper macro to encode 64-bit LE Supported Features value into advertising data. The macro encodes the least significant byte into advertising data. Other 7 bytes are not encoded.
Example of how to encode the `0x000000DFF00DF00D` into advertising data.

```c
BT_DATA_BYTES(BT_DATA_LE_SUPPORTED_FEATURES, BT_LE_SUPP_FEAT_8_ENCODE(0x000000DFF00DF00D))
```

Parameters
- `w64` – LE Supported Features value (64-bits)

Returns
The value of least significant byte of LE Supported Features value that may be used directly as an argument for `BT_DATA_BYTES`.

`BT_LE_SUPP_FEAT_VALIDATE(w64)`
Validate whether LE Supported Features value does not use bits that are reserved for future use.
Helper macro to check if `w64` has zeros as bits 40-63. The macro is compliant with BT 5.3 Core Specification where bits 0-40 has assigned values. In case of invalid value, build time error is reported.

Enums

c
```
enum [anonymous]
LE PHY types
Values:

enumerator BT_GAP_LE_PHY_NONE = 0
    Convenience macro for when no PHY is set.

enumerator BT_GAP_LE_PHY_1M = BIT(0)
    LE 1M PHY

enumerator BT_GAP_LE_PHY_2M = BIT(1)
    LE 2M PHY

enumerator BT_GAP_LE_PHY_CODED = BIT(2)
    LE Coded PHY
```
```c
enum [anonymous]
Advertising PDU types
Values:
```
enumerator BT_GAP_ADV_TYPE_ADV_IND = 0x00
   Scannable and connectable advertising.

enumerator BT_GAP_ADV_TYPE_ADV_DIRECT_IND = 0x01
   Directed connectable advertising.

enumerator BT_GAP_ADV_TYPE_ADV_SCAN_IND = 0x02
   Non-connectable and scannable advertising.

enumerator BT_GAP_ADV_TYPE_ADV_NONCONN_IND = 0x03
   Non-connectable and non-scannable advertising.

enumerator BT_GAP_ADV_TYPE_SCAN_RSP = 0x04
   Additional advertising data requested by an active scanner.

enumerator BT_GAP_ADV_TYPE_EXT_ADV = 0x05
   Extended advertising, see advertising properties.

enum [anonymous]
   Advertising PDU properties
   Values:

   enumerator BT_GAP_ADV_PROP_CONNECTABLE = BIT(0)
      Connectable advertising.

   enumerator BT_GAP_ADV_PROP_SCANNABLE = BIT(1)
      Scannable advertising.

   enumerator BT_GAP_ADV_PROP_DIRECTED = BIT(2)
      Directed advertising.

   enumerator BT_GAP_ADV_PROP_SCAN_RESPONSE = BIT(3)
      Additional advertising data requested by an active scanner.

   enumerator BT_GAP_ADV_PROP_EXT_ADV = BIT(4)
      Extended advertising.

enum [anonymous]
   Constant Tone Extension (CTE) types
   Values:

   enumerator BT_GAP_CTE_AOA = 0x00
      Angle of Arrival

   enumerator BT_GAP_CTE_AOD_1US = 0x01
      Angle of Departure with 1 us slots
enumerator BT_GAP_CTE_AOD_2US = 0x02
   Angle of Departure with 2 us slots

enumerator BT_GAP_CTE_NONE = 0xFF
   No extensions

enum [anonymous]
   Peripheral sleep clock accuracy (SCA) in ppm (parts per million)
   Values:

   enumerator BT_GAP_SCA_UNKNOWN = 0

   enumerator BT_GAP_SCA_251_500 = 0

   enumerator BT_GAP_SCA_151_250 = 1

   enumerator BT_GAP_SCA_101_150 = 2

   enumerator BT_GAP_SCA_76_100 = 3

   enumerator BT_GAP_SCA_51_75 = 4

   enumerator BT_GAP_SCA_31_50 = 5

   enumerator BT_GAP_SCA_21_30 = 6

   enumerator BT_GAP_SCA_0_20 = 7

Generic Attribute Profile (GATT)

GATT layer manages the service database providing APIs for service registration and attribute declaration.

Services can be registered using `bt_gatt_service_register()` API which takes the `bt_gatt_service` struct that provides the list of attributes the service contains. The helper macro `BT_GATT_SERVICE()` can be used to declare a service.

Attributes can be declared using the `bt_gatt_attr` struct or using one of the helper macros:

- `BT_GATT_PRIMARY_SERVICE`
  Declares a Primary Service.
- `BT_GATT_SECONDARY_SERVICE`
  Declares a Secondary Service.
- `BT_GATT_INCLUDE_SERVICE`
  Declares a Include Service.
- `BT_GATT_CHARACTERISTIC`
  Declares a Characteristic.
- `BT_GATT_DESCRIPTOR`
  Declares a Descriptor.
BT_GATT_ATTRIBUTE
Declares an Attribute.

BT_GATT_CCC
Declares a Client Characteristic Configuration.

BT_GATT_CEP
Declares a Characteristic Extended Properties.

BT_GATT_CUD
Declares a Characteristic User Format.

Each attribute contains a uuid, which describes their type, a read callback, a write callback and a set of permission. Both read and write callbacks can be set to NULL if the attribute permission don’t allow their respective operations.

**Note:** 32-bit UUIDs are not supported in GATT. All 32-bit UUIDs shall be converted to 128-bit UUIDs when the UUID is contained in an ATT PDU.

**Note:** Attribute read and write callbacks are called directly from RX Thread thus it is not recommended to block for long periods of time in them.

Attribute value changes can be notified using `bt_gatt_notify()` API, alternatively there is `bt_gatt_notify_cb()` where it is possible to pass a callback to be called when it is necessary to know the exact instant when the data has been transmitted over the air. Indications are supported by `bt_gatt_indicate()` API.

Client procedures can be enabled with the configuration option: `CONFIG_BT_GATT_CLIENT`

Discover procedures can be initiated with the use of `bt_gatt_discover()` API which takes the `bt_gatt_discover_params` struct which describes the type of discovery. The parameters also serve as a filter when setting the uuid field only attributes which matches will be discovered, in contrast setting it to NULL allows all attributes to be discovered.

**Note:** Caching discovered attributes is not supported.

Read procedures are supported by `bt_gatt_read()` API which takes the `bt_gatt_read_params` struct as parameters. In the parameters one or more attributes can be set, though setting multiple handles requires the option: `CONFIG_BT_GATT_READ_MULTIPLE`

Write procedures are supported by `bt_gatt_write()` API and takes `bt_gatt_write_params` struct as parameters. In case the write operation don’t require a response `bt_gatt_write_without_response()` or `bt_gatt_write_without_response_cb()` APIs can be used, with the later working similarly to `bt_gatt_notify_cb()`.

Subscriptions to notification and indication can be initiated with use of `bt_gatt_subscribe()` API which takes `bt_gatt_subscribe_params` as parameters. Multiple subscriptions to the same attribute are supported so there could be multiple notify callback being triggered for the same attribute. Subscriptions can be removed with use of `bt_gatt_unsubscribe()` API.

**Note:** When subscriptions are removed notify callback is called with the data set to NULL.

**API Reference**

`group bt_gatt`

Generic Attribute Profile (GATT)
Defines

BT_GATT_ERR(_att_err)
Construct error return value for attribute read and write callbacks.

Parameters
- _att_err – ATT error code

Returns
Appropriate error code for the attribute callbacks.

BT_GATT_CHRC_BROADCAST
Characteristic broadcast property.

Characteristic Properties Bit field values
If set, permits broadcasts of the Characteristic Value using Server Characteristic Configuration Descriptor.

BT_GATT_CHRC_READ
Characteristic read property.
If set, permits reads of the Characteristic Value.

BT_GATT_CHRC_WRITE_WITHOUT_RESP
Characteristic write without response property.
If set, permits write of the Characteristic Value without response.

BT_GATT_CHRC_WRITE
Characteristic write with response property.
If set, permits write of the Characteristic Value with response.

BT_GATT_CHRC_NOTIFY
Characteristic notify property.
If set, permits notifications of a Characteristic Value without acknowledgment.

BT_GATT_CHRC_INDICATE
Characteristic indicate property.
If set, permits indications of a Characteristic Value with acknowledgment.

BT_GATT_CHRC_AUTH
Characteristic Authenticated Signed Writes property.
If set, permits signed writes to the Characteristic Value.

BT_GATT_CHRC_EXT_PROP
Characteristic Extended Properties property.
If set, additional characteristic properties are defined in the Characteristic Extended Properties Descriptor.

BT_GATT_CEP_RELIABLE_WRITE
Characteristic Extended Properties Bit field values
BT_GATT_CEP_WRITABLE_AUX

BT_GATT_CCC_NOTIFY
  Client Characteristic Configuration Notification.
  Client Characteristic Configuration Values
  If set, changes to Characteristic Value shall be notified.

BT_GATT_CCC_INDICATE
  Client Characteristic Configuration Indication.
  If set, changes to Characteristic Value shall be indicated.

BT_GATT_SCC_BROADCAST
  Server Characteristic Configuration Broadcast.
  Server Characteristic Configuration Values
  If set, the characteristic value shall be broadcast in the advertising data when the server is
  advertising.

Typedefs

typedef ssize_t (*bt_gatt_attr_read_func_t)(struct bt_conn *conn, const struct bt_gatt_attr
  *attr, void *buf, uint16_t len, uint16_t offset)
  Attribute read callback.
  The callback can also be used locally to read the contents of the attribute in which case no
  connection will be set.
  
  **Param conn**
  The connection that is requesting to read

  **Param attr**
  The attribute that's being read

  **Param buf**
  Buffer to place the read result in

  **Param len**
  Length of data to read

  **Param offset**
  Offset to start reading from

  **Return**
  Number of bytes read, or in case of an error `BT_GATT_ERR()` with a specific
  BT_ATT_ERR_* error code.

  typedef ssize_t (*bt_gatt_attr_write_func_t)(struct bt_conn *conn, const struct bt_gatt_attr
  *attr, const void *buf, uint16_t len, uint16_t offset, uint8_t flags)
  Attribute write callback.

  **Param conn**
  The connection that is requesting to write

  **Param attr**
  The attribute that's being written
**Param buf**
Buffer with the data to write

**Param len**
Number of bytes in the buffer

**Param offset**
Offset to start writing from

**Param flags**
Flags (BT_GATT_WRITE_FLAG_*)

**Return**
Number of bytes written, or in case of an error BT_GATT_ERR() with a specific BT_ATT_ERR_* error code.

**Enums**

e num bt_gatt_perm
GATT attribute permission bit field values

*Values:*

enumerator BT_GATT_PERM_NONE = 0
No operations supported, e.g. for notify-only

enumerator BT_GATT_PERM_READ = BIT(0)
Attribute read permission.

enumerator BT_GATT_PERM_WRITE = BIT(1)
Attribute write permission.

enumerator BT_GATT_PERM_READ_ENCRYPT = BIT(2)
Attribute read permission with encryption.

If set, requires encryption for read access.

enumerator BT_GATT_PERM_WRITE_ENCRYPT = BIT(3)
Attribute write permission with encryption.

If set, requires encryption for write access.

enumerator BT_GATT_PERM_READ_AUTHEN = BIT(4)
Attribute read permission with authentication.

If set, requires encryption using authenticated link-key for read access.
enumerator BT_GATT_PERM_WRITE_AUTHEN = \textit{BIT}(5)
Attribute write permission with authentication.

If \textit{set}, requires encryption using authenticated link-key for write access.

enumerator BT_GATT_PERM_PREPARE_WRITE = \textit{BIT}(6)
Attribute prepare write permission.

If \textit{set}, allows prepare writes \textbf{with} use of BT_GATT_WRITE_FLAG_PREPARE passed to write callback.

enumerator BT_GATT_PERM_READ_LESC = \textit{BIT}(7)
Attribute read permission with LE Secure Connection encryption.

If \textit{set}, requires that LE Secure Connections \textbf{is} used for read access.

enumerator BT_GATT_PERM_WRITE_LESC = \textit{BIT}(8)
Attribute write permission with LE Secure Connection encryption.

If \textit{set}, requires that LE Secure Connections \textbf{is} used for write access.

den \{anonymous\}
GATT attribute write flags

\textit{Values:}

enumerator BT_GATT_WRITE_FLAG_PREPARE = \textit{BIT}(0)
Attribute prepare write flag.

If \textit{set}, write callback should only check \textit{if} the device \textit{is} authorized but no data shall be written.

enumerator BT_GATT_WRITE_FLAG_CMD = \textit{BIT}(1)
Attribute write command flag.

If \textit{set}, indicates that write operation \textit{is} a command (Write without response) which doesn't \textbf{generate} any response.

enumerator BT_GATT_WRITE_FLAG_EXECUTE = \textit{BIT}(2)
Attribute write execute flag.
If set, indicates that write operation is a execute, which indicates the end of a long write, and will come after 1 or more
@ref BT_GATT_WRITE_FLAG_PREPARE.

```c
struct bt_gatt_attr
#include <gatt.h> GATT Attribute structure.

Public Members

const struct bt_uuid *uuid
Attribute UUID

bt_gatt_attr_write_func_t write
Attribute write callback

void *user_data
Attribute user data

uint16_t handle
Attribute handle

uint16_t perm
Attribute permissions.
Will be 0 if returned from bt_gatt_discover().
```

```c
struct bt_gatt_service_static
#include <gatt.h> GATT Service structure.

Public Members

const struct bt_gatt_attr *attrs
Service Attributes

size_t attr_count
Service Attribute count
```

```c
struct bt_gatt_service
#include <gatt.h> GATT Service structure.

Public Members

struct bt_gatt_attr *attrs
Service Attributes

size_t attr_count
Service Attribute count
```

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struct bt_gatt_service_val
    #include <gatt.h> Service Attribute Value.

    Public Members

    const struct bt_uuid *uuid
        Service UUID.

    uint16_t end_handle
        Service end handle.

struct bt_gatt_include
    #include <gatt.h> Include Attribute Value.

    Public Members

    const struct bt_uuid *uuid
        Service UUID.

    uint16_t start_handle
        Service start handle.

    uint16_t end_handle
        Service end handle.

struct bt_gatt_cb
    #include <gatt.h> GATT callback structure.

    Public Members

    void (*att_mtu_updated)(struct bt_conn *conn, uint16_t tx, uint16_t rx)
        The maximum ATT MTU on a connection has changed.
        This callback notifies the application that the maximum TX or RX ATT MTU has increased.

        Param conn
            Connection object.

        Param tx
            Updated TX ATT MTU.

        Param rx
            Updated RX ATT MTU.

struct bt_gatt_chrc
    #include <gatt.h> Characteristic Attribute Value.

    Public Members
const struct bt_uuid *uuid
    Characteristic UUID.

uint16_t value_handle
    Characteristic Value handle.

uint8_t properties
    Characteristic properties.

struct bt_gatt_cep
    #include <gatt.h> Characteristic Extended Properties Attribute Value.

Public Members

uint16_t properties
    Characteristic Extended properties

struct bt_gatt_ccc
    #include <gatt.h> Client Characteristic Configuration Attribute Value

Public Members

uint16_t flags
    Client Characteristic Configuration flags

struct bt_gatt_scc
    #include <gatt.h> Server Characteristic Configuration Attribute Value

Public Members

uint16_t flags
    Server Characteristic Configuration flags

struct bt_gatt_cpf
    #include <gatt.h> GATT Characteristic Presentation Format Attribute Value.

Public Members

uint8_t format
    Format of the value of the characteristic

int8_t exponent
    Exponent field to determine how the value of this characteristic is further formatted
uint16_t unit
    Unit of the characteristic

uint8_t name_space
    Name space of the description

uint16_t description
    Description of the characteristic as defined in a higher layer profile

GATT Server

group bt_gatt_server

Defines

BT_GATT_SERVICE_DEFINE(_name,...)
    Statically define and register a service.
    Helper macro to statically define and register a service.

    Parameters
    • _name – Service name.

BT_GATT_SERVICE_INSTANCE_DEFINE(_name,_instances,_instance_num,_attrs_def)
    Statically define service structure array.
    Helper macro to statically define service structure array. Each element of the array is linked
to the service attribute array which is also defined in this scope using _attrs_def macro.

    Parameters
    • _name – Name of service structure array.
    • _instances – Array of instances to pass as user context to the attribute callbacks.
    • _instance_num – Number of elements in instance array.
    • _attrs_def – Macro provided by the user that defines attribute array for the
service. This macro should accept single parameter which is the instance con-
text.

BT_GATT_SERVICE(_attrs)
    Service Structure Declaration Macro.
    Helper macro to declare a service structure.

    Parameters
    • _attrs – Service attributes.

BT_GATT_PRIMARY_SERVICE(_service)
    Primary Service Declaration Macro.
    Helper macro to declare a primary service attribute.

    Parameters
    • _service – Service attribute value.
BT_GATT_SECONDARY_SERVICE(_service)
Secondary Service Declaration Macro.
Helper macro to declare a secondary service attribute.

Note: A secondary service is only intended to be included from a primary service or another secondary service or other higher layer specification.

Parameters
- _service – Service attribute value.

BT_GATT_INCLUDE_SERVICE(_service_incl)
Include Service Declaration Macro.
Helper macro to declare database internal include service attribute.

Parameters
- _service_incl – the first service attribute of service to include

BT_GATT_CHRC_INIT(_uuid, _handle, _props)
BT_GATT_CHARACTERISTIC(_uuid, _props, _perm, _read, _write, _user_data)
Characteristic and Value Declaration Macro.
Helper macro to declare a characteristic attribute along with its attribute value.

Parameters
- _uuid – Characteristic attribute uuid.
- _props – Characteristic attribute properties, a bitmap of BT_GATT_CHRC_* macros.
- _perm – Characteristic Attribute access permissions, a bitmap of bt_gatt_perm values.
- _read – Characteristic Attribute read callback (bt_gatt_attr_read_func_t).
- _write – Characteristic Attribute write callback (bt_gatt_attr_write_func_t).
- _user_data – Characteristic Attribute user data.

BT_GATT_CCC_MAX
BT_GATT_CCC_INITIALIZER(_changed, _write, _match)
Initialize Client Characteristic Configuration Declaration Macro.
Helper macro to initialize a Managed CCC attribute value.

Parameters
- _changed – Configuration changed callback.
- _write – Configuration write callback.
- _match – Configuration match callback.

BT_GATT_CCC_MANAGED(_ccc, _perm)
Managed Client Characteristic Configuration Declaration Macro.
Helper macro to declare a Managed CCC attribute.

Parameters
- _ccc – CCC attribute user data, shall point to a _bt_gatt_ccc.
• _perm – CCC access permissions, a bitmap of `bt_gatt_perm` values.

```c
BT_GATT_CCC(_changed, _perm)
```

Client Characteristic Configuration Declaration Macro.

Helper macro to declare a CCC attribute.

**Parameters**

• _changed – Configuration changed callback.
• _perm – CCC access permissions, a bitmap of `bt_gatt_perm` values.

```c
BT_GATT_CEP(_value)
```

Characteristic Extended Properties Declaration Macro.

Helper macro to declare a CEP attribute.

**Parameters**

• _value – Pointer to a struct `bt_gatt_cep`.

```c
BT_GATT_CUD(_value, _perm)
```

Characteristic User Format Descriptor Declaration Macro.

Helper macro to declare a CUD attribute.

**Parameters**

• _value – User description NULL-terminated C string.
• _perm – Descriptor attribute access permissions, a bitmap of `bt_gatt_perm` values.

```c
BT_GATT_CPF(_value)
```

Characteristic Presentation Format Descriptor Declaration Macro.

Helper macro to declare a CPF attribute.

**Parameters**

• _value – Pointer to a struct `bt_gatt_cpf`.

```c
BT_GATT_DESCRIPTOR(_uuid, _perm, _read, _write, _user_data)
```

Descriptor Declaration Macro.

Helper macro to declare a descriptor attribute.

**Parameters**

• _uuid – Descriptor attribute uuid.
• _perm – Descriptor attribute access permissions, a bitmap of `bt_gatt_perm` values.
• _read – Descriptor attribute read callback (`bt_gatt_attr_read_func_t`).
• _write – Descriptor attribute write callback (`bt_gatt_attr_write_func_t`).
• _user_data – Descriptor attribute user data.

```c
BT_GATT_ATTRIBUTE(_uuid, _perm, _read, _write, _user_data)
```

Attribute Declaration Macro.

Helper macro to declare an attribute.

**Parameters**

• _uuid – Attribute uuid.
• _perm – Attribute access permissions, a bitmap of `bt_gatt_perm` values.
• _read – Attribute read callback (`bt_gatt_attr_read_func_t`).
• _write – Attribute write callback (bt_gatt_attr_write_func_t).
• _user_data – Attribute user data.

Typedefs

typedef uint8_t (*bt_gatt_attr_func_t)(const struct bt_gatt_attr *attr, uint16_t handle, void *user_data)

Attribute iterator callback.

  **Param** attr
  Attribute found.

  **Param** handle
  Attribute handle found.

  **Param** user_data
  Data given.

  **Return**
  BT_GATT_ITER_CONTINUE if should continue to the next attribute.

  **Return**
  BT_GATT_ITER_STOP to stop.

typedef void (*bt_gatt_complete_func_t)(struct bt_conn *conn, void *user_data)

Notification complete result callback.

  **Param** conn
  Connection object.

  **Param** user_data
  Data passed in by the user.

typedef void (*bt_gatt_indicate_func_t)(struct bt_conn *conn, struct bt_gatt_indicate_params *params, uint8_t err)

Indication complete result callback.

  **Param** conn
  Connection object.

  **Param** params
  Indication params object.

  **Param** err
  ATT error code

typedef void (*bt_gatt_indicate_params_destroy_t)(struct bt_gatt_indicate_params *params)

Enums

enum [anonymous]

  **Values:**

  enumerator BT_GATT_ITER_STOP = 0

  enumerator BT_GATT_ITER_CONTINUE
Functions

```c
void bt_gatt_cb_register(struct bt_gatt_cb *cb)
    Register GATT callbacks.
    Register callbacks to monitor the state of GATT.

    Parameters
    • cb – Callback struct.
```

```c
int bt_gatt_service_register(struct bt_gatt_service *svc)
    Register GATT service.
    Register GATT service. Applications can make use of macros such as
    BT_GATT_PRIMARY_SERVICE, BT_GATT_CHARACTERISTIC, BT_GATT_DESCRIPTOR,
    etc.
    When using CONFIG_BT_SETTINGS then all services that should have bond configuration
    loaded, i.e. CCC values, must be registered before calling settings_load.
    When using CONFIG_BT_GATT_CACHING and CONFIG_BT_SETTINGS then all services that should
    be included in the GATT Database Hash calculation should be added before calling settings_load.
    All services registered after settings_load will trigger a new database hash calculation
    and a new hash stored.

    Parameters
    • svc – Service containing the available attributes

    Returns
    0 in case of success or negative value in case of error.
```

```c
int bt_gatt_service_unregister(struct bt_gatt_service *svc)
    Unregister GATT service.

    Parameters
    • svc – Service to be unregistered.

    Returns
    0 in case of success or negative value in case of error.
```

```c
bool bt_gatt_service_is_registered(const struct bt_gatt_service *svc)
    Check if GATT service is registered.

    Parameters
    • svc – Service to be checked.

    Returns
    true if registered or false if not register.
```

```c
void bt_gatt_foreach_attr_type(uint16_t start_handle, uint16_t end_handle, const struct bt_uuid *uuid, const void *attr_data, uint16_t num_matches,
    bt_gatt_attr_func_t func, void *user_data)
    Attribute iterator by type.
    Iterate attributes in the given range matching given UUID and/or data.

    Parameters
    • start_handle – Start handle.
    • end_handle – End handle.
    • uuid – UUID to match, passing NULL skips UUID matching.
    • attr_data – Attribute data to match, passing NULL skips data matching.
```

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• `num_matches` – Number matches, passing 0 makes it unlimited.
• `func` – Callback function.
• `user_data` – Data to pass to the callback.

static inline void bt_gatt_foreach_attr(uint16_t start_handle, uint16_t end_handle, bt_gatt_attr_func_t func, void *user_data)

Attribute iterator.
Iterate attributes in the given range.

Parameters
• `start_handle` – Start handle.
• `end_handle` – End handle.
• `func` – Callback function.
• `user_data` – Data to pass to the callback.

struct bt_gatt_attr *bt_gatt_attr_next(const struct bt_gatt_attr *attr)

Iterate to the next attribute.
Iterate to the next attribute following a given attribute.

Parameters
• `attr` – Current Attribute.

Returns
The next attribute or NULL if it cannot be found.

struct bt_gatt_attr *bt_gatt_find_by_uuid(const struct bt_gatt_attr *attr, uint16_t attr_count, const struct bt_uuid *uuid)

Find Attribute by UUID.
Find the attribute with the matching UUID. To limit the search to a service set the attr to the service attributes and the attr_count to the service attribute count.

Parameters
• `attr` – Pointer to an attribute that serves as the starting point for the search of a match for the UUID. Passing NULL will search the entire range.
• `attr_count` – The number of attributes from the starting point to search for a match for the UUID. Set to 0 to search until the end.
• `uuid` – UUID to match.

uint16_t bt_gatt_attr_get_handle(const struct bt_gatt_attr *attr)

Get Attribute handle.

Parameters
• `attr` – Attribute object.

Returns
Handle of the corresponding attribute or zero if the attribute could not be found.

uint16_t bt_gatt_attr_value_handle(const struct bt_gatt_attr *attr)

Get the handle of the characteristic value descriptor.

Note: The `user_data` of the attribute must of type `bt_gatt_chrc`.

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• attr – A Characteristic Attribute.

**Returns**

the handle of the corresponding Characteristic Value. The value will be zero (the invalid handle) if attr was not a characteristic attribute.

```c
ssize_t bt_gatt_attr_read(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t buf_len, uint16_t offset, const void *value, uint16_t value_len)
```

Generic Read Attribute value helper.

Read attribute value from local database storing the result into buffer.

**Parameters**

- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value.
- buf_len – Buffer length.
- offset – Start offset.
- value – Attribute value.
- value_len – Length of the attribute value.

**Returns**

number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_service(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Service Attribute helper.

Read service attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a `bt_uuid`.

**Parameters**

- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.

**Returns**

number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_included(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Include Attribute helper.

Read include service attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a `bt_gatt_include`.
Parameters

- `conn` – Connection object.
- `attr` – Attribute to read.
- `buf` – Buffer to store the value read.
- `len` – Buffer length.
- `offset` – Start offset.

Returns

the number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_chrc(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Characteristic Attribute helper.

Read characteristic attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a `bt_gatt_chrc`.

---

Parameters

- `conn` – Connection object.
- `attr` – Attribute to read.
- `buf` – Buffer to store the value read.
- `len` – Buffer length.
- `offset` – Start offset.

Returns

the number of bytes read in case of success or negative values in case of error.

```c
ssize_t bt_gatt_attr_read_ccc(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)
```

Read Client Characteristic Configuration Attribute helper.

Read CCC attribute value from local database storing the result into buffer after encoding it.

**Note:** Only use this with attributes which user_data is a `_bt_gatt_ccc`.

---

Parameters

- `conn` – Connection object.
- `attr` – Attribute to read.
- `buf` – Buffer to store the value read.
- `len` – Buffer length.
- `offset` – Start offset.

Returns

the number of bytes read in case of success or negative values in case of error.
ssize_t bt_gatt_attr_write_ccc(struct bt_conn *conn, const struct bt_gatt_attr *attr, const void *buf, uint16_t len, uint16_t offset, uint8_t flags)

Write Client Characteristic Configuration Attribute helper.
Write value in the buffer into CCC attribute.

Note: Only use this with attributes which user_data is a _bt_gatt_ccc.

Parameters
- conn – Connection object.
- attr – Attribute to read.
- buf – Buffer to store the value read.
- len – Buffer length.
- offset – Start offset.
- flags – Write flags.

Returns
number of bytes written in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_cep(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Characteristic Extended Properties Attribute helper.
Read CEP attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a bt_gatt_cep.

Parameters
- conn – Connection object
- attr – Attribute to read
- buf – Buffer to store the value read
- len – Buffer length
- offset – Start offset

Returns
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_cud(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Characteristic User Description Descriptor Attribute helper.
Read CUD attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a NULL-terminated C string.

Parameters
- conn – Connection object
- attr – Attribute to read
buf – Buffer to store the value read

len – Buffer length

offset – Start offset

Returns
number of bytes read in case of success or negative values in case of error.

ssize_t bt_gatt_attr_read_cpf(struct bt_conn *conn, const struct bt_gatt_attr *attr, void *buf, uint16_t len, uint16_t offset)

Read Characteristic Presentation format Descriptor Attribute helper.
Read CPF attribute value from local database storing the result into buffer after encoding it.

Note: Only use this with attributes which user_data is a bt_gatt_pf.

Parameters
- conn – Connection object
- attr – Attribute to read
- buf – Buffer to store the value read
- len – Buffer length
- offset – Start offset

Returns
number of bytes read in case of success or negative values in case of error.

int bt_gatt_notify_cb(struct bt_conn *conn, struct bt_gatt_notify_params *params)

Notify attribute value change.
This function works in the same way as bt_gatt_notify. With the addition that after sending the notification the callback function will be called.
The callback is run from System Workqueue context. When called from the System Workqueue context this API will not wait for resources for the callback but instead return an error. The number of pending callbacks can be increased with the CONFIG_BT_CONN_TX_MAX option.
Alternatively it is possible to notify by UUID by setting it on the parameters, when using this method the attribute if provided is used as the start range when looking up for possible matches.

Parameters
- conn – Connection object.
- params – Notification parameters.

Returns
0 in case of success or negative value in case of error.

int bt_gatt_notify_multiple(struct bt_conn *conn, uint16_t num_params, struct bt_gatt_notify_params params[])

Send multiple notifications in a single PDU.
The GATT Server will send a single ATT_MULTIPLE_HANDLE_VALUE_NTF PDU containing all the notifications passed to this API.

All params must have the same func and user_data (due to implementation limitation). But func(user_data) will be invoked for each parameter.
As this API may block to wait for Bluetooth Host resources, it is not recommended to call it from a cooperative thread or a Bluetooth callback.

The peer's GATT Client must write to this device's Client Supported Features attribute and set the bit for Multiple Handle Value Notifications before this API can be used.

Only use this API to force the use of the ATT_MULTIPLE_HANDLE_VALUE_NTF PDU. For standard applications, bt_gatt_notify_cb is preferred, as it will use this PDU if supported and automatically fallback to ATT_HANDLE_VALUE_NTF when not supported by the peer.

This API has an additional limitation: it only accepts valid attribute references and not UUIDs like bt_gatt_notify and bt_gatt_notify_cb.

**Parameters**

- **conn** – Target client. Notifying all connected clients by passing NULL is not yet supported, please use bt_gatt_notify instead.
- **num_params** – Element count of `params` array. Has to be greater than 1.
- **params** – Array of notification parameters. It is okay to free this after calling this function.

**Return values**

- **0** – Success. The PDU is queued for sending.
- **-EINVAL**
  - One of the attribute handles is invalid.
  - Only one parameter was passed. This API expects 2 or more.
  - Not all `func` were equal or not all `user_data` were equal.
  - One of the characteristics is not notifiable.
  - An UUID was passed in one of the parameters.
- **-ERANGE**
  - The notifications cannot all fit in a single ATT_MULTIPLE.Handle.VALUE.NTF.
  - They exceed the MTU of all open ATT bearers.
- **-EPERM** – The connection has a lower security level than required by one of the attributes.
- **-EOPNOTSUPP** – The peer hasn't yet communicated that it supports this PDU type.

```c
static inline int bt_gatt_notify(struct bt_conn *conn, const struct bt_gatt_attr *attr, const void *data, uint16_t len)
```

**Notify attribute value change.**

Send notification of attribute value change, if connection is NULL notify all peer that have notification enabled via CCC otherwise do a direct notification only the given connection.

The attribute object on the parameters can be the so called Characteristic Declaration, which is usually declared with `BT_GATT_CHARACTERISTIC` followed by `BT_GATT_CCC`, or the Characteristic Value Declaration which is automatically created after the Characteristic Declaration when using `BT_GATT_CHARACTERISTIC`.

**Parameters**

- **conn** – Connection object.
- **attr** – Characteristic or Characteristic Value attribute.
- **data** – Pointer to Attribute data.
• `len` – Attribute value length.

**Returns**

0 in case of success or negative value in case of error.

```c
static inline int bt_gatt_notify_uuid(struct bt_conn *conn, const struct bt_uuid *uuid, const struct bt_gatt_attr *attr, const void *data, uint16_t len)
```

Notify attribute value change by UUID.

Send notification of attribute value change, if connection is NULL notify all peer that have notification enabled via CCC otherwise do a direct notification only on the given connection.

The attribute object is the starting point for the search of the UUID.

**Parameters**

• `conn` – Connection object.
• `uuid` – The UUID. If the server contains multiple services with the same UUID, then the first occurrence, starting from the attr given, is used.
• `attr` – Pointer to an attribute that serves as the starting point for the search of a match for the UUID.
• `data` – Pointer to Attribute data.
• `len` – Attribute value length.

**Returns**

0 in case of success or negative value in case of error.

```c
int bt_gatt_indicate(struct bt_conn *conn, struct bt_gatt_indicate_params *params)
```

Indicate attribute value change.

Send an indication of attribute value change. if connection is NULL indicate all peer that have notification enabled via CCC otherwise do a direct indication only the given connection.

The attribute object on the parameters can be the so called Characteristic Declaration, which is usually declared with `BT_GATT_CHARACTERISTIC` followed by `BT_GATT_CCC`, or the Characteristic Value Declaration which is automatically created after the Characteristic Declaration when using `BT_GATT_CHARACTERISTIC`.

Alternatively it is possible to indicate by UUID by setting it on the parameters, when using this method the attribute if provided is used as the start range when looking up for possible matches.

**Note:** This procedure is asynchronous therefore the parameters need to remains valid while it is active. The procedure is active until the destroy callback is run.

**Parameters**

• `conn` – Connection object.
• `params` – Indicate parameters.

**Returns**

0 in case of success or negative value in case of error.

```c
bool bt_gatt_is_subscribed(struct bt_conn *conn, const struct bt_gatt_attr *attr, uint16_t ccc_type)
```

Check if connection have subscribed to attribute.

Check if connection has subscribed to attribute value change.

The attribute object can be the so called Characteristic Declaration, which is usually declared with `BT_GATT_CHARACTERISTIC` followed by `BT_GATT_CCC`, or the Characteristic Value
Declaration which is automatically created after the Characteristic Declaration when using BT_GATT_CHARACTERISTIC, or the Client Characteristic Configuration Descriptor (CCCD) which is created by BT_GATT_CCC.

**Parameters**

- `conn` – Connection object.
- `attr` – Attribute object.
- `ccc_type` – The subscription type, `BT_GATT_CCC_NOTIFY` and/or `BT_GATT_CCC_INDICATE`.

**Returns**

true if the attribute object has been subscribed.

```c
uint16_t bt_gatt_get_mtu(struct bt_conn *conn)
```

Get ATT MTU for a connection.

Get negotiated ATT connection MTU, note that this does not equal the largest amount of attribute data that can be transferred within a single packet.

**Parameters**

- `conn` – Connection object.

**Returns**

MTU in bytes

```c
struct bt_gatt_ccc_cfg
```

#Include `<gatt.h>` GATT CCC configuration entry.

**Public Members**

```c
uint8_t id
```

Local identity, BT_ID_DEFAULT in most cases.

```c
bt_addr_le_t peer
```

Remote peer address.

```c
uint16_t value
```

Configuration value.

```c
struct bt_gatt_notify_params
```

#Include `<gatt.h>`

**Public Members**

```c
const struct bt_uuid *uuid
```

Notification Attribute UUID type.

Optional, use to search for an attribute with matching UUID when the attribute object pointer is not known.
const struct bt_gatt_attr *attr
    Notification Attribute object.
    Optional if uuid is provided, in this case it will be used as start range to search for the attribute with the given UUID.

const void *data
    Notification Value data

uint16_t len
    Notification Value length

bt_gatt_complete_func_t func
    Notification Value callback

void *user_data
    Notification Value callback user data

struct bt_gatt_indicate_params
    #include <gatt.h> GATT Indicate Value parameters.

**Public Members**

const struct bt_uuid *uuid
    Indicate Attribute UUID type.
    Optional, use to search for an attribute with matching UUID when the attribute object pointer is not known.

const struct bt_gatt_attr *attr
    Indicate Attribute object.
    Optional if uuid is provided, in this case it will be used as start range to search for the attribute with the given UUID.

bt_gatt_indicate_func_t func
    Indicate Value callback

bt_gatt_indicate_params_destroy_t destroy
    Indicate operation complete callback

const void *data
    Indicate Value data

uint16_t len
    Indicate Value length

**GATT Client**

group bt_gatt_client
**Typedefs**

```c
typedef uint8_t (*bt_gatt_discover_func_t)(struct bt_conn *conn, const struct bt_gatt_attr *attr, struct bt_gatt_discover_params *params)
```

Discover attribute callback function.

If discovery procedure has completed this callback will be called with `attr` set to NULL. This will not happen if procedure was stopped by returning `BT_GATT_ITER_STOP`.

The attribute object as well as its UUID and value objects are temporary and must be copied to in order to cache its information. Only the following fields of the attribute contains valid information:

- `uuid` UUID representing the type of attribute.
- `handle` Handle in the remote database.
- `user_data` The value of the attribute, if the discovery type maps to an ATT operation that provides this information. NULL otherwise. See below.

The effective type of `attr->user_data` is determined by `params`. Note that the fields `params->type` and `params->uuid` are left unchanged by the discovery procedure.

<table>
<thead>
<tr>
<th><code>params-&gt;type</code></th>
<th><code>params-&gt;uuid</code></th>
<th>Type of <code>attr-&gt;user_data</code></th>
</tr>
</thead>
<tbody>
<tr>
<td><code>BT_GATT_DISCOVER_PRIMARY</code></td>
<td>any</td>
<td><code>bt_gatt_service_val</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_SECONDARY</code></td>
<td>any</td>
<td><code>bt_gatt_service_val</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_INCLUDE</code></td>
<td>any</td>
<td><code>bt_gatt_include</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_CHARACTERISTIC</code></td>
<td>any</td>
<td><code>bt_gatt_chrc</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_STD_CHAR_DESC</code></td>
<td><code>BT_UUID_GATT_CEP</code></td>
<td><code>bt_gatt_cep</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_STD_CHAR_DESC</code></td>
<td><code>BT_UUID_GATT_CCC</code></td>
<td><code>bt_gatt_ccc</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_STD_CHAR_DESC</code></td>
<td><code>BT_UUID_GATT_SCC</code></td>
<td><code>bt_gatt_scc</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_STD_CHAR_DESC</code></td>
<td><code>BT_UUID_GATT_CPF</code></td>
<td><code>bt_gatt_cpf</code></td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_DESCRIPTOR</code></td>
<td>any</td>
<td>NULL</td>
</tr>
<tr>
<td><code>BT_GATT_DISCOVER_ATTRIBUTE</code></td>
<td>any</td>
<td>NULL</td>
</tr>
</tbody>
</table>

Also consider if using read-by-type instead of discovery is more convenient. See `bt_gatt_read` with `bt_gatt_read_params::handle_count` set to 0.

**Param conn**

Connection object.

**Param attr**

Attribute found, or NULL if not found.

**Param params**

Discovery parameters given.

**Return**

- `BT_GATT_ITER_CONTINUE` to continue discovery procedure.
- `BT_GATT_ITER_STOP` to stop discovery procedure.

```c
typedef uint8_t (*bt_gatt_read_func_t)(struct bt_conn *conn, uint8_t err, struct bt_gatt_read_params *params, const void *data, uint16_t length)
```

Read callback function.
**Param conn**
Connection object.

**Param err**
ATT error code.

**Param params**
Read parameters used.

**Param data**
Attribute value data. NULL means read has completed.

**Param length**
Attribute value length.

**Return**
BT_GATT_ITER_CONTINUE if should continue to the next attribute.

**Return**
BT_GATT_ITER_STOP to stop.

```c
typedef void (*bt_gatt_write_func_t)(struct bt_conn *conn, uint8_t err, struct bt_gatt_write_params *params)
```
Write callback function.

**Param conn**
Connection object.

**Param err**
ATT error code.

**Param params**
Write parameters used.

```c
typedef uint8_t (*bt_gatt_notify_func_t)(struct bt_conn *conn, struct bt_gatt_subscribe_params *params, const void *data, uint16_t length)
```
Notification callback function.

In the case of an empty notification, the data pointer will be non-NULL while the length will be 0, which is due to the special case where a data NULL pointer means unsubscribed.

**Param conn**
Connection object. May be NULL, indicating that the peer is being unpaired

**Param params**
Subscription parameters.

**Param data**
Attribute value data. If NULL then subscription was removed.

**Param length**
Attribute value length.

**Return**
BT_GATT_ITER_CONTINUE to continue receiving value notifications.
BT_GATT_ITER_STOP to unsubscribe from value notifications.

```c
typedef void (*bt_gatt_subscribe_func_t)(struct bt_conn *conn, uint8_t err, struct bt_gatt_subscribe_params *params)
```
Subscription callback function.

**Param conn**
Connection object.
**Param err**
ATT error code.

**Param params**
Subscription parameters used.

**Enums**

```plaintext
enum [anonymous]
  GATT Discover types

Values:

enumerator BT_GATT_DISCOVER_PRIMARY
  Discover Primary Services.

enumerator BT_GATT_DISCOVER_SECONDARY
  Discover Secondary Services.

enumerator BT_GATT_DISCOVER_INCLUDE
  Discover Included Services.

enumerator BT_GATT_DISCOVER_CHARACTERISTIC
  Discover Characteristic Values.
```

Discover Characteristic Value and its properties.

```plaintext
enumerator BT_GATT_DISCOVER_DESCRIPTOR
  Discover Descriptors.
```

Discover Attributes which are not services or characteristics.

@note The use of this type of discover is not recommended for discovering in ranges across multiple services/characteristics as it may incur in extra round trips.

```plaintext
enumerator BT_GATT_DISCOVER_ATTRIBUTE
  Discover Attributes.
```

Discover Attributes of any type.

@note The use of this type of discover is not recommended for discovering in ranges across multiple services/characteristics as it may incur in more round trips.

```plaintext
enumerator BT_GATT_DISCOVER_STD_CHAR_DESC
  Discover standard characteristic descriptor values.
```
Discover standard characteristic descriptor values and their properties.
Supported descriptors:
- Characteristic Extended Properties
- Client Characteristic Configuration
- Server Characteristic Configuration
- Characteristic Presentation Format

```c
enum [anonymous]
Subscription flags

Values:

enumerator BT_GATT_SUBSCRIBE_FLAG_VOLATILE
Persistence flag.

If set, indicates that the subscription is not saved on the GATT server side. Therefore, upon disconnection, the subscription will be automatically removed from the client's subscriptions list and when the client reconnects, it will have to issue a new subscription.

enumerator BT_GATT_SUBSCRIBE_FLAG_NO_RESUB
No resubscribe flag.

By default when BT_GATT_SUBSCRIBE_FLAG_VOLATILE is unset, the subscription will be automatically renewed when the client reconnects, as a workaround for GATT servers that do not persist subscriptions.

This flag will disable the automatic resubscription. It is useful if the application layer knows that the GATT server remembers subscriptions from previous connections and wants to avoid renewing the subscriptions.

enumerator BT_GATT_SUBSCRIBE_FLAG_WRITE_PENDING
Write pending flag.

If set, indicates write operation is pending waiting remote end to respond.

enumerator BT_GATT_SUBSCRIBE_NUM_FLAGS
```

**Functions**

```c
int bt_gatt_exchange_mtu(struct bt_conn *conn, struct bt_gatt_exchange_params *params)
Exchange MTU.
```
This client procedure can be used to set the MTU to the maximum possible size the buffers can hold.

The Response comes in callback `params->func`. The callback is run from the context specified by `config BT_RECV_CONTEXT`. `params` must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Note:** Shall only be used once per connection.

### Parameters
- `conn` – Connection object.
- `params` – Exchange MTU parameters.

### Return values
- **0** – Successfully queued request. Will call `params->func` on resolution.
- **-ENOMEM** – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_L2CAP_TX_BUF_COUNT`.
- **-EALREADY** – The MTU exchange procedure has been already performed.

```c
int bt_gatt_discover(struct bt_conn *conn, struct bt_gatt_discover_params *params)
```

GATT Discover function.

This procedure is used by a client to discover attributes on a server.

Primary Service Discovery: Procedure allows to discover primary services either by Discover All Primary Services or Discover Primary Services by Service UUID. Include Service Discovery: Procedure allows to discover all Include Services within specified range. Characteristic Discovery: Procedure allows to discover all characteristics within specified handle range as well as discover characteristics with specified UUID. Descriptors Discovery: Procedure allows to discover all characteristic descriptors within specified range.

For each attribute found the callback is called which can then decide whether to continue discovering or stop.

The Response comes in callback `params->func`. The callback is run from the BT RX thread. `params` must remain valid until start of callback where `iter.attr` is `NULL` or callback will return `BT_GATT_ITER_STOP`.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

### Parameters
- `conn` – Connection object.
- `params` – Discover parameters.

### Return values
- **0** – Successfully queued request. Will call `params->func` on resolution.
- **-ENOMEM** – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_L2CAP_TX_BUF_COUNT`.
int bt_gatt_read(struct bt_conn *conn, struct bt_gatt_read_params *params)
Read Attribute Value by handle.

This procedure read the attribute value and return it to the callback.

When reading attributes by UUID the callback can be called multiple times depending on how many instances of given the UUID exists with the start_handle being updated for each instance.

If an instance does contain a long value which cannot be read entirely the caller will need to read the remaining data separately using the handle and offset.

The Response comes in callback params->func. The callback is run from the context specified by 'config BT_RECV_CONTEXT'. params must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

Parameters
• conn – Connection object.
• params – Read parameters.

Return values
• 0 – Successfully queued request. Will call params->func on resolution.
• -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by CONFIG_BT_L2CAP_TX_BUF_COUNT.

int bt_gatt_write(struct bt_conn *conn, struct bt_gatt_write_params *params)
Write Attribute Value by handle.

The Response comes in callback params->func. The callback is run from the context specified by 'config BT_RECV_CONTEXT'. params must remain valid until start of callback.

This function will block while the ATT request queue is full, except when called from Bluetooth event context. When called from Bluetooth context, this function will instead return -ENOMEM if it would block to avoid a deadlock.

Parameters
• conn – Connection object.
• params – Write parameters.

Return values
• 0 – Successfully queued request. Will call params->func on resolution.
• -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside Bluetooth event context to get blocking behavior. Queue size is controlled by CONFIG_BT_L2CAP_TX_BUF_COUNT.

int bt_gatt_write_without_response_cb(struct bt_conn *conn, uint16_t handle, const void *data, uint16_t length, bool sign, bt_gatt_complete_func_t func, void *user_data)
Write Attribute Value by handle without response with callback.

This function works in the same way as bt_gatt_write_without_response. With the addition that after sending the write the callback function will be called.

The callback is run from System Workqueue context. When called from the System Workqueue context this API will not wait for resources for the callback but instead return an error. The number of pending callbacks can be increased with the CONFIG_BT_CONN_TX_MAX option.
This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

**Note:** By using a callback it also disable the internal flow control which would prevent sending multiple commands without waiting for their transmissions to complete, so if that is required the caller shall not submit more data until the callback is called.

### Parameters
- **conn** – Connection object.
- **handle** – Attribute handle.
- **data** – Data to be written.
- **length** – Data length.
- **sign** – Whether to sign data
- **func** – Transmission complete callback.
- **user_data** – User data to be passed back to callback.

### Return values
- **0** – Successfully queued request.
- **-ENOMEM** – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_L2CAP_TX_BUF_COUNT`.

```c
static inline int bt_gatt_write_without_response(struct bt_conn *conn, uint16_t handle, const void *data, uint16_t length, bool sign)
```

Write Attribute Value by handle without response.

This procedure write the attribute value without requiring an acknowledgment that the write was successfully performed

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

### Parameters
- **conn** – Connection object.
- **handle** – Attribute handle.
- **data** – Data to be written.
- **length** – Data length.
- **sign** – Whether to sign data

### Return values
- **0** – Successfully queued request.
- **-ENOMEM** – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by `CONFIG_BT_L2CAP_TX_BUF_COUNT`.

```c
```
int bt_gatt_subscribe(struct bt_conn *conn, struct bt_gatt_subscribe_params *params)
  Subscribe Attribute Value Notification.

  This procedure subscribe to value notification using the Client Characteristic Configuration handle. If notification received subscribe value callback is called to return notified value. One may then decide whether to unsubscribe directly from this callback. Notification callback with NULL data will not be called if subscription was removed by this method.

  The Response comes in callback params->subscribe. The callback is run from the context specified by 'config BT_RECV_CONTEXT'. params must remain valid until start of callback. The Notification callback params->notify is also called from the BT RX thread.

  This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

  Note: Notifications are asynchronous therefore the parameters need to remain valid while subscribed.

Parameters
  • conn – Connection object.
  • params – Subscribe parameters.

Return values
  • 0 – Successfully queued request. Will call params->write on resolution.
  • -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by CONFIG_BT_L2CAP_TX_BUF_COUNT.

int bt_gatt_resubscribe(uint8_t id, const bt_addr_le_t *peer, struct bt_gatt_subscribe_params *params)
  Resubscribe Attribute Value Notification subscription.

  Resubscribe to Attribute Value Notification when already subscribed from a previous connection. The GATT server will remember subscription from previous connections when bonded, so resubscribing can be done without performing a new subscribe procedure after a power cycle.

  Note: Notifications are asynchronous therefore the parameters need to remain valid while subscribed.

Parameters
  • id – Local identity (in most cases BT_ID_DEFAULT).
  • peer – Remote address.
  • params – Subscribe parameters.

Returns
  0 in case of success or negative value in case of error.
int bt_gatt_unsubscribe(struct bt_conn *conn, struct bt_gatt_subscribe_params *params)

Unsubscribe Attribute Value Notification.

This procedure unsubscribe to value notification using the Client Characteristic Configuration handle. Notification callback with NULL data will be called if subscription was removed by this call, until then the parameters cannot be reused.

The Response comes in callback params->func. The callback is run from the BT RX thread.

This function will block while the ATT request queue is full, except when called from the BT RX thread, as this would cause a deadlock.

Parameters

- conn – Connection object.
- params – Subscribe parameters.

Return values

- 0 – Successfully queued request. Will call params->write on resolution.
- -ENOMEM – ATT request queue is full and blocking would cause deadlock. Allow a pending request to resolve before retrying, or call this function outside the BT RX thread to get blocking behavior. Queue size is controlled by CONFIG_BT_L2CAP_TX_BUF_COUNT.

void bt_gatt_cancel(struct bt_conn *conn, void *params)

Try to cancel the first pending request identified by params.

This function does not release params for reuse. The usual callbacks for the request still apply. A successful cancel simulates a BT_ATT_ERR_UNLIKELY response from the server.

This function can cancel the following request functions:

- bt_gatt_exchange_mtu
- bt_gatt_discover
- bt_gatt_read
- bt_gatt_write
- bt_gatt_subscribe
- bt_gatt_unsubscribe

Parameters

- conn – The connection the request was issued on.
- params – The address params used in the request function call.

struct bt_gatt_exchange_params

#include <gatt.h> GATT Exchange MTU parameters.

Public Members

void (*func)(struct bt_conn *conn, uint8_t err, struct bt_gatt_exchange_params *params)

Response callback

struct bt_gatt_discover_params

#include <gatt.h> GATT Discover Attributes parameters.
Public Members

const struct bt_uuid *uuid
    Discover UUID type

bt_gatt_discover_func_t func
    Discover attribute callback

uint16_t attr_handle
    Include service attribute declaration handle

uint16_t start_handle
    Included service start handle
    Discover start handle

uint16_t end_handle
    Included service end handle
    Discover end handle

uint8_t type
    Discover type

struct bt_gatt_read_params
    #include <gatt.h> GATT Read parameters.

Public Members

bt_gatt_read_func_t func
    Read attribute callback.

size_t handle_count
    If equals to 1 single.handle and single.offset are used. If greater than 1 multiple.handles are used. If equals to 0 by_uuid is used for Read Using Characteristic UUID.

uint16_t handle
    Attribute handle.

uint16_t offset
    Attribute data offset.

uint16_t *handles
    Attribute handles to read with Read Multiple Characteristic Values.

bool variable
    If true use Read Multiple Variable Length Characteristic Values procedure. The values of the set of attributes may be of variable or unknown length. If false use Read Multiple Characteristic Values procedure. The values of the set of attributes must be of a known fixed length, with the exception of the last value that can have a variable length.


```c
uint16_t start_handle
    First requested handle number.

uint16_t end_handle
    Last requested handle number.

const struct bt_uuid *uuid
    2 or 16 octet UUID.
```

```c
struct bt_gatt_write_params
    #include <gatt.h> GATT Write parameters.

Public Members

bt_gatt_write_func_t func
    Response callback

uint16_t handle
    Attribute handle

uint16_t offset
    Attribute data offset

const void *data
    Data to be written

uint16_t length
    Length of the data
```

```c
struct bt_gatt_subscribe_params
    #include <gatt.h> GATT Subscribe parameters.

Public Members

bt_gatt_notify_func_t notify
    Notification value callback

bt_gatt_subscribe_func_t subscribe
    Subscribe CCC write request response callback If given, called with the subscription parameters given when subscribing

bt_gatt_write_func_t write
    Deprecated:

uint16_t value_handle
    Subscribe value handle
```
uint16_t ccc_handle
   Subscribe CCC handle

uint16_t value
   Subscribe value

bt_security_t min_security
   Minimum required security for received notification. Notifications and indications received over a connection with a lower security level are silently discarded.

atomic_t flags[ATOMIC_BITMAP_SIZE(BT_GATT_SUBSCRIBE_NUM_FLAGS)]
   Subscription flags

**HCI Drivers**

**API Reference**

**group bt_hci_driver**
   HCI drivers.

**Defines**

IS_BT_QUIRK_NO_AUTO_DLE(bt_dev)

BT_HCI_EVT_FLAG_RECV_PRIO

BT_HCI_EVT_FLAG_RECV

**Enums**

**enum [anonymous]**
   **Values:**

   enumerator BT_QUIRK_NO_RESET = BIT(0)

   enumerator BT_QUIRK_NO_AUTO_DLE = BIT(1)

**enum bt_hci_driver_bus**
   Possible values for the 'bus' member of the **bt_hci_driver** struct
   **Values:**

   enumerator BT_HCI_DRIVER_BUS_VIRTUAL = 0

   enumerator BT_HCI_DRIVER_BUS_USB = 1

   enumerator BT_HCI_DRIVER_BUS_PCCARD = 2
enumerator BT_HCI_DRIVER_BUS_UART = 3
enumerator BT_HCI_DRIVER_BUS_RS232 = 4
enumerator BT_HCI_DRIVER_BUS_PCI = 5
enumerator BT_HCI_DRIVER_BUS_SDIO = 6
enumerator BT_HCI_DRIVER_BUS_SPI = 7
enumerator BT_HCI_DRIVER_BUS_I2C = 8
enumerator BT_HCI_DRIVER_BUS_IPM = 9

Functions

static inline uint8_t bt_hci_evt_get_flags(uint8_t evt)
Get HCI event flags.
Helper for the HCI driver to get HCI event flags that describes rules that must be followed.
When CONFIG_BT_RECV_BLOCKING is enabled the flags BT_HCI_EVT_FLAG_RECV and BT_HCI_EVT_FLAG_RECV_PRIO indicates if the event should be given to bt_recv or bt_recv_prio.

Parameters

- evt – HCI event code.

Returns

HCI event flags for the specified event.

int bt_recv(struct net_buf *buf)
Receive data from the controller/HCI driver.
This is the main function through which the HCI driver provides the host with data from the controller. The buffer needs to have its type set with the help of bt_buf_set_type() before calling this API.
When CONFIG_BT_RECV_BLOCKING is defined then this API should not be used for so-called high priority HCI events, which should instead be delivered to the host stack through bt_recv_prio().

Parameters

- buf – Network buffer containing data from the controller.

Returns

0 on success or negative error number on failure.

int bt_recv_prio(struct net_buf *buf)
Receive high priority data from the controller/HCI driver.
This is the same as bt_recv(), except that it should be used for so-called high priority HCI events. There's a separate bt_hci_evt_get_flags() helper that can be used to identify which events have the BT_HCI_EVT_FLAG_RECV_PRIO flag set.
As with bt_recv(), the buffer needs to have its type set with the help of bt_buf_set_type() before calling this API. The only exception is so called high priority HCI events which should be delivered to the host stack through bt_recv_prio() instead.
Parameters

- `buf` – Network buffer containing data from the controller.

Returns

0 on success or negative error number on failure.

```c
uint8_t bt_read_static_addr(struct bt_hci_vs_static_addr addrs[], uint8_t size)
```

Read static addresses from the controller.

Parameters

- `addrs` – Random static address and Identity Root (IR) array.
- `size` – Size of array.

Returns

Number of addresses read.

```c
int bt_hci_driver_register(const struct bt_hci_driver *drv)
```

Register a new HCI driver to the Bluetooth stack.

This needs to be called before any application code runs. The `bt_enable()` API will fail if there is no driver registered.

Parameters

- `drv` – A `bt_hci_driver` struct representing the driver.

Returns

0 on success or negative error number on failure.

```c
int bt_hci_transport_setup(const struct device *dev)
```

Setup the HCI transport, which usually means to reset the Bluetooth IC.

Note: A weak version of this function is included in the H4 driver, so defining it is optional per board.

Parameters

- `dev` – The device structure for the bus connecting to the IC

Returns

0 on success, negative error value on failure

```c
struct net_buf *bt_hci_evt_create(uint8_t evt, uint8_t len)
```

Allocate an HCI event buffer.

This function allocates a new buffer for an HCI event. It is given the OpCode and the total length of the parameters. Upon successful return the buffer is ready to have the parameters encoded into it.

Parameters

- `len` – Length of event parameters.

Returns

Newly allocated buffer.

```c
struct net_buf *bt_hci_cmd_complete_create(uint16_t op, uint8_t plen)
```

Allocate an HCI Command Complete event buffer.

This function allocates a new buffer for HCI Command Complete event. It is given the OpCode (encoded e.g. using the BT_OP macro) and the total length of the parameters. Upon successful return the buffer is ready to have the parameters encoded into it.
Parameters

- plen – Length of command parameters.

Returns

Newly allocated buffer.

```c
struct net_buf *bt_hci_cmd_status_create(uint16_t op, uint8_t status)
```

Allocate an HCI Command Status event buffer.

This function allocates a new buffer for HCI Command Status event. It is given the OpCode (encoded e.g. using the BT_OP macro) and the status code. Upon successful return the buffer is ready to have the parameters encoded into it.

Parameters

- status – Status code.

Returns

Newly allocated buffer.

```c
struct bt_hci_driver
```

#include <hci_driver.h>

Abstraction which represents the HCI transport to the controller.

This struct is used to represent the HCI transport to the Bluetooth controller.

Public Members

```c
const char *name
```

Name of the driver

```c
enum bt_hci_driver_bus bus
```

Bus of the transport (BT_HCI_DRIVER_BUS_*)

```c
uint32_t quirks
```

Specific controller quirks. These are set by the HCI driver and acted upon by the host. They can either be statically set at buildtime, or set at runtime before the HCI driver's `open()` callback returns.

```c
int (*open)(void)
```

Open the HCI transport.

Opens the HCI transport for operation. This function must not return until the transport is ready for operation, meaning it is safe to start calling the `send()` handler.

If the driver uses its own RX thread, i.e. `CONFIG_BT_RECV_BLOCKING` is set, then this function is expected to start that thread.

Return

0 on success or negative error number on failure.

```c
int (*close)(void)
```

Close the HCI transport.

Closes the HCI transport. This function must not return until the transport is closed.

If the driver uses its own RX thread, i.e. `CONFIG_BT_RECV_BLOCKING` is set, then this function is expected to abort that thread.
Return
0 on success or negative error number on failure.

int (*send)(struct net_buf *buf)
Send HCI buffer to controller.
Send an HCI command or ACL data to the controller. The exact type of the data can be checked with the help of bt_buf_get_type().

Note: This function must only be called from a cooperative thread.

Param buf
Buffer containing data to be sent to the controller.
Return
0 on success or negative error number on failure.

int (*setup)(void)
HCI vendor-specific setup.
Executes vendor-specific commands sequence to initialize BT Controller before BT Host executes Reset sequence.

Note: CONFIG_BT_HCI_SETUP must be selected for this field to be available.

Return
0 on success or negative error number on failure.

HCI RAW channel

Overview
HCI RAW channel API is intended to expose HCI interface to the remote entity. The local Bluetooth controller gets owned by the remote entity and host Bluetooth stack is not used. RAW API provides direct access to packets which are sent and received by the Bluetooth HCI driver.

API Reference

group hci_raw
HCI RAW channel.

Defines

BT_HCI_ERR_EXT_HANDLED
BT_HCI_RAW_CMD_EXT(_op, _min_len, _func)
Helper macro to define a command extension

Parameters
• _op – Opcode of the command.
• _min_len – Minimal length of the command.
• _func – Handler function to be called.
Enums

enum [anonymous]

Values:

enumerator BT_HCI_RAW_MODE_PASSTHROUGH = 0x00

Passthrough mode

> While in this mode the buffers are passed as is between the stack and the driver.

enumerator BT_HCI_RAW_MODE_H4 = 0x01

H:4 mode

> While in this mode H:4 headers will added into the buffers according to the buffer type when coming from the stack and will be removed and used to set the buffer type.

Functions

int bt_send(struct net_buf *buf)

Send packet to the Bluetooth controller.

Send packet to the Bluetooth controller. Caller needs to implement netbuf pool.

Parameters

- buf – netbuf packet to be send

Returns

Zero on success or (negative) error code otherwise.

int bt_hci_raw_set_mode(uint8_t mode)

Set Bluetooth RAW channel mode.

Set access mode of Bluetooth RAW channel.

Parameters

- mode – Access mode.

Returns

Zero on success or (negative) error code otherwise.

uint8_t bt_hci_raw_get_mode(void)

Get Bluetooth RAW channel mode.

Get access mode of Bluetooth RAW channel.

Returns

Access mode.

void bt_hci_raw_cmd_ext_register(struct bt_hci_raw_cmd_ext *cmds, size_t size)

Register Bluetooth RAW command extension table.

Register Bluetooth RAW channel command extension table, opcodes in this table are intercepted to sent to the handler function.

Parameters

- cmds – Pointer to the command extension table.
• size – Size of the command extension table.

```c
int bt_enable_raw(struct k_fifo *rx_queue)
```

Enable Bluetooth RAW channel:
Enable Bluetooth RAW HCI channel.

**Parameters**

• `rx_queue` – netbuf queue where HCI packets received from the Bluetooth controller are to be queued. The queue is defined in the caller while the available buffers pools are handled in the stack.

**Returns**

Zero on success or (negative) error code otherwise.

```c
struct bt_hci_raw_cmd_ext
#include <hci_raw.h>
```

**Public Members**

```c
uint16_t op
   Opcode of the command

size_t min_len
   Minimal length of the command

uint8_t (*func)(struct net_buf *buf)
   Handler function.
   Handler function to be called when a command is intercepted.
   **Param buf**
   Buffer containing the command.
   **Return**
   HCI Status code or BT_HCI_ERR_EXT_HANDLED if command has been handled already and a response has been sent as oppose to BT_HCI_ERR_SUCCESS which just indicates that the command can be sent to the controller to be processed.
```

**Hands Free Profile (HFP)**

**API Reference**

`group bt_hfp`  
Hands Free Profile (HFP)

**Defines**

```c
HFP_HF_CMD_OK

HFP_HF_CMD_ERROR

HFP_HF_CMD_CME_ERROR
```
HFP_HF_CMD_UNKNOWN_ERROR

Enums

enum bt_hfp_hf_at_cmd

Values:

enumerator BT_HFP_HF_ATA
enumerator BT_HFP_HF_AT_CHUP

Functions

int bt_hfp_hf_register(struct bt_hfp_hf_cb *cb)

Register HFP HF profile.

Register Handsfree profile callbacks to monitor the state and get the required HFP details to display.

Parameters

• cb – callback structure.

Returns

0 in case of success or negative value in case of error.

int bt_hfp_hf_send_cmd(struct bt_conn *conn, enum bt_hfp_hf_at_cmd cmd)

Handsfree client Send AT.

Send specific AT commands to handsfree client profile.

Parameters

• conn – Connection object.
• cmd – AT command to be sent.

Returns

0 in case of success or negative value in case of error.

struct bt_hfp_hf_cmd_complete

#include <hfp_hf.h> HFP HF Command completion field.

struct bt_hfp_hf_cb

#include <hfp_hf.h> HFP profile application callback.

Public Members

void (*connected)(struct bt_conn *conn)

HF connected callback to application

If this callback is provided it will be called whenever the connection completes.

Param conn

Connection object.
void (*)(struct bt_conn *conn)
    HF disconnected callback to application
    If this callback is provided it will be called whenever the connection gets disconnected,
    including when a connection gets rejected or cancelled or any error in SLC establishment.
    
    **Param conn**
    Connection object.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides service indicator value to the application
    
    **Param conn**
    Connection object.
    
    **Param value**
    service indicator value received from the AG.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides call indicator value to the application
    
    **Param conn**
    Connection object.
    
    **Param value**
    call indicator value received from the AG.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides call setup indicator value to the application
    
    **Param conn**
    Connection object.
    
    **Param value**
    call setup indicator value received from the AG.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides call held indicator value to the application
    
    **Param conn**
    Connection object.
    
    **Param value**
    call held indicator value received from the AG.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides signal indicator value to the application
    
    **Param conn**
    Connection object.
    
    **Param value**
    signal indicator value received from the AG.

void (*)(struct bt_conn *conn, uint32_t value)
    HF indicator Callback
    This callback provides roaming indicator value to the application

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**Param conn**
Connection object.

**Param value**
roaming indicator value received from the AG.

```c
void (*battery)(struct bt_conn *conn, uint32_t value)
```
HF indicator Callback

This callback battery service indicator value to the application

**Param conn**
Connection object.

**Param value**
battery indicator value received from the AG.

```c
void (*ring_indication)(struct bt_conn *conn)
```
HF incoming call Ring indication callback to application

If this callback is provided it will be called whenever there is an incoming call.

**Param conn**
Connection object.

```c
void (*cmd_complete_cb)(struct bt_conn *conn, struct bt_hfp_hf_cmd_complete *cmd)
```
HF notify command completed callback to application

The command sent from the application is notified about its status

**Param conn**
Connection object.

**Param cmd**
structure contains status of the command including cme.

---

**Logical Link Control and Adaptation Protocol (L2CAP)**

L2CAP layer enables connection-oriented channels which can be enable with the configuration option: `CONFIG_BT_L2CAP_DYNAMIC_CHANNEL`. This channels support segmentation and reassembly transparently, they also support credit based flow control making it suitable for data streams.

Channels instances are represented by the `bt_l2cap_chan` struct which contains the callbacks in the `bt_l2cap_chan_ops` struct to inform when the channel has been connected, disconnected or when the encryption has changed. In addition to that it also contains the `recv` callback which is called whenever an incoming data has been received. Data received this way can be marked as processed by returning 0 or using `bt_l2cap_chan_recv_complete()` API if processing is asynchronous.

---

**Note:** The `recv` callback is called directly from RX Thread thus it is not recommended to block for long periods of time.

For sending data the `bt_l2cap_chan_send()` API can be used noting that it may block if no credits are available, and resuming as soon as more credits are available.

Servers can be registered using `bt_l2cap_server_register()` API passing the `bt_l2cap_server` struct which informs what `pmap` it should listen to, the required security level `sec_level`, and the callback `accept` which is called to authorize incoming connection requests and allocate channel instances.

Client channels can be initiated with use of `bt_l2cap_chan_connect()` API and can be disconnected with the `bt_l2cap_chan_disconnect()` API. Note that the later can also disconnect channel instances created by servers.
API Reference

group bt_l2cap

L2CAP.

Defines

BT_L2CAP_HDR_SIZE
L2CAP PDU header size, used for buffer size calculations

BT_L2CAP_TX_MTU
Maximum Transmission Unit (MTU) for an outgoing L2CAP PDU.

BT_L2CAP_RX_MTU
Maximum Transmission Unit (MTU) for an incoming L2CAP PDU.

BT_L2CAP_BUF_SIZE(mtu)
Helper to calculate needed buffer size for L2CAP PDUs. Useful for creating buffer pools.

Parameters
• mtu – Needed L2CAP PDU MTU.

Returns
Needed buffer size to match the requested L2CAP PDU MTU.

BT_L2CAP_SDU_HDR_SIZE
L2CAP SDU header size, used for buffer size calculations

BT_L2CAP_SDU_TX_MTU
Maximum Transmission Unit for an unsegmented outgoing L2CAP SDU.

The Maximum Transmission Unit for an outgoing L2CAP SDU when sent without segmentation, i.e. a single L2CAP SDU will fit inside a single L2CAP PDU.

The MTU for outgoing L2CAP SDUs with segmentation is defined by the size of the application buffer pool.

BT_L2CAP_SDU_RX_MTU
Maximum Transmission Unit for an unsegmented incoming L2CAP SDU.

The Maximum Transmission Unit for an incoming L2CAP SDU when sent without segmentation, i.e. a single L2CAP SDU will fit inside a single L2CAP PDU.

The MTU for incoming L2CAP SDUs with segmentation is defined by the size of the application buffer pool. The application will have to define an alloc_buf callback for the channel in order to support receiving segmented L2CAP SDUs.

BT_L2CAP_SDU_BUF_SIZE(mtu)
Helper to calculate needed buffer size for L2CAP SDUs. Useful for creating buffer pools.

Parameters
• mtu – Required BT_L2CAP_*_SDU.

Returns
Needed buffer size to match the requested L2CAP SDU MTU.
BT_L2CAP_LE_CHAN(_ch)

Helper macro getting container object of type bt_l2cap_le_chan address having the same container chan member address as object in question.

**Parameters**

- _ch – Address of object of bt_l2cap_chan type

**Returns**

Address of in memory bt_l2cap_le_chan object type containing the address of in question object.

BT_L2CAP_CHAN_SEND_RESERVE

Headroom needed for outgoing L2CAP PDUs.

BT_L2CAP_SDU_CHAN_SEND_RESERVE

Headroom needed for outgoing L2CAP SDUs.

**Typedefs**

typedef void (*bt_l2cap_chan_destroy_t)(struct bt_l2cap_chan *chan)

Channel destroy callback.

**Param chan**

Channel object.

typedef enum bt_l2cap_chan_state bt_l2cap_chan_state_t

Life-span states of L2CAP CoC channel.

Used only by internal APIs dealing with setting channel to proper state depending on operational context.

typedef enum bt_l2cap_chan_status bt_l2cap_chan_status_t

Status of L2CAP channel.

** Enums **

eenum bt_l2cap_chan_state

Life-span states of L2CAP CoC channel.

Used only by internal APIs dealing with setting channel to proper state depending on operational context.

**Values:**

- enumerator BT_L2CAP_DISCONNECTED
  Channel disconnected

- enumerator BT_L2CAP_CONNECTING
  Channel in connecting state

- enumerator BT_L2CAP_CONFIG
  Channel in config state, BR/EDR specific
enumerator BT_L2CAP_CONNECTED
- Channel ready for upper layer traffic on it

enumerator BT_L2CAP_DISCONNECTING
- Channel in disconnecting state

enum bt_l2cap_chan_status
- Status of L2CAP channel.
  Values:

  enumerator BT_L2CAP_STATUS_OUT
  - Channel output status

  enumerator BT_L2CAP_STATUS_SHUTDOWN
  - Channel shutdown status.
  
  Once this status is notified it means the channel will no longer be able to transmit or receive data.

  enumerator BT_L2CAP_STATUS_ENCRYPT_PENDING
  - Channel encryption pending status.

  enumerator BT_L2CAP_NUM_STATUS

Functions

int bt_l2cap_server_register(struct bt_l2cap_server *server)
- Register L2CAP server.
  Register L2CAP server for a PSM, each new connection is authorized using the accept() call-back which in case of success shall allocate the channel structure to be used by the new connection.
  For fixed, SIG-assigned PSMs (in the range 0x0001-0x007f) the PSM should be assigned to server->psm before calling this API. For dynamic PSMs (in the range 0x0080-0x00ff) server->psm may be pre-set to a given value (this is however not recommended) or be left as 0, in which case upon return a newly allocated value will have been assigned to it. For dynamically allocated values the expectation is that it's exposed through a GATT service, and that's how L2CAP clients discover how to connect to the server.

  Parameters

  • server – Server structure.

  Returns

  0 in case of success or negative value in case of error.

int bt_l2cap_br_server_register(struct bt_l2cap_server *server)
- Register L2CAP server on BR/EDR oriented connection.
  Register L2CAP server for a PSM, each new connection is authorized using the accept() call-back which in case of success shall allocate the channel structure to be used by the new connection.
Parameters

• server – Server structure.

Returns

0 in case of success or negative value in case of error.

int bt_l2cap_ecred_chan_connect(struct bt_conn *conn, struct bt_l2cap_chan **chans, uint16_t psm)

Connect Enhanced Credit Based L2CAP channels.

Connect up to 5 L2CAP channels by PSM, once the connection is completed each channel connected() callback will be called. If the connection is rejected disconnected() callback is called instead.

Parameters

• conn – Connection object.
• chans – Array of channel objects.
• psm – Channel PSM to connect to.

Returns

0 in case of success or negative value in case of error.

int bt_l2cap_ecred_chan_reconfigure(struct bt_l2cap_chan **chans, uint16_t mtu)

Reconfigure Enhanced Credit Based L2CAP channels.

Reconfigure up to 5 L2CAP channels. Channels must be from the same bt_conn. Once reconfiguration is completed each channel reconfigured() callback will be called. MTU cannot be decreased on any of provided channels.

Parameters

• chans – Array of channel objects. Null-terminated. Elements after the first 5 are silently ignored.
• mtu – Channel MTU to reconfigure to.

Returns

0 in case of success or negative value in case of error.

int bt_l2cap_chan_connect(struct bt_conn *conn, struct bt_l2cap_chan *chan, uint16_t psm)

Connect L2CAP channel.

Connect L2CAP channel by PSM, once the connection is completed channel connected() callback will be called. If the connection is rejected disconnected() callback is called instead. Channel object passed (over an address of it) as second parameter shouldn’t be instantiated in application as standalone. Instead of, application should create transport dedicated L2CAP objects, i.e. type of bt_l2cap_le_chan for LE and/or type of bt_l2cap_br_chan for BR/EDR. Then pass to this API the location (address) of bt_l2cap_chan type object which is a member of both transport dedicated objects.

Parameters

• conn – Connection object.
• chan – Channel object.
• psm – Channel PSM to connect to.

Returns

0 in case of success or negative value in case of error.
int bt_l2cap_chan_disconnect(struct bt_l2cap_chan *chan)
Disconnect L2CAP channel.

Disconnect L2CAP channel, if the connection is pending it will be canceled and as a result the channel disconnected() callback is called. Regarding to input parameter, to get details see reference description to bt_l2cap_chan_connect() API above.

Parameters
• chan – Channel object.

Returns
0 in case of success or negative value in case of error.

int bt_l2cap_chan_send(struct bt_l2cap_chan *chan, struct net_buf *buf)
Send data to L2CAP channel.

Send data from buffer to the channel. If credits are not available, buf will be queued and sent as and when credits are received from peer. Regarding to first input parameter, to get details see reference description to bt_l2cap_chan_connect() API above.

When sending L2CAP data over an BR/EDR connection the application is sending L2CAP PDUs. The application is required to have reserved BT_L2CAP_CHAN_SEND_RESERVE bytes in the buffer before sending. The application should use the BT_L2CAP_BUF_SIZE() helper to correctly size the buffers for the outgoing buffer pool.

When sending L2CAP data over an LE connection the application is sending L2CAP SDUs. The application can optionally reserve BT_L2CAP_SDU_CHAN_SEND_RESERVE bytes in the buffer before sending. By reserving bytes in the buffer the stack can use this buffer as a segment directly, otherwise it will have to allocate a new segment for the first segment. If the application is reserving the bytes it should use the BT_L2CAP_BUF_SIZE() helper to correctly size the buffers for the outgoing buffer pool. When segmenting an L2CAP SDU into L2CAP PDUs the stack will first attempt to allocate buffers from the original buffer pool of the L2CAP SDU before using the stacks own buffer pool.

Note: Buffer ownership is transferred to the stack in case of success, in case of an error the caller retains the ownership of the buffer.

Returns
Bytes sent in case of success or negative value in case of error.

int bt_l2cap_chan_recv_complete(struct bt_l2cap_chan *chan, struct net_buf *buf)
Complete receiving L2CAP channel data.

Complete the reception of incoming data. This shall only be called if the channel recv callback has returned -EINPROGRESS to process some incoming data. The buffer shall contain the original user_data as that is used for storing the credits/segments used by the packet.

Parameters
• chan – Channel object.
• buf – Buffer containing the data.

Returns
0 in case of success or negative value in case of error.

struct bt_l2cap_chan
#include <l2cap.h> L2CAP Channel structure.

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Public Members

struct bt_conn *conn
    Channel connection reference

const struct bt_l2cap_chan_ops *ops
    Channel operations reference

struct bt_l2cap_le_endpoint
    #include <l2cap.h> LE L2CAP Endpoint structure.

Public Members

uint16_t cid
    Endpoint Channel Identifier (CID)

uint16_t mtu
    Endpoint Maximum Transmission Unit

uint16_t mps
    Endpoint Maximum PDU payload Size

uint16_t init_credits
    Endpoint initial credits

atomic_t credits
    Endpoint credits

struct bt_l2cap_le_chan
    #include <l2cap.h> LE L2CAP Channel structure.

Public Members

struct bt_l2cap_chan chan
    Common L2CAP channel reference object

struct bt_l2cap_le_endpoint rx
    Channel Receiving Endpoint.

If the application has set an alloc_buf channel callback for the channel to support receiving segmented L2CAP SDUs the application should initialize the MTU of the Receiving Endpoint. Otherwise the MTU of the receiving endpoint will be initialized to BT_L2CAP_SDU_RX_MTU by the stack.

uint16_t pending_rx_mtu
    Pending RX MTU on ECFC reconfigure, used internally by stack
struct bt_l2cap_le_endpoint tx
    Channel Transmission Endpoint

struct kfifo tx_queue
    Channel Transmission queue

struct netbuf *tx_buf
    Channel Pending Transmission buffer

struct k_work tx_work
    Channel Transmission work

struct bt_l2cap_br_endpoint
    #include <l2cap.h> BREDR L2CAP Endpoint structure.

Public Members

uint16_t cid
    Endpoint Channel Identifier (CID)

uint16_t mtu
    Endpoint Maximum Transmission Unit

struct bt_l2cap_br_chan
    #include <l2cap.h> BREDR L2CAP Channel structure.

Public Members

struct bt_l2cap_chan chan
    Common L2CAP channel reference object

struct bt_l2cap_br_endpoint rx
    Channel Receiving Endpoint

struct bt_l2cap_br_endpoint tx
    Channel Transmission Endpoint

uint16_t psm
    Remote PSM to be connected

uint8_t ident
    Helps match request context during CoC

struct bt_l2cap_chan_ops
    #include <l2cap.h> L2CAP Channel operations structure.
Public Members

```c
void (*connected)(struct bt_l2cap_chan *chan)
   Channel connected callback.
   If this callback is provided it will be called whenever the connection completes.
   **Param chan**
   The channel that has been connected

void (*disconnected)(struct bt_l2cap_chan *chan)
   Channel disconnected callback.
   If this callback is provided it will be called whenever the channel is disconnected, including when a connection gets rejected.
   **Param chan**
   The channel that has been Disconnected

void (*encrypt_change)(struct bt_l2cap_chan *chan, uint8_t hci_status)
   Channel encrypt_change callback.
   If this callback is provided it will be called whenever the security level changed (indirectly link encryption done) or authentication procedure fails. In both cases security initiator and responder got the final status (HCI status) passed by related to encryption and authentication events from local host’s controller.
   **Param chan**
   The channel which has made encryption status changed.
   **Param status**
   HCI status of performed security procedure caused by channel security requirements. The value is populated by HCI layer and set to 0 when success and to non-zero (reference to HCI Error Codes) when security/authentication failed.

struct net_buf *(*alloc_seg)(struct bt_l2cap_chan *chan)
   Channel alloc_seg callback.
   If this callback is provided the channel will use it to allocate buffers to store segments. This avoids wasting big SDU buffers with potentially much smaller PDUs. If this callback is supplied, it must return a valid buffer.
   **Param chan**
   The channel requesting a buffer.
   **Return**
   Allocated buffer.

struct net_buf *(*alloc_buf)(struct bt_l2cap_chan *chan)
   Channel alloc_buf callback.
   If this callback is provided the channel will use it to allocate buffers to store incoming data. Channels that require segmentation must set this callback. If the application has not set a callback the L2CAP SDU MTU will be truncated to BT_L2CAP_SDU_RX_MTU.
   **Param chan**
   The channel requesting a buffer.
   **Return**
   Allocated buffer.

int (*recv)(struct bt_l2cap_chan *chan, struct net_buf *buf)
   Channel recv callback.
   **Param chan**
   The channel receiving data.
```
**Param** buf
  Buffer containing incoming data.

**Return**
  0 in case of success or negative value in case of error.

**Return**
  -EINPROGRESS in case where user has to confirm once the data has been processed by calling `bt_l2cap_chan_recv_complete` passing back the buffer received with its original user_data which contains the number of segments/credits used by the packet.

```c
void (*sent)(struct bt_l2cap_chan *chan)
```
Channel sent callback.

If this callback is provided it will be called whenever a SDU has been completely sent.

**Param chan**
The channel which has sent data.

```c
void (*status)(struct bt_l2cap_chan *chan, atomic_t *status)
```
Channel status callback.

If this callback is provided it will be called whenever the channel status changes.

**Param chan**
The channel which status changed

**Param status**
The channel status

```c
void (*reconfigured)(struct bt_l2cap_chan *chan)
```
Channel reconfigured callback.

If this callback is provided it will be called whenever peer or local device requested reconfiguration. Application may check updated MTU and MPS values by inspecting chan->le endpoints.

**Param chan**
The channel which was reconfigured

```c
struct bt_l2cap_server
```

#include `<l2cap.h>` L2CAP Server structure.

**Public Members**

```c
uint16_t psm
```
Server PSM.

Possible values: 0 A dynamic value will be auto-allocated when `bt_l2cap_server_register()` is called.

0x0001-0x007f Standard, Bluetooth SIG-assigned fixed values.

0x0080-0x00ff Dynamically allocated. May be pre-set by the application before server registration (not recommended however), or auto-allocated by the stack if the app gave 0 as the value.

```c
bt_security_t sec_level
```
Required minimum security level
int (*accept)(struct bt_conn *conn, struct bt_l2cap_chan **chan)

Server accept callback.

This callback is called whenever a new incoming connection requires authorization.

**Param conn**
The connection that is requesting authorization

**Param chan**
Pointer to received the allocated channel

**Return**
0 in case of success or negative value in case of error.

**Return**
-ENOMEM if no available space for new channel.

**Return**
-EACCES if application did not authorize the connection.

**Return**
-EPERM if encryption key size is too short.

Bluetooth Media

API Reference

Media Control Service

group bt_mcs

Media Control Service (MCS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

Definitions and types related to the Media Control Service and Media Control Profile specifications.

Defines

BT_MCS_PLAYBACK_SPEED_MIN

Playback speeds.

All values from -128 to 127 allowed, only some defined

BT_MCS_PLAYBACK_SPEED_QUARTER

BT_MCS_PLAYBACK_SPEED_HALF

BT_MCS_PLAYBACK_SPEED_UNITY

BT_MCS_PLAYBACK_SPEED_DOUBLE

BT_MCS_PLAYBACK_SPEED_MAX

BT_MCSSEEKING_SPEED_FACTOR_MAX

Seeking speed.

The allowed values for seeking speed are the range -64 to -4 (endpoints included), the value 0, and the range 4 to 64 (endpoints included).
BT_MCS_SEEKING_SPEED_FACTOR_MIN

BT_MCS_SEEKING_SPEED_FACTOR_ZERO

BT_MCS_PLAYING_ORDER_SINGLE_ONCE
   Playing orders

BT_MCS_PLAYING_ORDER_SINGLE_REPEAT

BT_MCS_PLAYING_ORDER_INORDER_ONCE

BT_MCS_PLAYING_ORDER_INORDER_REPEAT

BT_MCS_PLAYING_ORDER_OLDEST_ONCE

BT_MCS_PLAYING_ORDER_OLDEST_REPEAT

BT_MCS_PLAYING_ORDER_NEWEST_ONCE

BT_MCS_PLAYING_ORDER_NEWEST_REPEAT

BT_MCS_PLAYING_ORDER_SHUFFLE_ONCE

BT_MCS_PLAYING_ORDER_SHUFFLE_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_SINGLE_ONCE
   Playing orders supported.
   A bitmap, in the same order as the playing orders above. Note that playing order 1 corre-
   sponds to bit 0, and so on.

BT_MCS_PLAYING_ORDERS_SUPPORTED_SINGLE_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_INORDER_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_INORDER_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_OLDEST_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_OLDEST_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_NEWEST_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_NEWEST_REPEAT

BT_MCS_PLAYING_ORDERS_SUPPORTED_SHUFFLE_ONCE

BT_MCS_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT
BT_MCS_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT

BT_MCS_MEDIA_STATE_INACTIVE
   Media states

BT_MCS_MEDIA_STATE_PLAYING

BT_MCS_MEDIA_STATE_PAUSED

BT_MCS_MEDIA_STATE_SEEKING

BT_MCS_MEDIA_STATE_LAST

BT_MCS_OPC_PLAY
   Media control point opcodes

BT_MCS_OPC_PAUSE

BT_MCS_OPC_FAST_REWIND

BT_MCS_OPC_FAST_FORWARD

BT_MCS_OPC_STOP

BT_MCS_OPC_MOVE_RELATIVE

BT_MCS_OPC_PREV_SEGMENT

BT_MCS_OPC_NEXT_SEGMENT

BT_MCS_OPC_FIRST_SEGMENT

BT_MCS_OPC_LAST_SEGMENT

BT_MCS_OPC_GOTO_SEGMENT

BT_MCS_OPC_PREV_TRACK

BT_MCS_OPC_NEXT_TRACK

BT_MCS_OPC_FIRST_TRACK

BT_MCS_OPC_LAST_TRACK

BT_MCS_OPC_GOTO_TRACK
BT_MCS_OPC_PREV_GROUP

BT_MCS_OPC_NEXT_GROUP

BT_MCS_OPC_FIRST_GROUP

BT_MCS_OPC_LAST_GROUP

BT_MCS_OPC_GOTO_GROUP

BT_MCS_OPCODES_SUPPORTED_LEN
  Media control point supported opcodes length

BT_MCS_OPC_SUP_PLAY
  Media control point supported opcodes values

BT_MCS_OPC_SUP_PAUSE

BT_MCS_OPC_SUP_FAST_REWIND

BT_MCS_OPC_SUP_FAST_FORWARD

BT_MCS_OPC_SUP_STOP

BT_MCS_OPC_SUP_MOVE_RELATIVE

BT_MCS_OPC_SUP_PREV_SEGMENT

BT_MCS_OPC_SUP_NEXT_SEGMENT

BT_MCS_OPC_SUP_FIRST_SEGMENT

BT_MCS_OPC_SUP_LAST_SEGMENT

BT_MCS_OPC_SUP_GOTO_SEGMENT

BT_MCS_OPC_SUP_PREV_TRACK

BT_MCS_OPC_SUP_NEXT_TRACK

BT_MCS_OPC_SUP_FIRST_TRACK

BT_MCS_OPC_SUP_LAST_TRACK

BT_MCS_OPC_SUP_GOTO_TRACK
Media control point notification result codes

- BT_MCS_OP_S_UP_PREV_GROUP
- BT_MCS_OP_S_UP_NEXT_GROUP
- BT_MCS_OP_S_UP_FIRST_GROUP
- BT_MCS_OP_S_UP_LAST_GROUP
- BT_MCS_OP_S_UP_GOTO_GROUP

- BT_MCS_OP_S_UP_NTF_SUCCESS

Search control point type values

- BT_MCS_SEARCH_TYPE_TRACK_NAME
- BT_MCS_SEARCH_TYPE_ARTIST_NAME
- BT_MCS_SEARCH_TYPE_ALBUM_NAME
- BT_MCS_SEARCH_TYPE_GROUP_NAME
- BT_MCS_SEARCH_TYPE_EARLIEST_YEAR
- BT_MCS_SEARCH_TYPE_LATEST_YEAR
- BT_MCS_SEARCH_TYPE_GENRE
- BT_MCS_SEARCH_TYPE_ONLY_TRACKS
- BT_MCS_SEARCH_TYPE_ONLY_GROUPS

Search control point values

- SEARCH_LEN_MIN
- SEARCH_SCI_LEN_MIN
- SEARCH_LEN_MAX
- SEARCH_PARAM_MAX
Media Proxy

`group bt_media_proxy`

Media proxy module.

The media proxy module is the connection point between media players and media controllers. A media player has (access to) media content and knows how to navigate and play this content. A media controller reads or gets information from a player and controls the player by setting player parameters and giving the player commands.

The media proxy module allows media player implementations to make themselves available to media controllers. And it allows controllers to access, and get updates from, any player.

The media proxy module allows both local and remote control of local player instances: A media controller may be a local application, or it may be a Media Control Service relaying requests from a remote Media Control Client. There may be either local or remote control, or both, or even multiple instances of each.

[Experimental] Users should note that the APIs can change as a part of ongoing development.

Defines

`MEDIA_PROXY_PLAYBACK_SPEED_MIN`

Playback speed parameters.

All values from -128 to 127 allowed, only some defined

`MEDIA_PROXY_PLAYBACK_SPEED_QUARTER`

`MEDIA_PROXY_PLAYBACK_SPEED_HALF`

`MEDIA_PROXY_PLAYBACK_SPEED_UNITY`

`MEDIA_PROXY_PLAYBACK_SPEED_DOUBLE`

`MEDIA_PROXY_PLAYBACK_SPEED_MAX`

`MEDIA_PROXY_SEEKING_SPEED_FACTOR_MAX`

Seeking speed factors.

The allowed values for seeking speed are the range -64 to -4 (endpoints included), the value 0, and the range 4 to 64 (endpoints included).
MEDIA_PROXYSEEKINGSPEEDFACTORMIN

MEDIA_PROXYSEEKINGSPEEDFACTORZERO

MEDIA_PROXYPLAYINGORDERSINGLEONCE
Playing orders.

MEDIA_PROXYPLAYINGORDERSINGLEREPEAT

MEDIA_PROXYPLAYINGORDERINORDERONCE

MEDIA_PROXYPLAYINGORDERINORDERREPEAT

MEDIA_PROXYPLAYINGORDEROLDESTONCE

MEDIA_PROXYPLAYINGORDEROLDESTREPEAT

MEDIA_PROXYPLAYINGORDERNEWESTONCE

MEDIA_PROXYPLAYINGORDERNEWESTREPEAT

MEDIA_PROXYPLAYINGORDERSHUFFLEONCE

MEDIA_PROXYPLAYINGORDERSHUFFLEREPEAT

MEDIA_PROXYPLAYINGORDERSSUPPORTEDSINGLEONCE
Playing orders supported.
A bitmap, in the same order as the playing orders above. Note that playing order 1 corre-
sponds to bit 0, and so on.

MEDIA_PROXYPLAYINGORDERSSUPPORTEDSINGLEREPEAT

MEDIA_PROXYPLAYINGORDERSSUPPORTEDINORDERONCE

MEDIA_PROXYPLAYINGORDERSSUPPORTEDINORDERREPEAT

MEDIA_PROXYPLAYINGORDERSSUPPORTEDOLDESTONCE

MEDIA_PROXYPLAYINGORDERSSUPPORTEDOLDESTREPEAT

MEDIA_PROXYPLAYINGORDERSSUPPORTEDNEWESTONCE

MEDIA_PROXYPLAYINGORDERSSUPPORTEDNEWESTREPEAT

MEDIA_PROXYPLAYINGORDERSSUPPORTEDSHUFFLEONCE
MEDIA_PROXY_PLAYING_ORDERS_SUPPORTED_SHUFFLE_REPEAT

MEDIA_PROXY_STATE_INACTIVE
   Media player states.

MEDIA_PROXY_STATE_PLAYING

MEDIA_PROXY_STATE_PAUSED

MEDIA_PROXY_STATE_SEEKING

MEDIA_PROXY_STATE_LAST

MEDIA_PROXY_OP_PLAY
   Media player command opcodes.

MEDIA_PROXY_OP_PAUSE

MEDIA_PROXY_OP_FAST_REWIND

MEDIA_PROXY_OP_FAST_FORWARD

MEDIA_PROXY_OP_STOP

MEDIA_PROXY_OP_MOVE_RELATIVE

MEDIA_PROXY_OP_PREV_SEGMENT

MEDIA_PROXY_OP_NEXT_SEGMENT

MEDIA_PROXY_OP_FIRST_SEGMENT

MEDIA_PROXY_OP_LAST_SEGMENT

MEDIA_PROXY_OP_GOTO_SEGMENT

MEDIA_PROXY_OP_PREV_TRACK

MEDIA_PROXY_OP_NEXT_TRACK

MEDIA_PROXY_OP_FIRST_TRACK

MEDIA_PROXY_OP_LAST_TRACK

MEDIA_PROXY_OP_GOTO_TRACK

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MEDIA_PROXY_OP_PREV_GROUP
MEDIA_PROXY_OP_NEXT_GROUP
MEDIA_PROXY_OP_FIRST_GROUP
MEDIA_PROXY_OP_LAST_GROUP
MEDIA_PROXY_OP_GOTO_GROUP

MEDIA_PROXY_OPCODES_SUPPORTED_LEN
    Media player supported opcodes length.

MEDIA_PROXY_OP_SUP_PLAY
    Media player supported command opcodes.

MEDIA_PROXY_OP_SUP_PAUSE
MEDIA_PROXY_OP_SUP_FAST_REWIND
MEDIA_PROXY_OP_SUP_FAST_FORWARD
MEDIA_PROXY_OP_SUP_STOP
MEDIA_PROXY_OP_SUP_MOVE_RELATIVE
MEDIA_PROXY_OP_SUP_PREV_SEGMENT
MEDIA_PROXY_OP_SUP_NEXT_SEGMENT
MEDIA_PROXY_OP_SUP_FIRST_SEGMENT
MEDIA_PROXY_OP_SUP_LAST_SEGMENT
MEDIA_PROXY_OP_SUP_GOTO_SEGMENT
MEDIA_PROXY_OP_SUP_PREV_TRACK
MEDIA_PROXY_OP_SUP_NEXT_TRACK
MEDIA_PROXY_OP_SUP_FIRST_TRACK
MEDIA_PROXY_OP_SUP_LAST_TRACK
MEDIA_PROXY_OP_SUP_GOTO_TRACK
MEDIA_PROXY_OP_SUP_PREV_GROUP
MEDIA_PROXY_OP_SUP_NEXT_GROUP
MEDIA_PROXY_OP_SUP_FIRST_GROUP
MEDIA_PROXY_OP_SUP_LAST_GROUP
MEDIA_PROXY_OP_SUP_GOTO_GROUP
MEDIA_PROXY_CMD_SUCCESS
    Media player command result codes.
MEDIA_PROXY_CMD_NOT_SUPPORTED
MEDIA_PROXY_CMD_PLAYER_INACTIVE
MEDIA_PROXY_CMD_CANNOT_BE_COMPLETED
MEDIA_PROXY_SEARCH_TYPE_TRACK_NAME
    Search operation type values.
MEDIA_PROXY_SEARCH_TYPE_ARTIST_NAME
MEDIA_PROXY_SEARCH_TYPE_ALBUM_NAME
MEDIA_PROXY_SEARCH_TYPE_GROUP_NAME
MEDIA_PROXY_SEARCH_TYPE_EARLIEST_YEAR
MEDIA_PROXY_SEARCH_TYPE_LATEST_YEAR
MEDIA_PROXY_SEARCH_TYPE_GENRE
MEDIA_PROXY_SEARCH_TYPE_ONLY_TRACKS
MEDIA_PROXY_SEARCH_TYPE_ONLY_GROUPS
MEDIA_PROXY_SEARCH_SUCCESS
    Search operation result codes.
MEDIA_PROXY_SEARCH_FAILURE
MEDIA_PROXY_GROUP_OBJECT_TRACK_TYPE
MEDIA_PROXY_GROUP_OBJECT_GROUP_TYPE
Functions

int media_proxy_ctrl_register(struct media_proxy_ctrl_cbs *ctrl_cbs)
Register a controller with the media_proxy.

Parameters
• ctrl_cbs – Callbacks to the controller

Returns
0 if success, errno on failure

int media_proxy_ctrl_discover_player(struct bt_conn *conn)
Discover a remote media player.
Discover a remote media player instance. The remote player instance will be discovered, and accessed, using Bluetooth, via the media control client and a remote media control service. This call will start a GATT discovery of the Media Control Service on the peer, and setup handles and subscriptions.
This shall be called once before any other actions can be executed for the remote player. The remote player instance will be returned in the discover_player() callback.

Parameters
• conn – The connection to do discovery for

Returns
0 if success, errno on failure

int media_proxy_ctrl_get_player_name(struct media_player *player)
Read Media Player Name.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_icon_id(struct media_player *player)
Read Icon Object ID.
Get an ID (48 bit) that can be used to retrieve the Icon Object from an Object Transfer Service
See the Media Control Service spec v1.0 sections 3.2 and 4.1 for a description of the Icon Object.
Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_icon_url(struct media_player *player)
Read Icon URL.
Get a URL to the media player's icon.

Parameters
• player – Media player instance pointer
int media_proxy_ctrl_get_track_title(struct media_player *player)

Read Track Title.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_track_duration(struct media_player *player)

Read Track Duration.

The duration of a track is measured in hundredths of a second.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_track_position(struct media_player *player)

Read Track Position.

The position of the player (the playing position) is measured in hundredths of a second from
the beginning of the track.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_track_position(struct media_player *player, int32_t position)

Set Track Position.

Set the playing position of the media player in the current track. The position is given in in
hundredths of a second, from the beginning of the track of the track for positive values, and
(backwards) from the end of the track for negative values.

Parameters
• player – Media player instance pointer
• position – The track position to set

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_playback_speed(struct media_player *player)

Get Playback Speed.

The playback speed parameter is related to the actual playback speed as follows: actual play-
back speed = $2^\text{(speed parameter/64)}$

A speed parameter of 0 corresponds to unity speed playback (i.e. playback at “normal” speed).
A speed parameter of -128 corresponds to playback at one fourth of normal speed, 127 corre-
sponds to playback at almost four times the normal speed.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.
int media_proxy_ctrl_set_playback_speed(struct media_player *player, int8_t speed)
Set Playback Speed.

See the get_playback_speed() function for an explanation of the playback speed parameter.

Note that the media player may not support all possible values of the playback speed parameter. If the value given is not supported, and is higher than the current value, the player should set the playback speed to the next higher supported value. (And correspondingly to the next lower supported value for given values lower than the current value.)

Parameters
• player – Media player instance pointer
• speed – The playback speed parameter to set

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_seeking_speed(struct media_player *player)
Get Seeking Speed.

The seeking speed gives the speed with which the player is seeking. It is a factor, relative to real-time playback speed - a factor four means seeking happens at four times the real-time playback speed. Positive values are for forward seeking, negative values for backwards seeking.

The seeking speed is not settable - a non-zero seeking speed is the result of “fast rewind” of “fast forward” commands.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_track_segments_id(struct media_player *player)
Read Current Track Segments Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Segments Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.10 and 4.2 for a description of the Track Segments Object.

Requires Object Transfer Service

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_current_track_id(struct media_player *player)
Read Current Track Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service

See the Media Control Service spec v1.0 sections 3.11 and 4.3 for a description of the Current Track Object.

Requires Object Transfer Service

Parameters
• player – Media player instance pointer
Returns
0 if success, errno on failure.

```
int media_proxy_ctrl_set_current_track_id(struct media_player *player, uint64_t id)
```

Set Current Track Object ID.
Change the player’s current track to the track given by the ID. (Behaves similarly to the goto track command.)

Requires Object Transfer Service

Parameters
- `player` – Media player instance pointer
- `id` – The ID of a track object

Returns
0 if success, errno on failure.

```
int media_proxy_ctrl_get_next_track_id(struct media_player *player)
```

Read Next Track Object ID.
Get an ID (48 bit) that can be used to retrieve the Next Track Object from an Object Transfer Service.

Requires Object Transfer Service

Parameters
- `player` – Media player instance pointer

Returns
0 if success, errno on failure.

```
int media_proxy_ctrl_set_next_track_id(struct media_player *player, uint64_t id)
```

Set Next Track Object ID.
Change the player’s next track to the track given by the ID.

Requires Object Transfer Service

Parameters
- `player` – Media player instance pointer
- `id` – The ID of a track object

Returns
0 if success, errno on failure.

```
int media_proxy_ctrl_get_parent_group_id(struct media_player *player)
```

Read Parent Group Object ID.
Get an ID (48 bit) that can be used to retrieve the Parent Track Object from an Object Transfer Service.
The parent group is the parent of the current group.

See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Track Object.

Requires Object Transfer Service

Parameters
- `player` – Media player instance pointer

Returns
0 if success, errno on failure.

---

6.1. Bluetooth
int media_proxy_ctrl_get_current_group_id(struct media_player *player)
Read Current Group Object ID.

Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service.

See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Group Object.

Requires Object Transfer Service.

Parameters
- player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_current_group_id(struct media_player *player, uint64_t id)
Set Current Group Object ID.

Change the player's current group to the group given by the ID, and the current track to the first track in that group.

Requires Object Transfer Service.

Parameters
- player – Media player instance pointer
- id – The ID of a group object

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_playing_order(struct media_player *player)
Read Playing Order.

Parameters
- player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_set_playing_order(struct media_player *player, uint8_t order)
Set Playing Order.

Set the media player's playing order

Parameters
- player – Media player instance pointer
- order – The playing order to set

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_playing_orders_supported(struct media_player *player)
Read Playing Orders Supported.

Read a bitmap containing the media player's supported playing orders.

Parameters
- player – Media player instance pointer

Returns
0 if success, errno on failure.
int media_proxy_ctrl_get_media_state(struct media_player *player)
Read Media State.

Read the media player's state

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

int media_proxy_ctrl_send_command(struct media_player *player, const struct mpl_cmd *command)
Send Command.

Send a command to the media player. Commands may cause the media player to change its state. May result in two callbacks - one for the actual sending of the command to the player, one for the result of the command from the player.

Parameters
• player – Media player instance pointer
• command – The command to send

Returns
0 if success, errno on failure.

int media_proxy_ctrl_get_commands_supported(struct media_player *player)
Read Commands Supported.

Read a bitmap containing the media player's supported command opcodes.

Parameters
• player – Media player instance pointer

Returns
0 if success, errno on failure.

Set Search.

Write a search to the media player. If the search is successful, the search results will be available as a group object in the Object Transfer Service (OTS).

May result in up to three callbacks
• one for the actual sending of the search to the player
• one for the result code for the search from the player
• if the search is successful, one for the search results object ID in the OTs

Requires Object Transfer Service

Parameters
• player – Media player instance pointer
• search – The search to write

Returns
0 if success, errno on failure.
int media_proxy_ctrl_get_search_results_id(struct media_player *player)

Read Search Results Object ID.

Get an ID (48 bit) that can be used to retrieve the Search Results Object from an Object Transfer Service.

The search results object is a group object. The search results object only exists if a successful search operation has been done.

Requires Object Transfer Service

**Parameters**

- player – Media player instance pointer

**Returns**

0 if success, errno on failure.

```c
uint8_t media_proxy_ctrl_get_content_ctrl_id(struct media_player *player)
```

Read Content Control ID.

The content control ID identifies a content control service on a device, and links it to the corresponding audio stream.

**Parameters**

- player – Media player instance pointer

**Returns**

0 if success, errno on failure.

```c
int media_proxy_pl_register(struct media_proxy_pl_calls *pl_calls)
```

Register a player with the media proxy.

Register a player with the media proxy module, for use by media controllers.

The media proxy may call any non-NULL function pointers in the supplied `media_proxy_pl_calls` structure.

**Parameters**

- pl_calls – Function pointers to the media player's calls

**Returns**

0 if success, errno on failure.

```c
int media_proxy_pl_init(void)
```

```c
struct bt_ots *bt_mcs_get_ots(void)
```

```c
void media_proxy_pl_track_changed_cb(void)
```

Track changed callback.

To be called when the player's current track is changed.

```c
void media_proxy_pl_track_title_cb(char *title)
```

Track title callback.

To be called when the player's current track is changed.

**Parameters**

- title – The title of the track

```c
void media_proxy_pl_track_duration_cb(int32_t duration)
```

Track duration callback.

To be called when the current track's duration is changed (e.g. due to a track change).

The track duration is given in hundredths of a second.
Parameters

• duration – The track duration

`void media_proxy_pl_track_position_cb(int32_t position)`

Track position callback.
To be called when the media player’s position in the track is changed, or when the player is paused or similar.
Exception: This callback should not be called when the position changes during regular playback, i.e. while the player is playing and playback happens at a constant speed.
The track position is given in hundredths of a second from the start of the track.

Parameters

• position – The media player’s position in the track

`void media_proxy_pl_playback_speed_cb(int8_t speed)`

Playback speed callback.
To be called when the playback speed is changed.

Parameters

• speed – The playback speed parameter

`void media_proxy_pl_seeking_speed_cb(int8_t speed)`

Seeking speed callback.
To be called when the seeking speed is changed.

Parameters

• speed – The seeking speed factor

`void media_proxy_pl_current_track_id_cb(uint64_t id)`

Current track object ID callback.
To be called when the ID of the current track is changed (e.g. due to a track change).

Parameters

• id – The ID of the current track object in the OTS

`void media_proxy_pl_next_track_id_cb(uint64_t id)`

Next track object ID callback.
To be called when the ID of the current track is changed

Parameters

• id – The ID of the next track object in the OTS

`void media_proxy_pl_parent_group_id_cb(uint64_t id)`

Parent group object ID callback.
To be called when the ID of the parent group is changed

Parameters

• id – The ID of the parent group object in the OTS

`void media_proxy_pl_current_group_id_cb(uint64_t id)`

Current group object ID callback.
To be called when the ID of the current group is changed

Parameters

• id – The ID of the current group object in the OTS
void media_proxy_pl_playing_order_cb(uint8_t order)
    // Playing order callback.
    // To be called when the playing order is changed
    Parameters
    • order – The playing order

void media_proxy_pl_media_state_cb(uint8_t state)
    // Media state callback.
    // To be called when the media state is changed
    Parameters
    • state – The media player’s state

void media_proxy_pl_command_cb(const struct mpl_cmd_ntf *cmd_ntf)
    // Command callback.
    // To be called when a command has been sent, to notify whether the command was successfully performed or not. See the MEDIA_PROXY_CMD_* result code defines.
    Parameters
    • cmd_ntf – The result of the command

void media_proxy_pl_commands_supported_cb(uint32_t opcodes)
    // Commands supported callback.
    // To be called when the set of commands supported is changed
    Parameters
    • opcodes – The supported commands opcodes

void media_proxy_pl_search_cb(uint8_t result_code)
    // Search callback.
    // To be called when a search has been set to notify whether the search was successfully performed or not. See the MEDIA_PROXY_SEARCH_* result code defines.
    // The actual results of the search, if successful, can be found in the search results object.
    Parameters
    • result_code – The result (success or failure) of the search

void media_proxy_pl_search_results_id_cb(uint64_t id)
    // Search Results object ID callback.
    // To be called when the ID of the search results is changed (typically as the result of a new successful search).
    Parameters
    • id – The ID of the search results object in the OTS

#include <media_proxy.h>
struct mpl_cmd
    // Media player command.

#include <media_proxy.h>
struct mpl_cmd_ntf
    // Media command notification.

#include <media_proxy.h>
struct mpl_sci
    // Search control item.
Public Members

uint8_t len
   Length of type and parameter

uint8_t type
   MEDIA_PROXY_SEARCH_TYPE_<...>

cchar param[62]
   Search parameter

struct mpl_search
   #include <media_proxy.h> Search.

struct media_proxy_ctrl_cbs
   #include <media_proxy.h> Callbacks to a controller, from the media proxy.
   Given by a controller when registering

Public Members

void (*local_player_instance)(struct media_player *player, int err)
   Media Player Instance callback.
   Called when the local Media Player instance is registered or read (TODO). Also called if
   the local player instance is already registered when the controller is registered. Provides
   the controller with the pointer to the local player instance.
   Param player
      Media player instance pointer
   Param err
      Error value. 0 on success, or errno on negative value.

void (*player_name_recv)(struct media_player *player, int err, const char *name)
   Media Player Name receive callback.
   Called when the Media Player Name is read or changed See also media_proxy_ctrl_name_get()
   Param player
      Media player instance pointer
   Param err
      Error value. 0 on success, GATT error on positive value or errno on negative value.
   Param name
      The name of the media player

void (*icon_id_recv)(struct media_player *player, int err, uint64_t id)
   Media Player Icon Object ID receive callback.
   Called when the Media Player Icon Object ID is read See also media_proxy_ctrl_get_icon_id()
   Param player
      Media player instance pointer
void (*icon_url_recv)(struct media_player *player, int err, const char *url)
Media Player Icon URL receive callback.
Called when the Media Player Icon URL is read See also media_proxy_ctrl_get_icon_url()
  Param player
  Media player instance pointer
  Param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
  Param url
  The URL of the icon

void (*track_changed_recv)(struct media_player *player, int err)
Track changed receive callback.
Called when the Current Track is changed
  Param player
  Media player instance pointer
  Param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.

void (*track_title_recv)(struct media_player *player, int err, const char *title)
Track Title receive callback.
Called when the Track Title is read or changed See also media_proxy_ctrl_get_track_title()
  Param player
  Media player instance pointer
  Param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
  Param title
  The title of the current track

void (*track_duration_recv)(struct media_player *player, int err, int32_t duration)
Track Duration receive callback.
Called when the Track Duration is read or changed See also media_proxy_ctrl_get_track_duration()
  Param player
  Media player instance pointer
  Param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
  Param duration
  The duration of the current track

void (*track_position_recv)(struct media_player *player, int err, int32_t position)
Track Position receive callback.
Called when the Track Position is read or changed See also media_proxy_ctrl_get_track_position() and media_proxy_ctrl_set_track_position()
void (*track_position_write)(struct media_player *player, int err, int32_t position)

Track Position write callback.

Called when the Track Position is written. See also media_proxy_ctrl_set_track_position().

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param position
The player's position in the track

void (*playback_speed_recv)(struct media_player *player, int err, int8_t speed)

Playback Speed receive callback.

Called when the Playback Speed is read or changed. See also media_proxy_ctrl_get_playback_speed() and media_proxy_ctrl_set_playback_speed().

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param speed
The playback speed parameter

void (*playback_speed_write)(struct media_player *player, int err, int8_t speed)

Playback Speed write callback.

Called when the Playback Speed is written. See also media_proxy_ctrl_set_playback_speed().

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param speed
The playback speed parameter attempted to write

void (*seeking_speed_recv)(struct media_player *player, int err, int8_t speed)

Seeking Speed receive callback.

Called when the Seeking Speed is read or changed. See also media_proxy_ctrl_get_seeking_speed().

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param speed
The seeking speed factor
void (*track_segments_id_recv)(struct media_player *player, int err, uint64_t id)

Track Segments Object ID receive callback.

Called when the Track Segments Object ID is read. See also media_proxy_ctrl_get_track_segments_id().

_param player
Media player instance pointer

_param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

_param id
The ID of the track segments object in Object Transfer Service (48 bits)

void (*current_track_id_recv)(struct media_player *player, int err, uint64_t id)

Current Track Object ID receive callback.

Called when the Current Track Object ID is read or changed. See also media_proxy_ctrl_get_current_track_id() and media_proxy_ctrl_set_current_track_id().

_param player
Media player instance pointer

_param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

_param id
The ID of the current track object in Object Transfer Service (48 bits)

void (*current_track_id_write)(struct media_player *player, int err, uint64_t id)

Current Track Object ID write callback.

Called when the Current Track Object ID is written. See also media_proxy_ctrl_set_current_track_id().

_param player
Media player instance pointer

_param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

_param id
The ID (48 bits) attempted to write

void (*next_track_id_recv)(struct media_player *player, int err, uint64_t id)

Next Track Object ID receive callback.

Called when the Next Track Object ID is read or changed. See also media_proxy_ctrl_get_next_track_id() and media_proxy_ctrl_set_next_track_id().

_param player
Media player instance pointer

_param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

_param id
The ID of the next track object in Object Transfer Service (48 bits)

void (*next_track_id_write)(struct media_player *player, int err, uint64_t id)

Next Track Object ID write callback.

Called when the Next Track Object ID is written. See also media_proxy_ctrl_set_next_track_id().
void (*parent_group_id_recv)(struct media_player *player, int err, uint64_t id)

Parent Group Object ID receive callback.

Called when the Parent Group Object ID is read or changed See also media_proxy_ctrl_get_parent_group_id()

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID (48 bits) attempted to write

void (*current_group_id_recv)(struct media_player *player, int err, uint64_t id)

Current Group Object ID receive callback.

Called when the Current Group Object ID is read or changed See also media_proxy_ctrl_get_current_group_id() and media_proxy_ctrl_set_current_group_id()

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID of the parent group object in Object Transfer Service (48 bits)

void (*current_group_id_write)(struct media_player *player, int err, uint64_t id)

Current Group Object ID write callback.

Called when the Current Group Object ID is written See also media_proxy_ctrl_set_current_group_id()

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID (48 bits) attempted to write

void (*playing_order_recv)(struct media_player *player, int err, uint8_t order)

Playing Order receive callback.

Called when the Playing Order is read or changed See also media_proxy_ctrl_get_playing_order() and media_proxy_ctrl_set_playing_order()

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.
Param order
The playing order

void (*playing_order_write)(struct media_player *player, int err, uint8_t order)
Playing Order write callback.
Called when the Playing Order is written See also media_proxy_ctrl_set_playing_order()
 _param player
  Media player instance pointer
 _param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
 _param order
  The playing order attempted to write

void (*playing_orders_supported_recv)(struct media_player *player, int err, uint16_t orders)
Playing Orders Supported receive callback.
Called when the Playing Orders Supported is read See also media_proxy_ctrl_get_playing_orders_supported()
 _param player
  Media player instance pointer
 _param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
 _param orders
  The playing orders supported

void (*media_state_recv)(struct media_player *player, int err, uint8_t state)
Media State receive callback.
Called when the Media State is read or changed See also media_proxy_ctrl_get_media_state() and media_proxy_ctrl_send_command()
 _param player
  Media player instance pointer
 _param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
 _param state
  The media player state

void (*command_send)(struct media_player *player, int err, const struct mpl_cmd *cmd)
Command send callback.
Called when a command has been sent See also media_proxy_ctrl_send_command()
 _param player
  Media player instance pointer
 _param err
  Error value. 0 on success, GATT error on positive value or errno on negative value.
 _param cmd
  The command sent

void (*command_recv)(struct media_player *player, int err, const struct mpl_cmd_ntf *result)
Command result receive callback.
Called when a command result has been received
See also media_proxy_ctrl_send_command()

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param result**
The result received

```c
void (*commands_supported_recv)(struct media_player *player, int err, uint32_t opcodes)
```
Commands supported receive callback.

Called when the Commands Supported is read or changed
See also media_proxy_ctrl_get_commands_supported()

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param opcodes**
The supported command opcodes (bitmap)

```c
void (*search_send)(struct media_player *player, int err, const struct mpl_search *search)
```
Search send callback.

Called when a search has been sent
See also media_proxy_ctrl_send_search()

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param search**
The search sent

```c
void (*search_recv)(struct media_player *player, int err, uint8_t result_code)
```
Search result code receive callback.

Called when a search result code has been received
See also media_proxy_ctrl_send_search()

The search result code tells whether the search was successful or not. For a successful search, the actual results of the search (i.e. what was found as a result of the search) can be accessed using the Search Results Object ID. The Search Results Object ID has a separate callback - search_results_id_recv().

**Param player**
Media player instance pointer

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

**Param result_code**
Search result code

```c
void (*search_results_id_recv)(struct media_player *player, int err, uint64_t id)
```
Search Results Object ID receive callback
See also media_proxy_ctrl_get_search_results_id()

Called when the Search Results Object ID is read or changed

6.1. Bluetooth
void (*content_ctrl_id_recv)(struct media_player *player, int err, uint8_t ccid)

Content Control ID receive callback.
Called when the Content Control ID is read. See also `media_proxy_ctrl_get_content_ctrl_id()`

Param player
Media player instance pointer

Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param id
The ID of the search results object in Object Transfer Service (48 bits)

struct media_proxy_pl_calls

#include <media_proxy.h> Available calls in a player, that the media proxy can call.

Given by a player when registering.

Public Members

const char *(*get_player_name)(void)

Read Media Player Name.

Return
The name of the media player

uint64_t (*get_icon_id)(void)

Read Icon Object ID.

Get an ID (48 bit) that can be used to retrieve the Icon Object from an Object Transfer Service
See the Media Control Service spec v1.0 sections 3.2 and 4.1 for a description of the Icon Object.

Return
The Icon Object ID

const char *(*get_icon_url)(void)

Read Icon URL.

Get a URL to the media player's icon.

Return
The URL of the Icon

const char *(*get_track_title)(void)

Read Track Title.

Return
The title of the current track
int32_t (*get_track_duration)(void)
Read Track Duration.

The duration of a track is measured in hundredths of a second.

Return
The duration of the current track

int32_t (*get_track_position)(void)
Read Track Position.

The position of the player (the playing position) is measured in hundredths of a second from the beginning of the track

Return
The position of the player in the current track

void (*set_track_position)(int32_t position)
Set Track Position.

Set the playing position of the media player in the current track. The position is given in hundredths of a second, from the beginning of the track for positive values, and (backwards) from the end of the track for negative values.

Param position
The player position to set

int8_t (*get_playback_speed)(void)
Get Playback Speed.

The playback speed parameter is related to the actual playback speed as follows: actual playback speed = \(2^{\text{speed\_parameter}/64}\)

A speed parameter of 0 corresponds to unity speed playback (i.e. playback at “normal” speed). A speed parameter of -128 corresponds to playback at one fourth of normal speed, 127 corresponds to playback at almost four times the normal speed.

Return
The playback speed parameter

void (*set_playback_speed)(int8_t speed)
Set Playback Speed.

See the get_playback_speed() function for an explanation of the playback speed parameter.

Note that the media player may not support all possible values of the playback speed parameter. If the value given is not supported, and is higher than the current value, the player should set the playback speed to the next higher supported value. (And correspondingly to the next lower supported value for given values lower than the current value.)

Param speed
The playback speed parameter to set

int8_t (*get_seeking_speed)(void)
Get Seeking Speed.

The seeking speed gives the speed with which the player is seeking. It is a factor, relative to real-time playback speed - a factor four means seeking happens at four times the real-time playback speed. Positive values are for forward seeking, negative values for backwards seeking.

The seeking speed is not settable - a non-zero seeking speed is the result of “fast rewind” of “fast forward” commands.

6.1. Bluetooth
Return
The seeking speed factor

uint64_t (*get_track_segments_id)(void)
Read Current Track Segments Object ID.
Get an ID (48 bit) that can be used to retrieve the Current Track Segments Object from an Object Transfer Service
See the Media Control Service spec v1.0 sections 3.10 and 4.2 for a description of the Track Segments Object.

Return
Current Track Segments Object ID

uint64_t (*get_current_track_id)(void)
Read Current Track Object ID.
Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object Transfer Service
See the Media Control Service spec v1.0 sections 3.11 and 4.3 for a description of the Current Track Object.

Return
The Current Track Object ID

void (*set_current_track_id)(uint64_t id)
Set Current Track Object ID.
Change the player's current track to the track given by the ID. (Behaves similarly to the goto track command.)

Param id
The ID of a track object

uint64_t (*get_next_track_id)(void)
Read Next Track Object ID.
Get an ID (48 bit) that can be used to retrieve the Next Track Object from an Object Transfer Service

Return
The Next Track Object ID

void (*set_next_track_id)(uint64_t id)
Set Next Track Object ID.
Change the player's next track to the track given by the ID.

Param id
The ID of a track object

uint64_t (*get_parent_group_id)(void)
Read Parent Group Object ID.
Get an ID (48 bit) that can be used to retrieve the Parent Track Object from an Object Transfer Service
The parent group is the parent of the current group.
See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the Current Track Object.

Return
The Current Group Object ID
uint64_t (*get_current_group_id)(void)
  Read Current Group Object ID.
  Get an ID (48 bit) that can be used to retrieve the Current Track Object from an Object
  Transfer Service
  See the Media Control Service spec v1.0 sections 3.14 and 4.4 for a description of the
  Current Group Object.
  \textbf{Return}
  The Current Group Object ID

void (*set_current_group_id)(uint64_t id)
  Set Current Group Object ID.
  Change the player's current group to the group given by the ID, and the current track to
  the first track in that group.
  \textbf{Param id}
  The ID of a group object

uint8_t (*get_playing_order)(void)
  Read Playing Order.
  return The media player's current playing order

void (*set_playing_order)(uint8_t order)
  Set Playing Order.
  Set the media player's playing order. See the MEDIA_PROXY_PLAYING_ORDER_* de-
  fines.
  \textbf{Param order}
  The playing order to set

uint16_t (*get_playing_orders_supported)(void)
  Read Playing Orders Supported.
  Read a bitmap containing the media player's supported playing orders. See the ME-
  DIA_PROXY_PLAYING_ORDERS_SUPPORTED_* defines.
  \textbf{Return}
  The media player's supported playing orders

uint8_t (*get_media_state)(void)
  Read Media State.
  Read the media player's state See the MEDIA_PROXY_MEDIA_STATE_* defines.
  \textbf{Return}
  The media player's state

void (*send_command)(const struct mpl_cmd *command)
  Send Command.
  Send a command to the media player. For command opcodes (play, pause, ...) - see the
  MEDIA_PROXY_OP_* defines.
  \textbf{Param command}
  The command to send

uint32_t (*get_commands_supported)(void)
  Read Commands Supported.
Read a bitmap containing the media player's supported command opcodes. See the ME-
DIA_PROXY_OP_SUP_* defines.

**Return**
The media player's supported command opcodes

```c
void (*send_search)(const struct mpl_search *search)
```
Set Search.

Write a search to the media player. (For the formatting of a search, see the Media Control Service spec and the mcs.h file.)

**Param search**
The search to write

```c
uint64_t (*get_search_results_id)(void)
```
Read Search Results Object ID.

Get an ID (48 bit) that can be used to retrieve the Search Results Object from an Object Transfer Service

The search results object is a group object. The search results object only exists if a successful search operation has been done.

**Return**
The Search Results Object ID

```c
uint8_t (*get_content_ctrl_id)(void)
```
Read Content Control ID.

The content control ID identifies a content control service on a device, and links it to the corresponding audio stream.

**Return**
The content control ID for the media player

**Media Control Client**

`group bt_gatt_mcc`

Bluetooth Media Control Client (MCC) interface.

Updated to the Media Control Profile specification revision 1.0

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Typedefs**

```c
typedef void (*bt_mcc_discover_mcs_cb)(struct bt_conn *conn, int err)
```
Callback function for `bt_mcc_discover_mcs()`

Called when a media control server is discovered

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

```c
typedef void (*bt_mcc_read_player_name_cb)(struct bt_conn *conn, int err, const char *name)
```
Callback function for `bt_mcc_read_player_name()`

Called when the player name is read or notified
Param conn
   The connection that was used to initialise the media control client

Param err
   Error value. 0 on success, GATT error or errno on fail

Param name
   Player name

typedef void (*bt_mcc_read_icon_url_cb)(struct bt_conn *conn, int err, const char *icon_url)
   Callback function for bt_mcc_read_icon_url()
   Called when the icon URL is read

   Param conn
      The connection that was used to initialise the media control client

   Param err
      Error value. 0 on success, GATT error or errno on fail

   Param icon_url
      The URL of the Icon

typedef void (*bt_mcc_track_changed_ntf_cb)(struct bt_conn *conn, int err)
   Callback function for track changed notifications.
   Called when a track change is notified.
   The track changed characteristic is a special case. It can not be read or set, it can only be notified.

   Param conn
      The connection that was used to initialise the media control client

   Param err
      Error value. 0 on success, GATT error or errno on fail

typedef void (*bt_mcc_read_track_title_cb)(struct bt_conn *conn, int err, const char *title)
   Callback function for bt_mcc_read_track_title()
   Called when the track title is read or notified

   Param conn
      The connection that was used to initialise the media control client

   Param err
      Error value. 0 on success, GATT error or errno on fail

   Param title
      The title of the track

typedef void (*bt_mcc_read_track_duration_cb)(struct bt_conn *conn, int err, int32_t dur)
   Callback function for bt_mcc_read_track_duration()
   Called when the track duration is read or notified

   Param conn
      The connection that was used to initialise the media control client

   Param err
      Error value. 0 on success, GATT error or errno on fail

   Param dur
      The duration of the track
typedef void (*bt_mcc_read_track_position_cb)(struct bt_conn *conn, int err, int32_t pos)
Callback function for bt_mcc_read_track_position()
Called when the track position is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param pos
The Track Position

typedef void (*bt_mcc_set_track_position_cb)(struct bt_conn *conn, int err, int32_t pos)
Callback function for bt_mcc_set_track_position()
Called when the track position is set

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param pos
The Track Position set (or attempted to set)

typedef void (*bt_mcc_read_playback_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_read_playback_speed()
Called when the playback speed is read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param speed
The Playback Speed

typedef void (*bt_mcc_set_playback_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_set_playback_speed()
Called when the playback speed is set

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param speed
The Playback Speed set (or attempted to set)

typedef void (*bt_mcc_read_seeking_speed_cb)(struct bt_conn *conn, int err, int8_t speed)
Callback function for bt_mcc_read_seeking_speed()
Called when the seeking speed is read or notified

Param conn
The connection that was used to initialise the media control client
**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param speed**
The Seeking Speed

typedef void (*bt_mcc_read_playing_order_cb)(struct bt_conn *conn, int err, uint8_t order)
Callback function for `bt_mcc_read_playing_order()`
Called when the playing order is read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param order**
The playback order

typedef void (*bt_mcc_set_playing_order_cb)(struct bt_conn *conn, int err, uint8_t order)
Callback function for `bt_mcc_set_playing_order()`
Called when the playing order is set

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param order**
The Playing Order set (or attempted to set)

typedef void (*bt_mcc_read_playing_orders_supported_cb)(struct bt_conn *conn, int err, uint16_t orders)
Callback function for `bt_mcc_read_playing_orders_supported()`
Called when the supported playing orders are read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param orders**
The playing orders supported (bitmap)

typedef void (*bt_mcc_read_media_state_cb)(struct bt_conn *conn, int err, uint8_t state)
Callback function for `bt_mcc_read_media_state()`
Called when the media state is read or notified

**Param conn**
The connection that was used to initialise the media control client

**Param err**
Error value. 0 on success, GATT error or errno on fail

**Param state**
The Media State
typedef void (*bt_mcc_send_cmd_cb)(struct bt_conn *conn, int err, const struct mpl_cmd *cmd)

Callback function for bt_mcc_send_cmd()

Called when a command is sent, i.e. when the media control point is set

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param cmd
The command sent

typedef void (*bt_mcc_cmd_ntf_cb)(struct bt_conn *conn, int err, const struct mpl_cmd_ntf *ntf)

Callback function for command notifications.

Called when the media control point is notified

Notifications for commands (i.e. for writes to the media control point) use a different parameter structure than what is used for sending commands (writing to the media control point)

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param ntf
The command notification

datatype void (*bt_mcc_read_opcodes_supported_cb)(struct bt_conn *conn, int err, uint32_t opcodes)

Callback function for bt_mcc_read_opcodes_supported()

Called when the supported opcodes (commands) are read or notified

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param opcodes
The supported opcodes

datatype void (*bt_mcc_read_content_control_id_cb)(struct bt_conn *conn, int err, uint8_t ccid)

Callback function for bt_mcc_read_content_control_id()

Called when the content control ID is read

Param conn
The connection that was used to initialise the media control client

Param err
Error value. 0 on success, GATT error or errno on fail

Param ccid
The Content Control ID
Functions

int bt_mcc_init(struct bt_mcc_cb *cb)
Initialize Media Control Client.

Parameters
• cb – Callbacks to be used

Returns
0 if success, errno on failure.

int bt_mcc_discover_mcs(struct bt_conn *conn, bool subscribe)
Discover Media Control Service.

Discover Media Control Service (MCS) on the server given by the connection Optionally subscribe to notifications.

Shall be called once, after media control client initialization and before using other media control client functionality.

Parameters
• conn – Connection to the peer device
• subscribe – Whether to subscribe to notifications

Returns
0 if success, errno on failure.

int bt_mcc_read_player_name(struct bt_conn *conn)
Read Media Player Name.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_icon_url(struct bt_conn *conn)
Read Icon Object URL.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_track_title(struct bt_conn *conn)
Read Track Title.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.

int bt_mcc_read_track_duration(struct bt_conn *conn)
Read Track Duration.

Parameters
• conn – Connection to the peer device

Returns
0 if success, errno on failure.
int bt_mcc_read_track_position(struct bt_conn *conn)
  Read Track Position.

Parameters
  • conn – Connection to the peer device

Returns
  0 if success, errno on failure.

int bt_mcc_set_track_position(struct bt_conn *conn, int32_t pos)
  Set Track position.

Parameters
  • conn – Connection to the peer device
  • pos – Track position

Returns
  0 if success, errno on failure.

int bt_mcc_read_playback_speed(struct bt_conn *conn)
  Read Playback speed.

Parameters
  • conn – Connection to the peer device

Returns
  0 if success, errno on failure.

int bt_mcc_set_playback_speed(struct bt_conn *conn, int8_t speed)
  Set Playback Speed.

Parameters
  • conn – Connection to the peer device
  • speed – Playback speed

Returns
  0 if success, errno on failure.

int bt_mcc_read_seeking_speed(struct bt_conn *conn)
  Read Seeking speed.

Parameters
  • conn – Connection to the peer device

Returns
  0 if success, errno on failure.

int bt_mcc_read_playing_order(struct bt_conn *conn)
  Read Playing Order.

Parameters
  • conn – Connection to the peer device

Returns
  0 if success, errno on failure.

int bt_mcc_set_playing_order(struct bt_conn *conn, uint8_t order)
  Set Playing Order.

Parameters
  • conn – Connection to the peer device
• order – Playing order

**Returns**

0 if success, errno on failure.

```c
int bt_mcc_read_playing_orders_supported(struct bt_conn *conn)
```

Read Playing Orders Supported.

**Parameters**

• conn – Connection to the peer device

**Returns**

0 if success, errno on failure.

```c
int bt_mcc_read_media_state(struct bt_conn *conn)
```

Read Media State.

**Parameters**

• conn – Connection to the peer device

**Returns**

0 if success, errno on failure.

```c
int bt_mcc_send_cmd(struct bt_conn *conn, const struct mpl_cmd *cmd)
```

Send a command.

Write a command (e.g. “play”, “pause”) to the server's media control point.

**Parameters**

• conn – Connection to the peer device

• cmd – The command to send

**Returns**

0 if success, errno on failure.

```c
int bt_mcc_read_opcodes_supported(struct bt_conn *conn)
```

Read Opcodes Supported.

**Parameters**

• conn – Connection to the peer device

**Returns**

0 if success, errno on failure.

```c
int bt_mcc_read_content_control_id(struct bt_conn *conn)
```

Read Content Control ID.

**Parameters**

• conn – Connection to the peer device

**Returns**

0 if success, errno on failure.

```c
struct bt_mcc_cb

#include <mcc.h> Media control client callbacks.
```

---

**Bluetooth Mesh Profile**

The Bluetooth mesh profile adds secure wireless multi-hop communication for Bluetooth Low Energy. This module implements the Bluetooth Mesh Profile Specification v1.0.1.

Read more about Bluetooth mesh on the Bluetooth SIG Website.
Core  The core provides functionality for managing the general Bluetooth mesh state.

Low Power Node  The Low Power Node (LPN) role allows battery powered devices to participate in a mesh network as a leaf node. An LPN interacts with the mesh network through a Friend node, which is responsible for relaying any messages directed to the LPN. The LPN saves power by keeping its radio turned off, and only wakes up to either send messages or poll the Friend node for any incoming messages. The radio control and polling is managed automatically by the mesh stack, but the LPN API allows the application to trigger the polling at any time through `bt_mesh_lpn_poll()`. The LPN operation parameters, including poll interval, poll event timing and Friend requirements is controlled through the `CONFIG_BT_MESH_LOW_POWER` option and related configuration options.

Replay Protection List  The Replay Protection List (RPL) is used to hold recently received sequence numbers from elements within the mesh network to perform protection against replay attacks. To keep a node protected against replay attacks after reboot, it needs to store the entire RPL in the persistent storage before it is powered off. Depending on the amount of traffic in a mesh network, storing recently seen sequence numbers can make flash wear out sooner or later. To mitigate this, `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` can be used. This option postpones storing of RPL entries in the persistent storage.

This option, however, doesn’t completely solve the issue as the node may get powered off before the timer to store the RPL is fired. To ensure that messages can not be replayed, the node can initiate storage of the pending RPL entry (or entries) at any time (or sufficiently before power loss) by calling `bt_mesh_rpl_pending_store()`. This is up to the node to decide, which RPL entries are to be stored in this case.

Setting `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` to -1 allows to completely switch off the timer, which can help to significantly reduce flash wear out. This moves the responsibility of storing RPL to the user application and requires that sufficient power backup is available from the time this API is called until all RPL entries are written to the flash.

Finding the right balance between `CONFIG_BT_MESH_RPL_STORE_TIMEOUT` and calling `bt_mesh_rpl_pending_store()` may reduce a risk of security vulnerability and flash wear out.

API reference

group bt_mesh
  Bluetooth mesh.

  Defines

  BT_MESH_NET_PRIMARY
  BT_MESH_FEAT_RELAY
    Relay feature
  BT_MESH_FEAT_PROXY
    GATT Proxy feature
  BT_MESH_FEAT_FRIEND
    Friend feature
BT_MESH_FEAT_LOW_POWER
Low Power Node feature

BT_MESH_FEAT_SUPPORTED

BT_MESH_LPN_CB_DEFINE(_name)
Register a callback structure for Friendship events.

Parameters
• _name – Name of callback structure.

BT_MESH_FRIEND_CB_DEFINE(_name)
Register a callback structure for Friendship events.
Registers a callback structure that will be called whenever Friendship gets established or terminated.

Parameters
• _name – Name of callback structure.

Functions

int bt_mesh_init(const struct bt_mesh_prov *prov, const struct bt_mesh_comp *comp)
Initialize Mesh support.

After calling this API, the node will not automatically advertise as unprovisioned, rather the bt_mesh_prov_enable() API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.

Parameters
• prov – Node provisioning information.
• comp – Node Composition.

Returns
Zero on success or (negative) error code otherwise.

void bt_mesh_reset(void)
Reset the state of the local Mesh node.

Resets the state of the node, which means that it needs to be reprovisioned to become an active node in a Mesh network again.

After calling this API, the node will not automatically advertise as unprovisioned, rather the bt_mesh_prov_enable() API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.

int bt_mesh_suspend(void)
Suspend the Mesh network temporarily.

This API can be used for power saving purposes, but the user should be aware that leaving the local node suspended for a long period of time may cause it to become permanently disconnected from the Mesh network. If at all possible, the Friendship feature should be used instead, to make the node into a Low Power Node.

Returns
0 on success, or (negative) error code on failure.
int bt_mesh_resume(void)
    Resume a suspended Mesh network.

    This API resumes the local node, after it has been suspended using the \texttt{bt_mesh_suspend()} API.

    \textbf{Returns}
    0 on success, or (negative) error code on failure.

void bt_mesh_iv_update_test(bool enable)
    Toggle the IV Update test mode.

    This API is only available if the IV Update test mode has been enabled in Kconfig. It is needed for passing most of the IV Update qualification test cases.

    \textbf{Parameters}
    \begin{itemize}
    \item \texttt{enable} – true to enable IV Update test mode, false to disable it.
    \end{itemize}

bool bt_mesh_iv_update(void)
    Toggle the IV Update state.

    This API is only available if the IV Update test mode has been enabled in Kconfig. It is needed for passing most of the IV Update qualification test cases.

    \textbf{Returns}
    true if IV Update In Progress state was entered, false otherwise.

int bt_mesh_lpn_set(bool enable)
    Toggle the Low Power feature of the local device.

    Enables or disables the Low Power feature of the local device. This is exposed as a run-time feature, since the device might want to change this e.g. based on being plugged into a stable power source or running from a battery power source.

    \textbf{Parameters}
    \begin{itemize}
    \item \texttt{enable} – true to enable LPN functionality, false to disable it.
    \end{itemize}

    \textbf{Returns}
    Zero on success or (negative) error code otherwise.

int bt_mesh_lpn_poll(void)
    Send out a Friend Poll message.

    Send a Friend Poll message to the Friend of this node. If there is no established Friendship the function will return an error.

    \textbf{Returns}
    Zero on success or (negative) error code otherwise.

int bt_mesh_friend_terminate(uint16_t lpn_addr)
    Terminate Friendship.

    Terminated Friendship for given LPN.

    \textbf{Parameters}
    \begin{itemize}
    \item \texttt{lpn_addr} – Low Power Node address.
    \end{itemize}

    \textbf{Returns}
    Zero on success or (negative) error code otherwise.

void bt_mesh_rpl_pending_store(uint16_t addr)
    Store pending RPL entry(ies) in the persistent storage.

    This API allows the user to store pending RPL entry(ies) in the persistent storage without waiting for the timeout.
**Note:** When flash is used as the persistent storage, calling this API too frequently may wear it out.

**Parameters**

- `addr` – Address of the node which RPL entry needs to be stored or `BT_MESH_ADDR_ALL_NODES` to store all pending RPL entries.

```c
#include <main.h>
struct bt_mesh_lpn_cb
```

**Public Members**

```c
void (*established)(uint16_t net_idx, uint16_t friend_addr, uint8_t queue_size, uint8_t recv_window)
```

Friendship established.

This callback notifies the application that friendship has been successfully established.

- **Param net_idx**
  - NetKeyIndex used during friendship establishment.
- **Param friend_addr**
  - Friend address.
- **Param queue_size**
  - Friend queue size.
- **Param recv_window**
  - Low Power Node's listens duration for Friend response.

```c
void (*terminated)(uint16_t net_idx, uint16_t friend_addr)
```

Friendship terminated.

This callback notifies the application that friendship has been terminated.

- **Param net_idx**
  - NetKeyIndex used during friendship establishment.
- **Param friend_addr**
  - Friend address.

```c
void (*polled)(uint16_t net_idx, uint16_t friend_addr, bool retry)
```

Local Poll Request.

This callback notifies the application that the local node has polled the friend node.

This callback will be called before `bt_mesh_lpn_cb::established` when attempting to establish a friendship.

- **Param net_idx**
  - NetKeyIndex used during friendship establishment.
- **Param friend_addr**
  - Friend address.
- **Param retry**
  - Retry or first poll request for each transaction.

```c
#include <main.h>
struct bt_mesh_friend_cb
```

**6.1. Bluetooth**

```
```
Public Members

void (*established)(uint16_t net_idx, uint16_t lpn_addr, uint8_t recv_delay, uint32_t polltimeout)

Friendship established.
This callback notifies the application that friendship has been successfully established.
  \textbf{Param net_idx}  
  NetKeyIndex used during friendship establishment.
  \textbf{Param lpn_addr}  
  Low Power Node address.
  \textbf{Param recv_delay}  
  Receive Delay in units of 1 millisecond.
  \textbf{Param polltimeout}  
  PollTimeout in units of 1 millisecond.

void (*terminated)(uint16_t net_idx, uint16_t lpn_addr)

Friendship terminated.
This callback notifies the application that friendship has been terminated.
  \textbf{Param net_idx}  
  NetKeyIndex used during friendship establishment.
  \textbf{Param lpn_addr}  
  Low Power Node address.

void (*polled)(uint16_t net_idx, uint16_t lpn_addr)

Friend Poll Request.
This callback notifies the application that the low power node has polled the friend node.
This callback will be called before \texttt{bt\_mesh\_friend\_cb::established} when attempting to establish a friendship.
  \textbf{Param net_idx}  
  NetKeyIndex used during friendship establishment.
  \textbf{Param lpn_addr}  
  LPN address.

Access layer  The access layer is the application's interface to the Bluetooth mesh network. The access layer provides mechanisms for compartmentalizing the node behavior into elements and models, which are implemented by the application.

Mesh models  The functionality of a mesh node is represented by models. A model implements a single behavior the node supports, like being a light, a sensor or a thermostat. The mesh models are grouped into \textit{elements}. Each element is assigned its own unicast address, and may only contain one of each type of model. Conventionally, each element represents a single aspect of the mesh node behavior. For instance, a node that contains a sensor, two lights and a power outlet would spread this functionality across four elements, with each element instantiating all the models required for a single aspect of the supported behavior.

The node's element and model structure is specified in the node composition data, which is passed to \texttt{bt\_mesh\_init()} during initialization. The Bluetooth SIG have defined a set of foundation models (see \textit{Foundation models}) and a set of models for implementing common behavior in the Bluetooth Mesh Model Specification. All models not specified by the Bluetooth SIG are vendor models, and must be tied to a Company ID.

Mesh models have several parameters that can be configured either through initialization of the mesh stack or with the \textit{Configuration Server}:
Opcode list  The opcode list contains all message opcodes the model can receive, as well as the minimum acceptable payload length and the callback to pass them to. Models can support any number of opcodes, but each opcode can only be listed by one model in each element.

The full opcode list must be passed to the model structure in the composition data, and cannot be changed at runtime. The end of the opcode list is determined by the special `BT_MESH_MODEL_OP_END` entry. This entry must always be present in the opcode list, unless the list is empty. In that case, `BT_MESH_MODEL_NO_OPS` should be used in place of a proper opcode list definition.

AppKey list  The AppKey list contains all the application keys the model can receive messages on. Only messages encrypted with application keys in the AppKey list will be passed to the model.

The maximum number of supported application keys each model can hold is configured with the `CONFIG_BT_MESH_MODEL_KEY_COUNT` configuration option. The contents of the AppKey list is managed by the Configuration Server.

Subscription list  A model will process all messages addressed to the unicast address of their element (given that the utilized application key is present in the AppKey list). Additionally, the model will process packets addressed to any group or virtual address in its subscription list. This allows nodes to address multiple nodes throughout the mesh network with a single message.

The maximum number of supported addresses in the Subscription list each model can hold is configured with the `CONFIG_BT_MESH_MODEL_GROUP_COUNT` configuration option. The contents of the subscription list is managed by the Configuration Server.

Model publication  The models may send messages in two ways:

- By specifying a set of message parameters in a `bt_mesh_msg_ctx`, and calling `bt_mesh_model_send()`.
- By setting up a `bt_mesh_model_pub` structure and calling `bt_mesh_model_publish()`.

When publishing messages with `bt_mesh_model_publish()`, the model will use the publication parameters configured by the Configuration Server. This is the recommended way to send unprompted model messages, as it passes the responsibility of selecting message parameters to the network administrator, which likely knows more about the mesh network than the individual nodes will.

To support publishing with the publication parameters, the model must allocate a packet buffer for publishing, and pass it to `bt_mesh_model_pub.msg`. The Config Server may also set up period publication for the publication message. To support this, the model must populate the `bt_mesh_model_pub.update` callback. The `bt_mesh_model_pub.update` callback will be called right before the message is published, allowing the model to change the payload to reflect its current state.

By setting `bt_mesh_model_pub.retr_update` to 1, the model can configure the `bt_mesh_model_pub.update` callback to be triggered on every retransmission. This can, for example, be used by models that make use of a Delay parameter, which can be adjusted for every retransmission. The `bt Mesh_model pub_is_retransmission()` function can be used to differentiate a first publication and a retransmission. The `BT_MESH_PUB_MSG_TOTAL` and `BT_MESH_PUB_MSG_NUM` macros can be used to return total number of transmissions and the retransmission number within one publication interval.

Extended models  The Bluetooth mesh specification allows the mesh models to extend each other. When a model extends another, it inherits that model's functionality, and extension can be used to construct complex models out of simple ones, leveraging the existing model functionality to avoid defining new opcodes. Models may extend any number of models, from any element. When one model extends another in the same element, the two models will share subscription lists. The mesh stack implements this by merging the subscription lists of the two models into one, combining the number of subscriptions the models can have in total. Models may extend models that extend others, creating an “extension tree”. All models in an extension tree share a single subscription list per element it spans.
Model extensions are done by calling `bt_mesh_model_extend()` during initialization. A model can only be extended by one other model, and extensions cannot be circular. Note that binding of node states and other relationships between the models must be defined by the model implementations.

The model extension concept adds some overhead in the access layer packet processing, and must be explicitly enabled with `CONFIG_BT_MESH_MODEL_EXTENSIONS` to have any effect.

**Model data storage**  Mesh models may have data associated with each model instance that needs to be stored persistently. The access API provides a mechanism for storing this data, leveraging the internal model instance encoding scheme. Models can store one user defined data entry per instance by calling `bt_mesh_model_data_store()`. To be able to read out the data the next time the device reboots, the model's `bt_mesh_model_cb.settings_set` callback must be populated. This callback gets called when model specific data is found in the persistent storage. The model can retrieve the data by calling the `read_cb` passed as a parameter to the callback. See the `Settings` module documentation for details.

**API reference**  

`group bt_mesh_access`

Access layer.

**Defines**

- `BT_MESH_ADDR_UNASSIGNED`
- `BT_MESH_ADDR_ALL_NODES`
- `BT_MESH_ADDR_PROXIES`
- `BT_MESH_ADDR_FRIENDS`
- `BT_MESH_ADDR_RELAYS`
- `BT_MESH_KEY_UNUSED`
- `BT_MESH_KEY_ANY`
- `BT_MESH_KEY_DEV`
- `BT_MESH_KEY_DEV_LOCAL`
- `BT_MESH_KEY_DEV_REMOTE`
- `BT_MESH_KEY_DEV_ANY`
- `BT_MESH_ADDR_IS_UNICAST(addr)`
- `BT_MESH_ADDR_IS_GROUP(addr)`
- `BT_MESH_ADDR_IS_FIXED_GROUP(addr)`
BT_MESH_ADDR_IS_VIRTUAL(addr)
BT_MESH_ADDR_IS_RFU(addr)
BT_MESH_IS_DEV_KEY(key)

BT_MESH_APP_SEG_SDU_MAX
    Maximum size of an access message segment (in octets).

BT_MESH_APP_UNSEG_SDU_MAX
    Maximum payload size of an unsegmented access message (in octets).

BT_MESH_RX_SEG_MAX
    Maximum number of segments supported for incoming messages.

BT_MESH_TX_SEG_MAX
    Maximum number of segments supported for outgoing messages.

BT_MESH_TX_SDU_MAX
    Maximum possible payload size of an outgoing access message (in octets).

BT_MESH_RX_SDU_MAX
    Maximum possible payload size of an incoming access message (in octets).

BT_MESH_ELEM(_loc, _mods, _vnd_mods)
    Helper to define a mesh element within an array.
    In case the element has no SIG or Vendor models the helper macro BT_MESH_MODEL_NONE can be given instead.

    Parameters
    • _loc – Location Descriptor.
    • _mods – Array of models.
    • _vnd_mods – Array of vendor models.

BT_MESH_MODEL_ID_CFG_SRV

BT_MESH_MODEL_ID_CFG_CLI

BT_MESH_MODEL_ID_HEALTH_SRV

BT_MESH_MODEL_ID_HEALTH_CLI

BT_MESH_MODEL_ID_GEN_ONOFF_SRV

BT_MESH_MODEL_ID_GEN_ONOFF_CLI

BT_MESH_MODEL_ID_GEN_LEVEL_SRV

BT_MESH_MODEL_ID_GEN_LEVEL_CLI
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BT_MESH_MODEL_ID_TIME_CLI

BT_MESH_MODEL_ID_SCENE_SRV

BT_MESH_MODEL_ID_SCENE_SETUP_SRV

BT_MESH_MODEL_ID_SCENE_CLI

BT_MESH_MODEL_ID_SCHEDULER_SRV

BT_MESH_MODEL_ID_SCHEDULER_SETUP_SRV

BT_MESH_MODEL_ID_SCHEDULER_CLI

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_SRV

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_SETUP_SRV

BT_MESH_MODEL_ID_LIGHT_LIGHTNESS_CLI

BT_MESH_MODEL_ID_LIGHT_CTL_SRV

BT_MESH_MODEL_ID_LIGHT_CTL_SETUP_SRV

BT_MESH_MODEL_ID_LIGHT_CTL_CLI

BT_MESH_MODEL_ID_LIGHT_CTL_TEMP_SRV

BT_MESH_MODEL_ID_LIGHT_HSL_SRV

BT_MESH_MODEL_ID_LIGHT_HSL_SETUP_SRV

BT_MESH_MODEL_ID_LIGHT_HSL_CLI

BT_MESH_MODEL_ID_LIGHT_HSL_HUE_SRV

BT_MESH_MODEL_ID_LIGHT_HSL_SAT_SRV

BT_MESH_MODEL_ID_LIGHT_XYL_SRV

BT_MESH_MODEL_ID_LIGHT_XYL_SETUP_SRV

BT_MESH_MODEL_ID_LIGHT_XYL_CLI

BT_MESH_MODEL_ID_LIGHT_LC_SRV
BT_MESH_MODEL_ID_LIGHT_LC_SETUPSERV

BT_MESH_MODEL_ID_LIGHT_LC_CLI

BT_MESH_MODEL_OP_1(b0)

BT_MESH_MODEL_OP_2(b0, b1)

BT_MESH_MODEL_OP_3(b0, cid)

BT_MESH_LEN_EXACT(len)
   Macro for encoding exact message length for fixed-length messages.

BT_MESH_LEN_MIN(len)
   Macro for encoding minimum message length for variable-length messages.

BT_MESH_MODEL_OP_END
   End of the opcode list. Must always be present.

BT_MESH_MODEL_NO_OPS
   Helper to define an empty opcode list.

BT_MESH_MODEL_NONE
   Helper to define an empty model array

BT_MESH_MODEL_CNT_CB(_id, _op, _pub, _user_data, _keys, _grps, _cb)
   Composition data SIG model entry with callback functions with specific number of keys & groups.

   Parameters
   • _id – Model ID.
   • _op – Array of model opcode handlers.
   • _pub – Model publish parameters.
   • _user_data – User data for the model.
   • _keys – Number of keys that can be bound to the model. Shall not exceed CONFIG_BT_MESH_MODEL_KEY_COUNT.
   • _grps – Number of addresses that the model can be subscribed to. Shall not exceed CONFIG_BT_MESH_MODEL_GROUP_COUNT.
   • _cb – Callback structure, or NULL to keep no callbacks.

BT_MESH_MODEL_CNT_VND_CB(_company, _id, _op, _pub, _user_data, _keys, _grps, _cb)
   Composition data vendor model entry with callback functions with specific number of keys & groups.

   Parameters
   • _company – Company ID.
   • _id – Model ID.
   • _op – Array of model opcode handlers.
   • _pub – Model publish parameters.
   • _user_data – User data for the model.
   • _keys – Number of keys that can be bound to the model. Shall not exceed CONFIG_BT_MESH_MODEL_KEY_COUNT.
• `_grps` – Number of addresses that the model can be subscribed to. Shall not exceed `CONFIG_BT_MESH_MODEL_GROUP_COUNT`.

• `_cb` – Callback structure, or NULL to keep no callbacks.

`BT_MESH_MODEL_CB(_id, _op, _pub, _user_data, _cb)`
Composition data SIG model entry with callback functions.

**Parameters**

- `_id` – Model ID.
- `_op` – Array of model opcode handlers.
- `_pub` – Model publish parameters.
- `_user_data` – User data for the model.
- `_cb` – Callback structure, or NULL to keep no callbacks.

`BT_MESH_MODEL_VND_CB(_company, _id, _op, _pub, _user_data, _cb)`
Composition data vendor model entry with callback functions.

**Parameters**

- `_company` – Company ID.
- `_id` – Model ID.
- `_op` – Array of model opcode handlers.
- `_pub` – Model publish parameters.
- `_user_data` – User data for the model.
- `_cb` – Callback structure, or NULL to keep no callbacks.

`BT_MESH_MODEL(_id, _op, _pub, _user_data)`
Composition data SIG model entry.

**Parameters**

- `_id` – Model ID.
- `_op` – Array of model opcode handlers.
- `_pub` – Model publish parameters.
- `_user_data` – User data for the model.

`BT_MESH_MODEL_VND(_company, _id, _op, _pub, _user_data)`
Composition data vendor model entry.

**Parameters**

- `_company` – Company ID.
- `_id` – Model ID.
- `_op` – Array of model opcode handlers.
- `_pub` – Model publish parameters.
- `_user_data` – User data for the model.

`BT_MESH_TRANSMIT(count, int_ms)`
Encode transmission count & interval steps.

**Parameters**

- `count` – Number of retransmissions (first transmission is excluded).
• int_ms – Interval steps in milliseconds. Must be greater than 0, less than or equal to 320, and a multiple of 10.

**Returns**
Mesh transmit value that can be used e.g. for the default values of the configuration model data.

**BT_MESH_TRANSMIT_COUNT** (transmit)
Decode transmit count from a transmit value.

**Parameters**
- transmit – Encoded transmit count & interval value.

**Returns**
Transmission count (actual transmissions is N + 1).

**BT_MESH_TRANSMIT_INT** (transmit)
Decode transmit interval from a transmit value.

**Parameters**
- transmit – Encoded transmit count & interval value.

**Returns**
Transmission interval in milliseconds.

**BT_MESH_PUB_TRANSMIT** (count, int_ms)
Encode Publish Retransmit count & interval steps.

**Parameters**
- count – Number of retransmissions (first transmission is excluded).
- int_ms – Interval steps in milliseconds. Must be greater than 0 and a multiple of 50.

**Returns**
Mesh transmit value that can be used e.g. for the default values of the configuration model data.

**BT_MESH_PUB_TRANSMIT_COUNT** (transmit)
Decode Publish Retransmit count from a given value.

**Parameters**
- transmit – Encoded Publish Retransmit count & interval value.

**Returns**
Retransmission count (actual transmissions is N + 1).

**BT_MESH_PUB_TRANSMIT_INT** (transmit)
Decode Publish Retransmit interval from a given value.

**Parameters**
- transmit – Encoded Publish Retransmit count & interval value.

**Returns**
Transmission interval in milliseconds.

**BT_MESH_PUB_MSG_TOTAL** (pub)
Get total number of messages within one publication interval including initial publication.

**Parameters**
- pub – Model publication context.

**Returns**
total number of messages.
BT_MESH_PUB_MSG_NUM(pub)
Get message number within one publication interval.
Meant to be used inside bt_mesh_model_pub::update.

Parameters
• pub – Model publication context.

Returns
message number starting from 1.

BT_MESH_MODEL_PUB_DEFINE(_name, _update, _msg_len)
Define a model publication context.

Parameters
• _name – Variable name given to the context.
• _update – Optional message update callback (may be NULL).
• _msg_len – Length of the publication message.

BT_MESH_TTL_DEFAULT
Special TTL value to request using configured default TTL

BT_MESH_TTL_MAX
Maximum allowed TTL value

Functions

int bt_mesh_model_send(struct bt_mesh_model *model, struct bt_mesh_msg_ctx *ctx, struct net_buf_simple *msg, const struct bt_mesh_send_cb *cb, void *cb_data)
Send an Access Layer message.

Parameters
• model – Mesh (client) Model that the message belongs to.
• ctx – Message context, includes keys, TTL, etc.
• msg – Access Layer payload (the actual message to be sent).
• cb – Optional “message sent” callback.
• cb_data – User data to be passed to the callback.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_model_publish(struct bt_mesh_model *model)
Send a model publication message.

Before calling this function, the user needs to ensure that the model publication message (bt_mesh_model_pub::msg) contains a valid message to be sent. Note that this API is only to be used for non-period publishing. For periodic publishing the app only needs to make sure that bt_mesh_model_pub::msg contains a valid message whenever the bt_mesh_model_pub::update callback is called.

Parameters
• model – Mesh (client) Model that’s publishing the message.

Returns
0 on success, or (negative) error code on failure.
static inline bool bt_mesh_model_pub_is_retransmission(const struct bt_mesh_model *model)
Check if a message is being retransmitted.

Meant to be used inside the bt_mesh_model_pub::update callback.

Parameters
• model – Mesh Model that supports publication.

Returns
true if this is a retransmission, false if this is a first publication.

struct bt_mesh_elem *bt_mesh_model_elem(struct bt_mesh_model *mod)
Get the element that a model belongs to.

Parameters
• mod – Mesh model.

Returns
Pointer to the element that the given model belongs to.

struct bt_mesh_model *bt_mesh_model_find(const struct bt_mesh_elem *elem, uint16_t id)
Find a SIG model.

Parameters
• elem – Element to search for the model in.
• id – Model ID of the model.

Returns
A pointer to the Mesh model matching the given parameters, or NULL if no SIG model with the given ID exists in the given element.

struct bt_mesh_model *bt_mesh_model_find_vnd(const struct bt_mesh_elem *elem, uint16_t company, uint16_t id)
Find a vendor model.

Parameters
• elem – Element to search for the model in.
• company – Company ID of the model.
• id – Model ID of the model.

Returns
A pointer to the Mesh model matching the given parameters, or NULL if no vendor model with the given ID exists in the given element.

static inline bool bt_mesh_model_in_primary(const struct bt_mesh_model *mod)
Get whether the model is in the primary element of the device.

Parameters
• mod – Mesh model.

Returns
true if the model is on the primary element, false otherwise.

int bt_mesh_model_data_store(struct bt_mesh_model *mod, bool vnd, const char *name, const void *data, size_t data_len)
Immediately store the model's user data in persistent storage.

Parameters
• mod – Mesh model.
• vnd – This is a vendor model.
• name – Name/key of the settings item. Only `SETTINGS_MAX_DIR_DEPTH` bytes will be used at most.
• data – Model data to store, or NULL to delete any model data.
• data_len – Length of the model data.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_model_extend(struct bt_mesh_model *extending_mod, struct bt_mesh_model *base_mod)
```

Let a model extend another.

Mesh models may be extended to reuse their functionality, forming a more complex model. A Mesh model may extend any number of models, in any element. The extensions may also be nested, ie a model that extends another may itself be extended.

A set of models that extend each other form a model extension list.

All models in an extension list share one subscription list per element. The access layer will utilize the combined subscription list of all models in an extension list and element, giving the models extended subscription list capacity.

**Parameters**
• extending_mod – Mesh model that is extending the base model.
• base_mod – The model being extended.

**Return values**
0 – Successfully extended the base_mod model.

```c
bool bt_mesh_model_is_extended(struct bt_mesh_model *model)
```

Check if model is extended by another model.

**Parameters**
• model – The model to check.

**Return values**
true – If model is extended by another model, otherwise false

```c
struct bt_mesh_elem
```

```c
#include <access.h> Abstraction that describes a Mesh Element
```

### Public Members

```c
uint16_t addr
```
Unicast Address. Set at runtime during provisioning.

```c
const uint16_t loc
```
Location Descriptor (GATT Bluetooth Namespace Descriptors)

```c
const uint8_t model_count
```
The number of SIG models in this element

```c
const uint8_t vnd_model_count
```
The number of vendor models in this element

6.1. Bluetooth
struct bt_mesh_model *const models
    The list of SIG models in this element

struct bt_mesh_model *const vnd_models
    The list of vendor models in this element

struct bt_mesh_model_op
    #include <access.h> Model opcode handler.

Public Members

cst uint32_t opcode
    OpCode encoded using the BT_MESH_MODEL_OP_* macros

cst ssize_t len
    Message length. If the message has variable length then this value indicates minimum
    message length and should be positive. Handler function should verify precise length
    based on the contents of the message. If the message has fixed length then this value
    should be negative. Use BT_MESH_LEN_* macros when defining this value.

int (*const func)(struct bt_mesh_model *model, struct bt_mesh_msg_ctx *ctx, struct
    net_buf_simple *buf)
    Handler function for this opcode.
        Param model
            Model instance receiving the message.
        Param ctx
            Message context for the message.
        Param buf
            Message buffer containing the message payload, not including the opcode.
    Return
        Zero on success or (negative) error code otherwise.

struct bt_mesh_model_pub
    #include <access.h> Model publication context.
    The context should primarily be created using the BT_MESH_MODEL_PUB_DEFINE macro.

Public Members

struct bt_mesh_model *mod
    The model the context belongs to. Initialized by the stack.

uint16_t addr
    Publish Address.

uint16_t key
    Publish AppKey Index.

uint16_t cred
    Friendship Credentials Flag.
uint16_t send_rel
    Force reliable sending (segment acks)

uint16_t fast_period
    Use FastPeriodDivisor

uint16_t retr_update
    Call update callback on every retransmission.

uint8_t ttl
    Publish Time to Live.

uint8_t retransmit
    Retransmit Count & Interval Steps.

uint8_t period
    Publish Period.

uint8_t period_div
    Divisor for the Period.

uint8_t count
    Transmissions left.

uint32_t period_start
    Start of the current period.

struct net_buf_simple *msg
    Publication buffer, containing the publication message.

This will get correctly created when the publication context has been defined using the
BT_MESH_MODEL_PUB_DEFINE macro.

```
BT_MESH_MODEL_PUB_DEFINE(name, update, size);
```

int (*update)(struct bt_mesh_model *mod)
    Callback for updating the publication buffer.

    When set to NULL, the model is assumed not to support periodic publishing. When
    set to non-NULL the callback will be called periodically and is expected to update
    bt_mesh_model_pub::msg with a valid publication message.

    If the callback returns non-zero, the publication is skipped and will resume on the next
    periodic publishing interval.

    When bt_mesh_model_pub::retr_update is set to 1, the callback will be called on every
    retransmission.

    **Param mod**
    The Model the Publication Context belongs to.

    **Return**
    Zero on success or (negative) error code otherwise.

6.1. Bluetooth
struct \texttt{k\_work\_delayable} timer

Publish Period Timer. Only for stack-internal use.

struct bt\_mesh\_model\_cb

\#include <access.h> Model callback functions.

**Public Members**

\begin{verbatim}
int (*const settings_set)(struct bt\_mesh\_model *model, const char *name, size\_t len\_rd, settings\_read\_cb read\_cb, void *cb\_arg)
Set value handler of user data tied to the model.
\end{verbatim}

**See also:**

settings\_handler::h\_set

**Param** model
Model to set the persistent data of.

**Param** name
Name/key of the settings item.

**Param** len\_rd
The size of the data found in the backend.

**Param** read\_cb
Function provided to read the data from the backend.

**Param** cb\_arg
Arguments for the read function provided by the backend.

**Return**
0 on success, error otherwise.

\begin{verbatim}
int (*const start)(struct bt\_mesh\_model *model)
Callback called when the mesh is started.
This handler gets called after the node has been provisioned, or after all mesh data has been loaded from persistent storage.
When this callback fires, the mesh model may start its behavior, and all Access APIs are ready for use.
**Param** model
Model this callback belongs to.
**Return**
0 on success, error otherwise.
\end{verbatim}

\begin{verbatim}
int (*const init)(struct bt\_mesh\_model *model)
Model init callback.
Called on every model instance during mesh initialization.
If any of the model init callbacks return an error, the Mesh subsystem initialization will be aborted, and the error will be returned to the caller of bt\_mesh\_init.
**Param** model
Model to be initialized.
**Return**
0 on success, error otherwise.
\end{verbatim}
void (*const reset)(struct bt_mesh_model *model)

Model reset callback.
Called when the mesh node is reset. All model data is deleted on reset, and the model should clear its state.

**Note:** If the model stores any persistent data, this needs to be erased manually.

**Param model**
Model this callback belongs to.

```
struct bt_mesh_mod_id_vnd
#include <access.h> Vendor model ID
```

**Public Members**

```
uint16_t company
Vendor's company ID
```

```
uint16_t id
Model ID
```

```
struct bt_mesh_model
#include <access.h> Abstraction that describes a Mesh Model instance
```

**Public Members**

```
const uint16_t id
SIG model ID
```

```
const struct bt_mesh_mod_id_vnd vnd
Vendor model ID
```

```
struct bt_mesh_model_pub *const pub
Model Publication
```

```
uint16_t *const keys
AppKey List
```

```
uint16_t *const groups
Subscription List (group or virtual addresses)
```

```
const struct bt_mesh_model_op *const op
Opcode handler list
```

```
const struct bt_mesh_model_cb *const cb
Model callback structure.
```

6.1. Bluetooth
void *user_data

Model-specific user data

struct bt_mesh_send_cb

#include <access.h> Callback structure for monitoring model message sending

Public Members

void (*start)(uint16_t duration, int err, void *cb_data)
Handler called at the start of the transmission.
  Param duration
  The duration of the full transmission.
  Param err
  Error occurring during sending.
  Param cb_data
  Callback data, as passed to the send API.

void (*end)(int err, void *cb_data)
Handler called at the end of the transmission.
  Param err
  Error occurring during sending.
  Param cb_data
  Callback data, as passed to the send API.

struct bt_mesh_comp

#include <access.h> Node Composition

Public Members

uint16_t cid
  Company ID

uint16_t pid
  Product ID

uint16_t vid
  Version ID

size_t elem_count
  The number of elements in this device.

struct bt_mesh_elem *elem
  List of elements.

Foundation models The Bluetooth mesh specification defines four foundation models that can be used by network administrators to configure and diagnose mesh nodes.
**Configuration Server**  The Configuration Server model is a foundation model defined by the Bluetooth mesh specification. The Configuration Server model controls most parameters of the mesh node. It does not have an API of its own, but relies on a *Configuration Client* to control it.

..note::
The `bt_mesh_cfg_srv` structure has been deprecated. The initial values of the Relay, Beacon, Friend, Network transmit and Relay retransmit should be set through Kconfig, and the Heartbeat feature should be controlled through the *Heartbeat* API.

The Configuration Server model is mandatory on all Bluetooth mesh nodes, and should be instantiated in the first element.

**API reference**

*group bt_mesh_cfg_srv*

Configuration Server Model.

**Defines**

`BT_MESH_MODEL_CFG_SRV`

Generic Configuration Server model composition data entry.

**Configuration Client**  The Configuration Client model is a foundation model defined by the Bluetooth mesh specification. It provides functionality for configuring most parameters of a mesh node, including encryption keys, model configuration and feature enabling.

The Configuration Client model communicates with a *Configuration Server* model using the device key of the target node. The Configuration Client model may communicate with servers on other nodes or self-configure through the local Configuration Server model.

All configuration functions in the Configuration Client API have `net_idx` and `addr` as their first parameters. These should be set to the network index and primary unicast address that the target node was provisioned with.

The Configuration Client model is optional, but should be instantiated on the first element if it is present in the composition data.

**API reference**

*group bt_mesh_cfg_cli*

Configuration Client Model.

**Defines**

`BT_MESH_MODEL_CFG_CLI(cli_data)`

Generic Configuration Client model composition data entry.

**Parameters**

- `cli_data` – Pointer to a *Configuration Client Model* instance.

`BT_MESH_PUB_PERIOD_100MS(steps)`

Helper macro to encode model publication period in units of 100ms.

**Parameters**

- `steps` – Number of 100ms steps.
Returns

Encoded value that can be assigned to $bt\_mesh\_cfg\_cli\_mod\_pub\_period$

$BT\_MESH\_PUB\_PERIOD\_SEC(steps)$

Helper macro to encode model publication period in units of 1 second.

Parameters

• $steps$ – Number of 1 second steps.

Returns

Encoded value that can be assigned to $bt\_mesh\_cfg\_cli\_mod\_pub\_period$

$BT\_MESH\_PUB\_PERIOD\_10SEC(steps)$

Helper macro to encode model publication period in units of 10 seconds.

Parameters

• $steps$ – Number of 10 second steps.

Returns

Encoded value that can be assigned to $bt\_mesh\_cfg\_cli\_mod\_pub\_period$

$BT\_MESH\_PUB\_PERIOD\_10MIN(steps)$

Helper macro to encode model publication period in units of 10 minutes.

Parameters

• $steps$ – Number of 10 minute steps.

Functions

int $bt\_mesh\_cfg\_node\_reset(uint16\_t net\_idx, uint16\_t addr, bool *status)$

Reset the target node and remove it from the network.

Parameters

• $net\_idx$ – Network index to encrypt with.
• $addr$ – Target node address.
• $status$ – Status response parameter

Returns

0 on success, or (negative) error code on failure.

int $bt\_mesh\_cfg\_comp\_data\_get(uint16\_t net\_idx, uint16\_t addr, uint8\_t page, uint8\_t *rsp,$

struct $net\_buf\_simple *comp)$

Get the target node's composition data.

If the other device does not have the given composition data page, it will return the largest page number it supports that is less than the requested page index. The actual page the device responds with is returned in $rsp$.

This method can be used asynchronously by setting $rsp$ and $comp$ as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• $net\_idx$ – Network index to encrypt with.
• $addr$ – Target node address.
• $page$ – Composition data page, or 0xff to request the first available page.
int bt_mesh_cfg_beacon_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
Get the target node's network beacon state.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• status – Status response parameter, returns one of
  BT_MESH_BEACON_DISABLED or BT_MESH_BEACON_ENABLED on suc-
  cess.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_krp_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint8_t *phase)
Get the target node's network key refresh phase state.

This method can be used asynchronously by setting status and phase as NULL. This way the
method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index.
• status – Status response parameter.
• phase – Pointer to the Key Refresh variable to fill.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_krp_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t transition, uint8_t *status, uint8_t *phase)
Set the target node's network key refresh phase parameters.

This method can be used asynchronously by setting status and phase as NULL. This way the
method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index.
• transition – Transition parameter.
• status – Status response parameter.
• phase – Pointer to the new Key Refresh phase. Will return the actual Key
  Refresh phase after updating.
Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_beacon_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
```

Set the target node's network beacon state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New network beacon state, should be one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED`.
- `status` – Status response parameter. Returns one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED` on success.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_ttl_get(uint16_t net_idx, uint16_t addr, uint8_t *ttl)
```

Get the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `ttl` – TTL response buffer.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_ttl_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *ttl)
```

Set the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New Time To Live value.
- `ttl` – TTL response buffer.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_friend_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```

Get the target node's Friend feature status.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
• **addr** – Target node address.

• **status** – Status response parameter. Returns one of `BT_MESH_FRIEND_DISABLED`, `BT_MESH_FRIEND_ENABLED` or `BT_MESH_FRIEND_NOT_SUPPORTED` on success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_friend_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
```

Set the target node's Friend feature state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **val** – New Friend feature state. Should be one of `BT_MESH_FRIEND_DISABLED` or `BT_MESH_FRIEND_ENABLED`.

• **status** – Status response parameter. Returns one of `BT_MESH_FRIEND_DISABLED`, `BT_MESH_FRIEND_ENABLED` or `BT_MESH_FRIEND_NOT_SUPPORTED` on success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_gatt_proxy_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```

Get the target node's Proxy feature state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **status** – Status response parameter. Returns one of `BT_MESH_GATT_PROXY_DISABLED`, `BT_MESH_GATT_PROXY_ENABLED` or `BT_MESH_GATT_PROXY_NOT_SUPPORTED` on success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_gatt_proxy_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
```

Set the target node's Proxy feature state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **val** – New Proxy feature state. Must be one of `BT_MESH_GATT_PROXY_DISABLED` or `BT_MESH_GATT_PROXY_ENABLED`.

• **status** – Status response parameter. Returns one of `BT_MESH_GATT_PROXY_DISABLED`, `BT_MESH_GATT_PROXY_ENABLED` or `BT_MESH_GATT_PROXY_NOT_SUPPORTED` on success.
Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_net_transmit_get(uint16_t net_idx, uint16_t addr, uint8_t *transmit)
```
Get the target node's network_transmit state.

This method can be used asynchronously by setting `transmit` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_net_transmit_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *transmit)
```
Set the target node's network transmit parameters.

This method can be used asynchronously by setting `transmit` as NULL. This way the method will not wait for response and will return immediately after sending the command.

See also:
`BT_MESH_TRANSMIT`.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New encoded network transmit parameters.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_relay_get(uint16_t net_idx, uint16_t addr, uint8_t *status, uint8_t *transmit)
```
Get the target node's Relay feature state.

This method can be used asynchronously by setting `status` and `transmit` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `status` – Status response parameter. Returns one of `BT_MESH_RELAY_DISABLED`, `BT_MESH_RELAY_ENABLED` or `BT_MESH_RELAY_NOT_SUPPORTED` on success.
Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_relay_set(uint16_t net_idx, uint16_t addr, uint8_t new_relay, uint8_t new_transmit, uint8_t *status, uint8_t *transmit)

Set the target node's Relay parameters.

This method can be used asynchronously by setting status and transmit as NULL. This way the method will not wait for response and will return immediately after sending the command.

See also:
BT_MESH_TRANSMIT.

Parameters
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **new_relay** – New relay state. Must be one of BT_MESH_RELAY_DISABLED or BT_MESH_RELAY_ENABLED.
- **new_transmit** – New encoded relay transmit parameters.
- **status** – Status response parameter. Returns one of BT_MESH_RELAY_DISABLED, BT_MESH_RELAY_ENABLED or BT_MESH_RELAY_NOT_SUPPORTED on success.
- **transmit** – Transmit response parameter. Returns the encoded relay transmission parameters on success. Decoded with BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_net_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, const uint8_t net_key[16], uint8_t *status)

Add a network key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **key_net_idx** – Network key index.
- **net_key** – Network key.
- **status** – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_net_key_get(uint16_t net_idx, uint16_t addr, uint16_t *keys, size_t *key_cnt)

Get a list of the target node's network key indexes.

This method can be used asynchronously by setting keys or key_cnt as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **keys** – Net key index list response parameter. Will be filled with all the returned network key indexes it can fill.
• **key_cnt** – Net key index list length. Should be set to the capacity of the **keys** list when calling. Will return the number of returned network key indexes upon success.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_net_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status)
```

Delete a network key from the target node.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **key_net_idx** – Network key index.
• **status** – Status response parameter.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_app_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)
```

Add an application key to the target node.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **key_net_idx** – Network key index the application key belongs to.
• **key_app_idx** – Application key index.
• **app_key** – Application key.
• **status** – Status response parameter.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_app_key_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint16_t *keys, size_t *key_cnt)
```

Get a list of the target node’s application key indexes for a specific network key.

This method can be used asynchronously by setting **status** and (**keys** or **key_cnt**) as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **key_net_idx** – Network key index to request the app key indexes of.
• **status** – Status response parameter.

• **keys** – App key index list response parameter. Will be filled with all the returned application key indexes it can fill.

• **key_cnt** – App key index list length. Should be set to the capacity of the **keys** list when calling. Will return the number of returned application key indexes upon success.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_app_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, uint8_t *status)
```

Delete an application key from the target node.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **key_net_idx** – Network key index the application key belongs to.

• **key_app_idx** – Application key index.

• **status** – Status response parameter.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_app_bind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)
```

Bind an application to a SIG model on the target node.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **elem_addr** – Element address the model is in.

• **mod_app_idx** – Application index to bind.

• **mod_id** – Model ID.

• **status** – Status response parameter.

### Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_app_unbind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)
```

Unbind an application from a SIG model on the target node.

This method can be used asynchronously by setting **status** as NULL. This way the method will not wait for response and will return immediately after sending the command.

### Parameters
• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to unbind.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_app_bind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                 uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid,
                                 uint8_t *status)

Bind an application to a vendor model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to bind.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_app_unbind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                   uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid,
                                   uint8_t *status)

Unbind an application from a vendor model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to unbind.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_app_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                            uint16_t mod_id, uint8_t *status, uint16_t *apps, size_t *app_cnt)

Get a list of all applications bound to a SIG model on the target node.
This method can be used asynchronously by setting status and (apps or app_cnt) as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `status` – Status response parameter.
- `apps` – App index list response parameter. Will be filled with all the returned application key indexes it can fill.
- `app_cnt` – App index list length. Should be set to the capacity of the apps list when calling. Will return the number of returned application key indexes upon success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_app_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                 uint16_t mod_id, uint16_t cid, uint8_t *status,
                                 uint16_t *apps, size_t *app_cnt)
```

Get a list of all applications bound to a vendor model on the target node.

This method can be used asynchronously by setting status and (apps or app_cnt) as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.
- `apps` – App index list response parameter. Will be filled with all the returned application key indexes it can fill.
- `app_cnt` – App index list length. Should be set to the capacity of the apps list when calling. Will return the number of returned application key indexes upon success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_pub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                            uint16_t mod_id, struct bt_mesh_cfg_mod_pub *pub, uint8_t *status)
```

Get publish parameters for a SIG model on the target node.

This method can be used asynchronously by setting status and pub as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• pub – Publication parameter return buffer.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_pub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                 uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_mod_pub
                                 *pub, uint8_t *status)

Get publish parameters for a vendor model on the target node.

This method can be used asynchronously by setting status and pub as NULL. This way the
method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• cid – Company ID of the model.
• pub – Publication parameter return buffer.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_pub_set(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t
mod_id, struct bt_mesh_cfg_mod_pub *pub, uint8_t *status)

Set publish parameters for a SIG model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

pub shall not be NULL.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• pub – Publication parameters.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_pub_set_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                 uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_mod_pub
                                 *pub, uint8_t *status)
Set publish parameters for a vendor model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

d pub shall not be NULL.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- elem_addr – Element address the model is in.
- mod_id – Model ID.
- cid – Company ID of the model.
- pub – Publication parameters.
- status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_sub_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)

Add a group address to a SIG model's subscription list.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- elem_addr – Element address the model is in.
- sub_addr – Group address to add to the subscription list.
- mod_id – Model ID.
- status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_sub_add_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status)

Add a group address to a vendor model's subscription list.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- elem_addr – Element address the model is in.
- sub_addr – Group address to add to the subscription list.
- mod_id – Model ID.
- cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_sub_del(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint8_t *status)

Delete a group address in a SIG model’s subscription list.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• sub_addr – Group address to add to the subscription list.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_sub_del_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)

Delete a group address in a vendor model’s subscription list.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• sub_addr – Group address to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_mod_sub_overwrite(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint8_t *status)

Overwrite all addresses in a SIG model’s subscription list with a group address.

Deletes all subscriptions in the model’s subscription list, and adds a single group address instead.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• **elem_addr** – Element address the model is in.
• **sub_addr** – Group address to add to the subscription list.
• **mod_id** – Model ID.
• **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_overwrite_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                       uint16_t sub_addr, uint16_t mod_id, uint16_t cid,
                                       uint8_t *status)
```

Overwrite all addresses in a vendor model’s subscription list with a group address.

Deletes all subscriptions in the model’s subscription list, and adds a single group address instead.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **elem_addr** – Element address the model is in.
• **sub_addr** – Group address to add to the subscription list.
• **mod_id** – Model ID.
• **cid** – Company ID of the model.
• **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_va_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, const
                                uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr,
                                uint8_t *status)
```

Add a virtual address to a SIG model’s subscription list.

This method can be used asynchronously by setting `status` and `virt_addr` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **elem_addr** – Element address the model is in.
• **label** – Virtual address label to add to the subscription list.
• **mod_id** – Model ID.
• **virt_addr** – Virtual address response parameter.
• **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.
Add a virtual address to a vendor model’s subscription list.
This method can be used asynchronously by setting \texttt{status} and \texttt{virt\_addr} as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- \texttt{net\_idx} – Network index to encrypt with.
- \texttt{addr} – Target node address.
- \texttt{elem\_addr} – Element address the model is in.
- \texttt{label} – Virtual address label to add to the subscription list.
- \texttt{mod\_id} – Model ID.
- \texttt{cid} – Company ID of the model.
- \texttt{virt\_addr} – Virtual address response parameter.
- \texttt{status} – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

Delete a virtual address in a SIG model’s subscription list.
This method can be used asynchronously by setting \texttt{status} and \texttt{virt\_addr} as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- \texttt{net\_idx} – Network index to encrypt with.
- \texttt{addr} – Target node address.
- \texttt{elem\_addr} – Element address the model is in.
- \texttt{label} – Virtual address parameter to add to the subscription list.
- \texttt{mod\_id} – Model ID.
- \texttt{virt\_addr} – Virtual address response parameter.
- \texttt{status} – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

Delete a virtual address in a vendor model’s subscription list.
This method can be used asynchronously by setting \texttt{status} and \texttt{virt\_addr} as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- \texttt{net\_idx} – Network index to encrypt with.
- \texttt{addr} – Target node address.
- \texttt{elem\_addr} – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_va_overwrite(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                      const uint8_t label[16], uint16_t mod_id, uint16_t
                                      *virt_addr, uint8_t *status)
```

Overwrite all addresses in a SIG model’s subscription list with a virtual address.
Deletes all subscriptions in the model’s subscription list, and adds a single group address instead.
This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_va_overwrite_vnd(uint16_t net_idx, uint16_t addr, uint16_t
                                         elem_addr, const uint8_t label[16], uint16_t
                                         mod_id, uint16_t cid, uint16_t *virt_addr, uint8_t
                                         *status)
```

Overwrite all addresses in a vendor model’s subscription list with a virtual address.
Deletes all subscriptions in the model’s subscription list, and adds a single group address instead.
This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.
Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status, uint16_t *subs, size_t *sub_cnt)
```

Get the subscription list of a SIG model on the target node.

This method can be used asynchronously by setting `status` and (`subs` or `sub_cnt`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `status` – Status response parameter.
- `subs` – Subscription list response parameter. Will be filled with all the returned subscriptions it can fill.
- `sub_cnt` – Subscription list element count. Should be set to the capacity of the subs list when calling. Will return the number of returned subscriptions upon success.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_mod_sub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status, uint16_t *subs, size_t *sub_cnt)
```

Get the subscription list of a vendor model on the target node.

This method can be used asynchronously by setting `status` and (`subs` or `sub_cnt`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.
- `subs` – Subscription list response parameter. Will be filled with all the returned subscriptions it can fill.
- `sub_cnt` – Subscription list element count. Should be set to the capacity of the subs list when calling. Will return the number of returned subscriptions upon success.

Returns
0 on success, or (negative) error code on failure.
int bt_mesh_cfg_hb_sub_set(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_hb_sub *sub, uint8_t *status)
Set the target node's Heartbeat subscription parameters.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.
sub shall not be null.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• sub – New Heartbeat subscription parameters.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_hb_sub_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_hb_sub *sub, uint8_t *status)
Get the target node's Heartbeat subscription parameters.
This method can be used asynchronously by setting status and sub as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• sub – Heartbeat subscription parameter return buffer.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_hb_pub_set(uint16_t net_idx, uint16_t addr, const struct bt_mesh_cfg_hb_pub *pub, uint8_t *status)
Set the target node's Heartbeat publication parameters.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.
pub shall not be NULL;

Note: The target node must already have received the specified network key.
Get the target node's Heartbeat publication parameters.

This method can be used asynchronously by setting `status` and `pub` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `pub` – Heartbeat publication parameter return buffer.
- `status` – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

Delete all group addresses in a SIG model's subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `status` – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

Delete all group addresses in a vendor model's subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_net_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, const uint8_t net_key[16], uint8_t *status)

0 on success, or (negative) error code on failure.
Update a network key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- net_idx – Network index to encrypt with.
- addr – Target node address.
- key_net_idx – Network key index.
- net_key – Network key.
- status – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_app_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
                                uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)
```

Update an application key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- net_idx – Network index to encrypt with.
- addr – Target node address.
- key_net_idx – Network key index the application key belongs to.
- key_app_idx – Application key index.
- app_key – Application key.
- status – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_node_identity_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
                                  uint8_t new_identity, uint8_t *status, uint8_t *identity)
```

Set the Node Identity parameters.

This method can be used asynchronously by setting status and identity as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- net_idx – Network index to encrypt with.
- addr – Target node address.
- new_identity – New identity state. Must be one of `BT_MESH_NODE_IDENTITY_STOPPED` or `BT_MESH_NODE_IDENTITY_RUNNING`
- key_net_idx – Network key index the application key belongs to.
- status – Status response parameter.
- identity – Identity response parameter.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_node_identity_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx,
int8_t *status, int8_t *identity)

Get the Node Identity parameters.
This method can be used asynchronously by setting status and identity as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- key_net_idx – Network key index the application key belongs to.
- status – Status response parameter.
- identity – Identity response parameter. Must be one of BT_MESH_NODE_IDENTITY_STOPPED or BT_MESH_NODE_IDENTITY_RUNNING

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_lpn_timeout_get(uint16_t net_idx, uint16_t addr, uint16_t unicast_addr,
int32_t *polltimeout)

Get the Low Power Node Polltimeout parameters.
This method can be used asynchronously by setting polltimeout as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- unicast_addr – LPN unicast address.
- polltimeout – Poll timeout response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_node_reset(uint16_t net_idx, uint16_t addr, bool *status)

Reset the target node and remove it from the network.

Parameters

- net_idx – Network index to encrypt with.
- addr – Target node address.
- status – Status response parameter

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_comp_data_get(uint16_t net_idx, uint16_t addr, uint8_t page, uint8_t *rsp, struct net_buf_simple *comp)

Get the target node’s composition data.
If the other device does not have the given composition data page, it will return the largest page number it supports that is less than the requested page index. The actual page the device responds with is returned in rsp.
This method can be used asynchronously by setting rsp and comp as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
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- net_idx – Network index to encrypt with.
- addr – Target node address.
- page – Composition data page, or 0xff to request the first available page.
- rsp – Return parameter for the returned page number, or NULL.
- comp – Composition data buffer to fill.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_beacon_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```
Get the target node's network beacon state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- net_idx – Network index to encrypt with.
- addr – Target node address.
- status – Status response parameter, returns one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED` on success.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_krp_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint8_t *phase)
```
Get the target node's network key refresh phase state.

This method can be used asynchronously by setting `status` and `phase` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- net_idx – Network index to encrypt with.
- addr – Target node address.
- key_net_idx – Network key index.
- status – Status response parameter.
- phase – Pointer to the Key Refresh variable to fill.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_krp_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t transition, uint8_t *status, uint8_t *phase)
```
Set the target node's network key refresh phase parameters.

This method can be used asynchronously by setting `status` and `phase` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- net_idx – Network index to encrypt with.
- addr – Target node address.
- key_net_idx – Network key index.
- transition – Transition parameter.
- status – Status response parameter.
• phase – Pointer to the new Key Refresh phase. Will return the actual Key Refresh phase after updating.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_beacon_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
```

Set the target node's network beacon state.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New network beacon state, should be one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED`.
- `status` – Status response parameter. Returns one of `BT_MESH_BEACON_DISABLED` or `BT_MESH_BEACON_ENABLED` on success.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_ttl_get(uint16_t net_idx, uint16_t addr, uint8_t *ttl)
```

Get the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `ttl` – TTL response buffer.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_ttl_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *ttl)
```

Set the target node's Time To Live value.

This method can be used asynchronously by setting `ttl` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `val` – New Time To Live value.
- `ttl` – TTL response buffer.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_friend_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
```

Get the target node's Friend feature status.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
• net_idx – Network index to encrypt with.
• addr – Target node address.
• status – Status response parameter. Returns one of
  BT_MESH_FRIEND_DISABLED, BT_MESH_FRIEND_ENABLED or
  BT_MESH_FRIEND_NOT_SUPPORTED on success.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_friend_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
Set the target node’s Friend feature state.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• val – New Friend feature state. Should be one of
  BT_MESH_FRIEND_DISABLED or BT_MESH_FRIEND_ENABLED.
• status – Status response parameter. Returns one of
  BT_MESH_FRIEND_DISABLED, BT_MESH_FRIEND_ENABLED or
  BT_MESH_FRIEND_NOT_SUPPORTED on success.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_gatt_proxy_get(uint16_t net_idx, uint16_t addr, uint8_t *status)
Get the target node’s Proxy feature state.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• status – Status response parameter. Returns one of
  BT_MESH_GATT_PROXY_DISABLED, BT_MESH_GATT_PROXY_ENABLED or
  BT_MESH_GATT_PROXY_NOT_SUPPORTED on success.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_gatt_proxy_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *status)
Set the target node’s Proxy feature state.

This method can be used asynchronously by setting status as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• val – New Proxy feature state. Must be one of
  BT_MESH_GATT_PROXY_DISABLED or BT_MESH_GATT_PROXY_ENABLED.
• status – Status response parameter. Returns one of
  BT_MESH_GATT_PROXY_DISABLED, BT_MESH_GATT_PROXY_ENABLED
  or BT_MESH_GATT_PROXY_NOT_SUPPORTED on success.

Returns
  0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_transmit_get(uint16_t net_idx, uint16_t addr, uint8_t *transmit)
Get the target node's network transmit state.
This method can be used asynchronously by setting transmit as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
  • net_idx – Network index to encrypt with.
  • addr – Target node address.
  • transmit – Network transmit response parameter. Returns the en-
    coded network transmission parameters on success. Decoded with
    BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT.

Returns
  0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_transmit_set(uint16_t net_idx, uint16_t addr, uint8_t val, uint8_t *
  transmit)
Set the target node's network transmit parameters.
This method can be used asynchronously by setting transmit as NULL. This way the method
will not wait for response and will return immediately after sending the command.

See also:
  BT_MESH_TRANSMIT.

Parameters
  • net_idx – Network index to encrypt with.
  • addr – Target node address.
  • val – New encoded network transmit parameters.
  • transmit – Network transmit response parameter. Returns the en-
    coded network transmission parameters on success. Decoded with
    BT_MESH_TRANSMIT_COUNT and BT_MESH_TRANSMIT_INT.

Returns
  0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_relay_get(uint16_t net_idx, uint16_t addr, uint8_t *
  status, uint8_t *
  transmit)
Get the target node's Relay feature state.
This method can be used asynchronously by setting status and transmit as NULL. This way the method
will not wait for response and will return immediately after sending the command.

Parameters
  • net_idx – Network index to encrypt with.
  • addr – Target node address.
• **status** – Status response parameter. Returns one of `BT_MESH_RELAY_DISABLED`, `BT_MESH_RELAY_ENABLED` or `BT_MESH_RELAY_NOT_SUPPORTED` on success.

• **transmit** – Transmit response parameter. Returns the encoded relay transmission parameters on success. Decoded with `BT_MESH_TRANSMIT_COUNT` and `BT_MESH_TRANSMIT_INT`.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_relay_set(uint16_t net_idx, uint16_t addr, uint8_t new_relay, uint8_t new_transmit, uint8_t *status, uint8_t *transmit)
```

Set the target node's Relay parameters.

This method can be used asynchronously by setting `status` and `transmit` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**See also:**

`BT_MESH_TRANSMIT`.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **new_relay** – New relay state. Must be one of `BT_MESH_RELAY_DISABLED` or `BT_MESH_RELAY_ENABLED`.
- **new_transmit** – New encoded relay transmit parameters.
- **status** – Status response parameter. Returns one of `BT_MESH_RELAY_DISABLED`, `BT_MESH_RELAY_ENABLED` or `BT_MESH_RELAY_NOT_SUPPORTED` on success.
- **transmit** – Transmit response parameter. Returns the encoded relay transmission parameters on success. Decoded with `BT_MESH_TRANSMIT_COUNT` and `BT_MESH_TRANSMIT_INT`.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_net_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, const uint8_t net_key[16], uint8_t *status)
```

Add a network key to the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **key_net_idx** – Network key index.
- **net_key** – Network key.
- **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_net_key_get(uint16_t net_idx, uint16_t addr, uint16_t *keys, size_t *key_cnt)

Get a list of the target node’s network key indexes. This method can be used asynchronously by setting keys or key_cnt as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• keys – Net key index list response parameter. Will be filled with all the returned network key indexes it can fill.
• key_cnt – Net key index list length. Should be set to the capacity of the keys list when calling. Will return the number of returned network key indexes upon success.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status)

Delete a network key from the target node. This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_app_key_add(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)

Add an application key to the target node. This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index the application key belongs to.
• key_app_idx – Application key index.
• app_key – Application key.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_app_key_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, 
uint8_t *status, uint16_t *keys, size_t *key_cnt)

Get a list of the target node’s application key indexes for a specific network key.

This method can be used asynchronously by setting status and (keys or key_cnt) as NULL. 
This way the method will not wait for response and will return immediately after sending the 
command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index to request the app key indexes of.
• status – Status response parameter.
• keys – App key index list response parameter. Will be filled with all the re-
turned application key indexes it can fill.
• key_cnt – App key index list length. Should be set to the capacity of the keys 
list when calling. Will return the number of returned application key indexes 
upon success.

Returns
 0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_app_key_del(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, 
uint16_t key_app_idx, uint8_t *status)

Delete an application key from the target node.

This method can be used asynchronously by setting status as NULL. This way the method 
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index the application key belongs to.
• key_app_idx – Application key index.
• status – Status response parameter.

Returns
 0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_bind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, 
uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)

Bind an application to a SIG model on the target node.

This method can be used asynchronously by setting status as NULL. This way the method 
will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to bind.
• mod_id – Model ID.
• status – Status response parameter.
Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_unbind(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint8_t *status)

Unbind an application from a SIG model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to unbind.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_bind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid, uint8_t *status)

Bind an application to a vendor model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_app_idx – Application index to bind.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_app_unbind_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_app_idx, uint16_t mod_id, uint16_t cid, uint8_t *status)

Unbind an application from a vendor model on the target node.
This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• `mod_app_idx` – Application index to unbind.
• `mod_id` – Model ID.
• `cid` – Company ID of the model.
• `status` – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_app_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status, uint16_t *apps, size_t *app_cnt)
```

Get a list of all applications bound to a SIG model on the target node.

This method can be used asynchronously by setting `status` and (`apps` or `app_cnt`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• `net_idx` – Network index to encrypt with.
• `addr` – Target node address.
• `elem_addr` – Element address the model is in.
• `mod_id` – Model ID.
• `status` – Status response parameter.
• `apps` – App index list response parameter. Will be filled with all the returned application key indexes it can fill.
• `app_cnt` – App index list length. Should be set to the capacity of the `apps` list when calling. Will return the number of returned application key indexes upon success.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_app_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint16_t cid, uint8_t *status, uint16_t *apps, size_t *app_cnt)
```

Get a list of all applications bound to a vendor model on the target node.

This method can be used asynchronously by setting `status` and (`apps` or `app_cnt`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• `net_idx` – Network index to encrypt with.
• `addr` – Target node address.
• `elem_addr` – Element address the model is in.
• `mod_id` – Model ID.
• `cid` – Company ID of the model.
• `status` – Status response parameter.
• `apps` – App index list response parameter. Will be filled with all the returned application key indexes it can fill.
• `app_cnt` – App index list length. Should be set to the capacity of the `apps` list when calling. Will return the number of returned application key indexes upon success.
**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t mod_id, struct bt_mesh_cfg_cli_mod_pub *pub,
                                uint8_t *status)
```

Get publish parameters for a SIG model on the target node.

This method can be used asynchronously by setting `status` and `pub` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `pub` – Publication parameter return buffer.
- `status` – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                    uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_cli_mod_pub *pub,
                                    uint8_t *status)
```

Get publish parameters for a vendor model on the target node.

This method can be used asynchronously by setting `status` and `pub` as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `pub` – Publication parameter return buffer.
- `status` – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_set(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t mod_id, struct bt_mesh_cfg_cli_mod_pub *pub,
                                uint8_t *status)
```

Set publish parameters for a SIG model on the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

`pub` shall not be NULL.

**Parameters**

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
elem_addr – Element address the model is in.
• mod_id – Model ID.
• pub – Publication parameters.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_pub_set_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                  uint16_t mod_id, uint16_t cid, struct bt_mesh_cfg_cli_mod_pub *pub, uint8_t *status)
```

Set publish parameters for a vendor model on the target node.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

`pub` shall not be NULL.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• cid – Company ID of the model.
• pub – Publication parameters.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t sub_addr, uint16_t mod_id, uint8_t *status)
```

Add a group address to a SIG model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• sub_addr – Group address to add to the subscription list.
• mod_id – Model ID.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_add_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                    uint16_t sub_addr, uint16_t mod_id, uint16_t cid,
                                    uint8_t *status)
```

Add a group address to a vendor model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.
Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `sub_addr` – Group address to add to the subscription list.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_del(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t sub_addr, uint16_t mod_id, uint8_t *status)
```

Delete a group address in a SIG model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `sub_addr` – Group address to add to the subscription list.
- `mod_id` – Model ID.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_mod_sub_del_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                   uint16_t sub_addr, uint16_t mod_id, uint16_t cid,
                                   uint8_t *status)
```

Delete a group address in a vendor model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `sub_addr` – Group address to add to the subscription list.
- `mod_id` – Model ID.
- `cid` – Company ID of the model.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.
int bt_mesh_cfg_cli_mod_sub_overwrite(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint8_t *status)

Overwrite all addresses in a SIG model's subscription list with a group address.

Deletes all subscriptions in the model's subscription list, and adds a single group address instead.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **sub_addr** – Group address to add to the subscription list.
- **mod_id** – Model ID.
- **status** – Status response parameter.

**Returns**
- 0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_overwrite_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t sub_addr, uint16_t mod_id, uint16_t cid, uint8_t *status)

Overwrite all addresses in a vendor model's subscription list with a group address.

Deletes all subscriptions in the model's subscription list, and adds a single group address instead.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **sub_addr** – Group address to add to the subscription list.
- **mod_id** – Model ID.
- **cid** – Company ID of the model.
- **status** – Status response parameter.

**Returns**
- 0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_va_add(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, const uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr, uint8_t *status)

Add a virtual address to a SIG model's subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_va_add_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
        const uint8_t label[16], uint16_t mod_id, uint16_t cid, uint16_t *virt_addr, uint8_t *status)

Add a virtual address to a vendor model’s subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way
the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_mod_sub_va_del(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
        const uint8_t label[16], uint16_t mod_id, uint16_t *virt_addr, uint8_t *status)

Delete a virtual address in a SIG model’s subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way
the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address parameter to add to the subscription list.
• mod_id – Model ID.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.
Delete a virtual address in a vendor model’s subscription list.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **label** – Virtual address label to add to the subscription list.
- **mod_id** – Model ID.
- **cid** – Company ID of the model.
- **virt_addr** – Virtual address response parameter.
- **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

Overwrite all addresses in a SIG model’s subscription list with a virtual address.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

- **net_idx** – Network index to encrypt with.
- **addr** – Target node address.
- **elem_addr** – Element address the model is in.
- **label** – Virtual address label to add to the subscription list.
- **mod_id** – Model ID.
- **virt_addr** – Virtual address response parameter.
- **status** – Status response parameter.

**Returns**

0 on success, or (negative) error code on failure.

Overwrite all addresses in a vendor model’s subscription list with a virtual address.

This method can be used asynchronously by setting status and virt_addr as NULL. This way the method will not wait for response and will return immediately after sending the command.
Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• label – Virtual address label to add to the subscription list.
• mod_id – Model ID.
• cid – Company ID of the model.
• virt_addr – Virtual address response parameter.
• status – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_get(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                uint16_t mod_id, uint8_t *status, uint16_t *subs, size_t *sub_cnt)
```

Get the subscription list of a SIG model on the target node.

This method can be used asynchronously by setting status and (subs or sub_cnt) as NULL.
This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• status – Status response parameter.
• subs – Subscription list response parameter. Will be filled with all the returned
  subscriptions it can fill.
• sub_cnt – Subscription list element count. Should be set to the capacity of the
  subs list when calling. Will return the number of returned subscriptions upon
  success.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_get_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr,
                                    uint16_t mod_id, uint8_t *status, uint16_t *subs, size_t *sub_cnt)
```

Get the subscription list of a vendor model on the target node.

This method can be used asynchronously by setting status and (subs or sub_cnt) as NULL.
This way the method will not wait for response and will return immediately after sending the command.

Parameters

• net_idx – Network index to encrypt with.
• addr – Target node address.
• elem_addr – Element address the model is in.
• mod_id – Model ID.
• **cid** – Company ID of the model.
• **status** – Status response parameter.
• **subs** – Subscription list response parameter. Will be filled with all the returned subscriptions it can fill.
• **sub_cnt** – Subscription list element count. Should be set to the capacity of the subs list when calling. Will return the number of returned subscriptions upon success.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_hb_sub_set(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_cli_hb_sub *sub, uint8_t *status)
```

Set the target node’s Heartbeat subscription parameters.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

sub shall not be null.

**Parameters**
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **sub** – New Heartbeat subscription parameters.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_hb_sub_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_cli_hb_sub *sub, uint8_t *status)
```

Get the target node’s Heartbeat subscription parameters.

This method can be used asynchronously by setting status and sub as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**
• **net_idx** – Network index to encrypt with.
• **addr** – Target node address.
• **sub** – Heartbeat subscription parameter return buffer.
• **status** – Status response parameter.

**Returns**
0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_hb_pub_set(uint16_t net_idx, uint16_t addr, const struct bt_mesh_cfg_cli_hb_pub *pub, uint8_t *status)
```

Set the target node’s Heartbeat publication parameters.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

pub shall not be NULL;

**Note:** The target node must already have received the specified network key.
Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `pub` – New Heartbeat publication parameters.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_hb_pub_get(uint16_t net_idx, uint16_t addr, struct bt_mesh_cfg_cli_hb_pub *pub, uint8_t *status)
```

Get the target node’s Heartbeat publication parameters.

This method can be used asynchronously by setting `status` and `pub` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `pub` – Heartbeat publication parameter return buffer.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_del_all(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t mod_id, uint8_t *status)
```

Delete all group addresses in a SIG model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
- `mod_id` – Model ID.
- `status` – Status response parameter.

Returns

0 on success, or (negative) error code on failure.

```
int bt_mesh_cfg_cli_mod_sub_del_all_vnd(uint16_t net_idx, uint16_t addr, uint16_t elem_addr, uint16_t elem_mod_id, uint16_t mod_id, uint16_t cid, uint8_t *status)
```

Delete all group addresses in a vendor model’s subscription list.

This method can be used asynchronously by setting `status` as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters

- `net_idx` – Network index to encrypt with.
- `addr` – Target node address.
- `elem_addr` – Element address the model is in.
• mod_id – Model ID.
• cid – Company ID of the model.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_net_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, const uint8_t net_key[16], uint8_t *status)

Update a network key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index.
• net_key – Network key.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_app_key_update(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint16_t key_app_idx, const uint8_t app_key[16], uint8_t *status)

Update an application key to the target node.

This method can be used asynchronously by setting status as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• key_net_idx – Network key index the application key belongs to.
• key_app_idx – Application key index.
• app_key – Application key.
• status – Status response parameter.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_cfg_cli_node_identity_set(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t new_identity, uint8_t *status, uint8_t *identity)

Set the Node Identity parameters.

This method can be used asynchronously by setting status and identity as NULL. This way the method will not wait for response and will return immediately after sending the command.

Parameters
• net_idx – Network index to encrypt with.
• addr – Target node address.
• **new_identity** – New identity state. Must be one of \texttt{BT_MESH_NODE_IDENTITY_STOPPED} or \texttt{BT_MESH_NODE_IDENTITY_RUNNING}.

• **key_net_idx** – Network key index the application key belongs to.

• **status** – Status response parameter.

• **identity** – Identity response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_node_identity_get(uint16_t net_idx, uint16_t addr, uint16_t key_net_idx, uint8_t *status, uint8_t *identity)
```

Get the Node Identity parameters.

This method can be used asynchronously by setting \texttt{status} and \texttt{identity} as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **key_net_idx** – Network key index the application key belongs to.

• **status** – Status response parameter.

• **identity** – Identity response parameter. Must be one of \texttt{BT_MESH_NODE_IDENTITY_STOPPED} or \texttt{BT_MESH_NODE_IDENTITY_RUNNING}.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_cfg_cli_lpn_timeout_get(uint16_t net_idx, uint16_t addr, uint16_t unicast_addr, int32_t *polltimeout)
```

Get the Low Power Node Polltimeout parameters.

This method can be used asynchronously by setting \texttt{polltimeout} as NULL. This way the method will not wait for response and will return immediately after sending the command.

**Parameters**

• **net_idx** – Network index to encrypt with.

• **addr** – Target node address.

• **unicast_addr** – LPN unicast address.

• **polltimeout** – Poll timeout response parameter.

**Returns**

0 on success, or (negative) error code on failure.

```c
int32_t bt_mesh_cfg_cli_timeout_get(void)
```

Get the current transmission timeout value.

**Returns**

The configured transmission timeout in milliseconds.

```c
void bt_mesh_cfg_cli_timeout_set(int32_t timeout)
```

Set the transmission timeout value.

**Parameters**

• **timeout** – The new transmission timeout.
int bt_mesh_comp_p0_get(struct bt_mesh_comp_p0 *comp, struct net_buf_simple *buf)

Create a composition data page 0 representation from a buffer.

The composition data page object will take ownership over the buffer, which should not be manipulated directly after this call.

This function can be used in combination with `bt_mesh_cfg_cli_comp_data_get` to read out composition data page 0 from other devices:

```c
NET_BUF_SIMPLE_DEFINE(buf, BT_MESH_RX_SDU_MAX);
struct bt_mesh_comp_p0 comp;
err = bt_mesh_cfg_cli_comp_data_get(net_idx, addr, 0, &page, &buf);
if (!err) {
    bt_mesh_comp_p0_get(&comp, &buf);
}
```

**Parameters**
- `buf` – Network buffer containing composition data.
- `comp` – Composition data structure to fill.

**Returns**
0 on success, or (negative) error code on failure.

```c
struct bt_mesh_comp_p0_elem *bt_mesh_comp_p0_elem_pull(const struct bt_mesh_comp_p0 *comp, struct bt_mesh_comp_p0_elem *elem)
```

Pull a composition data page 0 element from a composition data page 0 instance.

Each call to this function will pull out a new element from the composition data page, until all elements have been pulled.

**Parameters**
- `comp` – Composition data page
- `elem` – Element to fill.

**Returns**
A pointer to `elem` on success, or NULL if no more elements could be pulled.

```c
uint16_t bt_mesh_comp_p0_elem_mod(struct bt_mesh_comp_p0_elem *elem, int idx)
```

Get a SIG model from the given composition data page 0 element.

**Parameters**
- `elem` – Element to read the model from.
- `idx` – Index of the SIG model to read.

**Returns**
The Model ID of the SIG model at the given index, or 0xffff if the index is out of bounds.

```c
struct bt_mesh_mod_id_vnd bt_mesh_comp_p0_elem_mod_vnd(struct bt_mesh_comp_p0_elem *elem, int idx)
```

Get a vendor model from the given composition data page 0 element.

**Parameters**
- `elem` – Element to read the model from.
- `idx` – Index of the vendor model to read.
Returns

The model ID of the vendor model at the given index, or {0xffff, 0xffff} if the index is out of bounds.

```c
struct bt_mesh_cfg_cli_cb
#include <cfg_cli.h> Mesh Configuration Client Status messages callback

Public Members

void (*mod_sub_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t sub_addr, uint32_t mod_id)
Optional callback for Model Sub Status messages.
Handles received Model Sub Status messages from a server.

Param cli  
Client that received the status message.

Param addr  
Address of the sender.

Param status  
Status Code for requesting message.

Param elem_addr  
The unicast address of the element.

Param sub_addr  
The sub address.

Param mod_id  
The model ID within the element.

void (*node_reset_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr)
Optional callback for Node Reset Status messages.
Handles received Node Reset Status messages from a server.

Param cli  
Client that received the status message.

Param addr  
Address of the sender.

void (*beacon_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
Optional callback for Beacon Status messages.
Handles received Beacon Status messages from a server.

Param cli  
Client that received the status message.

Param addr  
Address of the sender.

Param status  
Status Code for requesting message.

void (*ttl_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
Optional callback for Default TTL Status messages.
Handles received Default TTL Status messages from a server.

Param cli  
Client that received the status message.

Param addr  
Address of the sender.
Param status
   Status Code for requesting message.

void (*friend_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
Optional callback for Friend Status messages.
Handles received Friend Status messages from a server.
   Param cli
      Client that received the status message.
   Param addr
      Address of the sender.
   Param status
      Status Code for requesting message.

void (*gatt_proxy_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
Optional callback for GATT Proxy Status messages.
Handles received GATT Proxy Status messages from a server.
   Param cli
      Client that received the status message.
   Param addr
      Address of the sender.
   Param status
      Status Code for requesting message.

void (*network_transmit_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status)
Optional callback for Network Transmit Status messages.
Handles received Network Transmit Status messages from a server.
   Param cli
      Client that received the status message.
   Param addr
      Address of the sender.
   Param status
      Status Code for requesting message.

void (*relay_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint8_t transmit)
Optional callback for Relay Status messages.
Handles received Relay Status messages from a server.
   Param cli
      Client that received the status message.
   Param addr
      Address of the sender.
   Param status
      Status Code for requesting message.
   Param transmit
      The relay retransmit count and interval steps.

void (*net_key_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx)
Optional callback for NetKey Status messages.
Handles received NetKey Status messages from a server.
   Param cli
      Client that received the status message.
**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param net_idx**
The index of the NetKey.

```c
void (*app_key_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, uint16_t app_idx)
```
Optional callback for AppKey Status messages.
Handles received AppKey Status messages from a server.

**Param cli**
Client that received the status message.

**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param net_idx**
The index of the NetKey.

**Param app_idx**
The index of the AppKey.

```c
void (*mod_app_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t elem_addr, uint16_t app_idx, uint32_t mod_id)
```
Optional callback for Model App Status messages.
Handles received Model App Status messages from a server.

**Param cli**
Client that received the status message.

**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param elem_addr**
The unicast address of the element.

**Param app_idx**
The sub address.

**Param mod_id**
The model ID within the element.

```c
void (*node_identity_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint8_t status, uint16_t net_idx, uint8_t identity)
```
Optional callback for Node Identity Status messages.
Handles received Node Identity Status messages from a server.

**Param cli**
Client that received the status message.

**Param addr**
Address of the sender.

**Param status**
Status Code for requesting message.

**Param net_idx**
The index of the NetKey.

**Param identity**
The node identity state.

```c
void (*lpn_timeout_status)(struct bt_mesh_cfg_cli *cli, uint16_t addr, uint16_t elem_addr, uint32_t timeout)
```

Optional callback for LPN PollTimeout Status messages. Handles received LPN PollTimeout Status messages from a server.

- **Param cli**
  - Client that received the status message.
- **Param addr**
  - Address of the sender.
- **Param elem_addr**
  - The unicast address of the LPN.
- **Param timeout**
  - Current value of PollTimeout timer of the LPN.

```c
struct bt_mesh_cfgCli
  #include <cfg_cli.h> Mesh Configuration Client Model Context

Public Members

- struct bt_mesh_model *model
  - Composition data model entry pointer.
- const struct bt_mesh_cfg_cli_cb *cb
  - Optional callback for Mesh Configuration Client Status messages.

struct bt_mesh_cfg_mod_pub
  #include <cfg_cli.h> Model publication configuration parameters.

Public Members

- uint16_t addr
  - Publication destination address.
- const uint8_t *uuid
  - Virtual address UUID, or NULL if this is not a virtual address.
- uint16_t app_idx
  - Application index to publish with.
- bool cred_flag
  - Friendship credential flag.
- uint8_t ttl
  - Time To Live to publish with.
- uint8_t period
  - Encoded publish period.

See also:

- BT_MESH_PUB_PERIOD_100MS
- BT_MESH_PUB_PERIOD_SEC
- BT_MESH_PUB_PERIOD_10SEC
- BT_MESH_PUB_PERIOD_10MIN
```

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uint8_t transmit
    Encoded transmit parameters.

See also:
    BT_MESH_TRANSMIT

struct bt_mesh_cfg_cli_mod_pub
    #include <cfg_cli.h> Model publication configuration parameters.

Public Members

uint16_t addr
    Publication destination address.

const uint8_t *uuid
    Virtual address UUID, or NULL if this is not a virtual address.

uint16_t app_idx
    Application index to publish with.

bool cred_flag
    Friendship credential flag.

uint8_t ttl
    Time To Live to publish with.

uint8_t period
    Encoded publish period.

See also:
    BT_MESH_PUB_PERIOD_100MS, BT_MESH_PUB_PERIOD_SEC,
    BT_MESH_PUB_PERIOD_10SEC, BT_MESH_PUB_PERIOD_10MIN

uint8_t transmit
    Encoded transmit parameters.

See also:
    BT_MESH_TRANSMIT

struct bt_mesh_cfg_hb_sub
    #include <cfg_cli.h> Heartbeat subscription configuration parameters.

Public Members

uint16_t src
    Source address to receive Heartbeat messages from.
uint16_t dst
Destination address to receive Heartbeat messages on.

uint8_t period
Logarithmic subscription period to keep listening for. The decoded subscription period is
\((1 << (period - 1))\) seconds, or 0 seconds if period is 0.

uint8_t count
Logarithmic Heartbeat subscription receive count. The decoded Heartbeat count is \((1 << (count - 1))\) if count is between 1 and 0xfe, 0 if count is 0 and 0xffff if count is 0xff.
Ignored in Heartbeat subscription set.

uint8_t min
Minimum hops in received messages, ie the shortest registered path from the publishing
node to the subscribing node. A Heartbeat received from an immediate neighbor has hop
count = 1.
Ignored in Heartbeat subscription set.

uint8_t max
Maximum hops in received messages, ie the longest registered path from the publishing
node to the subscribing node. A Heartbeat received from an immediate neighbor has hop
count = 1.
Ignored in Heartbeat subscription set.

struct bt_mesh_cfg_cli hb_sub
#include <cfg_cli.h> Heartbeat subscription configuration parameters.

Public Members

uint16_t src
Source address to receive Heartbeat messages from.

uint16_t dst
Destination address to receive Heartbeat messages on.

uint8_t period
Logarithmic subscription period to keep listening for. The decoded subscription period is
\((1 << (period - 1))\) seconds, or 0 seconds if period is 0.

uint8_t count
Logarithmic Heartbeat subscription receive count. The decoded Heartbeat count is \((1 << (count - 1))\) if count is between 1 and 0xfe, 0 if count is 0 and 0xffff if count is 0xff.
Ignored in Heartbeat subscription set.

uint8_t min
Minimum hops in received messages, ie the shortest registered path from the publishing
node to the subscribing node. A Heartbeat received from an immediate neighbor has hop
count = 1.
Ignored in Heartbeat subscription set.
struct bt_mesh_cfg_hb_pub
#include <cfg_cli.h> Heartbeat publication configuration parameters.

Public Members

uint16_t dst
Heartbeat destination address.

uint8_t count
Logarithmic Heartbeat count. Decoded as (1 << (count - 1)) if count is between 1 and 0x11, 0 if count is 0, or “indefinitely” if count is 0xff.
When used in Heartbeat publication set, this parameter denotes the number of Heartbeat messages to send.
When returned from Heartbeat publication get, this parameter denotes the number of Heartbeat messages remaining to be sent.

uint8_t period
Logarithmic Heartbeat publication transmit interval in seconds. Decoded as (1 << (period - 1)) if period is between 1 and 0x11. If period is 0, Heartbeat publication is disabled.

uint8_t ttl
Publication message Time To Live value.

uint16_t feat
Bitmap of features that trigger Heartbeat publications. Legal values are BT_MESH_FEAT_RELAY, BT_MESH_FEAT_PROXY, BT_MESH_FEAT_FRIEND and BT_MESH_FEAT_LOW_POWER

uint16_t net_idx
Network index to publish with.

struct bt_mesh_cfg_cli_hb_pub
#include <cfg_cli.h> Heartbeat publication configuration parameters.

Public Members

uint16_t dst
Heartbeat destination address.
uint8_t count
Logarithmic Heartbeat count. Decoded as \((1 \ll (\text{count} - 1))\) if count is between 1 and 0x11, 0 if count is 0, or “indefinitely” if count is 0xff.
When used in Heartbeat publication set, this parameter denotes the number of Heartbeat messages to send.
When returned from Heartbeat publication get, this parameter denotes the number of Heartbeat messages remaining to be sent.

uint8_t period
Logarithmic Heartbeat publication transmit interval in seconds. Decoded as \((1 \ll (\text{period} - 1))\) if period is between 1 and 0x11. If period is 0, Heartbeat publication is disabled.

uint8_t ttl
Publication message Time To Live value.

uint16_t feat
Bitmap of features that trigger Heartbeat publications. Legal values are \texttt{BT_MESH_FEAT_RELAY}, \texttt{BT_MESH_FEAT_PROXY}, \texttt{BT_MESH_FEAT_FRIEND} and \texttt{BT_MESH_FEAT_LOW_POWER}.

uint16_t net_idx
Network index to publish with.

struct bt_mesh_comp_p0
#include <cfg_cli.h> Parsed Composition data page 0 representation.
Should be pulled from the return buffer passed to \texttt{bt_mesh_cfg_cli_comp_data_get} using \texttt{bt_mesh_comp_p0_get}.

Public Members

uint16_t cid
Company ID

uint16_t pid
Product ID

uint16_t vid
Version ID

uint16_t crpl
Replay protection list size

uint16_t feat
Supported features, see \texttt{BT_MESH_FEAT_SUPPORTED}.

struct bt_mesh_comp_p0_elem
#include <cfg_cli.h> Composition data page 0 element representation
Public Members

uint16_t loc
   Element location

size_t nsig
   The number of SIG models in this element

size_t nvnd
   The number of vendor models in this element

Health Server  The Health Server model provides attention callbacks and node diagnostics for Health Client models. It is primarily used to report faults in the mesh node and map the mesh nodes to their physical location.

Faults  The Health Server model may report a list of faults that have occurred in the device’s lifetime. Typically, the faults are events or conditions that may alter the behavior of the node, like power outages or faulty peripherals. Faults are split into warnings and errors. Warnings indicate conditions that are close to the limits of what the node is designed to withstand, but not necessarily damaging to the device. Errors indicate conditions that are outside of the node’s design limits, and may have caused invalid behavior or permanent damage to the device.

Fault values 0x01 to 0x7f are reserved for the Bluetooth mesh specification, and the full list of specification defined faults are available in Health faults. Fault values 0x80 to 0xff are vendor specific. The list of faults are always reported with a company ID to help interpreting the vendor specific faults.

Attention state  The attention state is used to make the device call attention to itself through some physical behavior like blinking, playing a sound or vibrating. The attention state may be used during provisioning to let the user know which device they’re provisioning, as well as through the Health models at runtime.

The attention state is always assigned a timeout in the range of one to 255 seconds when enabled. The Health Server API provides two callbacks for the application to run their attention calling behavior: bt_mesh_health_srv.cb.attn_on is called at the beginning of the attention period, bt_mesh_health_srv.cb.attn_off is called at the end.

The remaining time for the attention period may be queried through bt_mesh_health_srv.attn_timer.

API reference

group bt_mesh_health_srv
   Health Server Model.

Defines

BT_MESH_HEALTH_PUB_DEFINE(_name, _max_faults)
   A helper to define a health publication context

Parameters

• _name – Name given to the publication context variable.
• _max_faults – Maximum number of faults the element can have.
Define a new health server model. Note that this API needs to be repeated for each element that the application wants to have a health server model on. Each instance also needs a unique `bt_mesh_health_srv` and `bt_mesh_model_pub` context.

**Parameters**
- `srv` – Pointer to a unique struct `bt_mesh_health_srv`.
- `pub` – Pointer to a unique struct `bt_mesh_model_pub`.

**Returns**
New mesh model instance.

### Functions

**int bt_mesh_fault_update (struct bt_mesh_elem *elem)**

Notify the stack that the fault array state of the given element has changed.

This prompts the Health server on this element to publish the current fault array if periodic publishing is disabled.

**Parameters**
- `elem` – Element to update the fault state of.

**Returns**
0 on success, or (negative) error code otherwise.

**int bt_mesh_health_srv_fault_update (struct bt_mesh_elem *elem)**

Notify the stack that the fault array state of the given element has changed.

This prompts the Health server on this element to publish the current fault array if periodic publishing is disabled.

**Parameters**
- `elem` – Element to update the fault state of.

**Returns**
0 on success, or (negative) error code otherwise.

**struct bt_mesh_health_srv_cb**

`#include <health_srv.h>` Callback function for the Health Server model

### Public Members

**int (*fault_get_cur) (struct bt_mesh_model *model, uint8_t *test_id, uint16_t *company_id, uint8_t *faults, uint8_t *fault_count)**

Callback for fetching current faults.

Fault values may either be defined by the specification, or by a vendor. Vendor specific faults should be interpreted in the context of the accompanying Company ID. Specification defined faults may be reported for any Company ID, and the same fault may be presented for multiple Company IDs.

All faults shall be associated with at least one Company ID, representing the device vendor or some other vendor whose vendor specific fault values are used.

If there are multiple Company IDs that have active faults, return only the faults associated with one of them at the time. To report faults for multiple Company IDs, interleave which Company ID is reported for each call.
int (*fault_get_reg)(struct bt_mesh_model *model, uint16_t company_id, uint8_t *test_id, uint8_t *faults, uint8_t *fault_count)
 Callback for fetching all registered faults.
 Registered faults are all past and current faults since the last call to fault_clear. Only faults associated with the given Company ID should be reported.
 Fault values may either be defined by the specification, or by a vendor. Vendor specific faults should be interpreted in the context of the accompanying Company ID. Specification defined faults may be reported for any Company ID, and the same fault may be presented for multiple Company IDs.

int (*fault_clear)(struct bt_mesh_model *model, uint16_t company_id)
 Clear all registered faults associated with the given Company ID.

int (*fault_test)(struct bt_mesh_model *model, uint8_t test_id, uint16_t company_id)
 Run a self-test.
 The Health server may support up to 256 self-tests for each Company ID. The behavior for all test IDs are vendor specific, and should be interpreted based on the accompanying Company ID. Test failures should result in changes to the fault array.

Param company_id
Company ID to run test for.

Return
0 if the test execution was started successfully, or (negative) error code otherwise. Note that the fault array will not be reported back to the client if the test execution didn't start.

void (*attn_on)(struct bt_mesh_model *model)
Start calling attention to the device.

The attention state is used to map an element address to a physical device. When this callback is called, the device should start some physical procedure meant to call attention to itself, like blinking, buzzing, vibrating or moving. If there are multiple Health server instances on the device, the attention state should also help identify the specific element the server is in.

The attention calling behavior should continue until the attn_off callback is called.

Param model
Health Server model to start the attention state of.

void (*attn_off)(struct bt_mesh_model *model)
Stop the attention state.

Any physical activity started to call attention to the device should be stopped.

Param model

struct bt_mesh_health_srv

#include <health_srv.h> Mesh Health Server Model Context

Public Members

struct bt_mesh_model *model
Composition data model entry pointer.

const struct bt_mesh_health_srv_cb *cb
Optional callback struct

struct k_work_delayable attn_timer
Attention Timer state

Health faults
Fault values defined by the Bluetooth mesh specification.

group bt_mesh_health_faults
List of specification defined Health fault values.

Defines

BT_MESH_HEALTH_FAULT_NO_FAULT
No fault has occurred.

BT_MESH_HEALTH_FAULT_BATTERY_LOW_WARNING
BT_MESH_HEALTH_FAULT_BATTERY_LOW_ERROR

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_LOW_WARNING

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_LOW_ERROR

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_HIGH_WARNING

BT_MESH_HEALTH_FAULT_SUPPLY_VOLTAGE_TOO_HIGH_ERROR

BT_MESH_HEALTH_FAULT_POWER_SUPPLY_INTERRUPTED_WARNING

BT_MESH_HEALTH_FAULT_POWER_SUPPLY_INTERRUPTED_ERROR

BT_MESH_HEALTH_FAULT_NO_LOAD_WARNING

BT_MESH_HEALTH_FAULT_NO_LOAD_ERROR

BT_MESH_HEALTH_FAULT_OVERLOAD_WARNING

BT_MESH_HEALTH_FAULT_OVERLOAD_ERROR

BT_MESH_HEALTH_FAULT_OVERHEAT_WARNING

BT_MESH_HEALTH_FAULT_OVERHEAT_ERROR

BT_MESH_HEALTH_FAULT_CONDENSATION_WARNING

BT_MESH_HEALTH_FAULT_CONDENSATION_ERROR

BT_MESH_HEALTH_FAULT_VIBRATION_WARNING

BT_MESH_HEALTH_FAULT_VIBRATION_ERROR

BT_MESH_HEALTH_FAULT_CONFIGURATION_WARNING

BT_MESH_HEALTH_FAULT_CONFIGURATION_ERROR

BT_MESH_HEALTH_FAULT_ELEMENT_NOT_CALIBRATED_WARNING

BT_MESH_HEALTH_FAULT_ELEMENT_NOT_CALIBRATED_ERROR

BT_MESH_HEALTH_FAULT_MEMORY_WARNING

BT_MESH_HEALTH_FAULT_MEMORY_ERROR
BT_MESH_HEALTH_FAULT_SELF_TEST_WARNING
BT_MESH_HEALTH_FAULT_SELF_TEST_ERROR
BT_MESH_HEALTH_FAULT_INPUT_TOO_LOW_WARNING
BT_MESH_HEALTH_FAULT_INPUT_TOO_LOW_ERROR
BT_MESH_HEALTH_FAULT_INPUT_TOO_HIGH_WARNING
BT_MESH_HEALTH_FAULT_INPUT_TOO_HIGH_ERROR
BT_MESH_HEALTH_FAULT_INPUT_NO_CHANGE_WARNING
BT_MESH_HEALTH_FAULT_INPUT_NO_CHANGE_ERROR
BT_MESH_HEALTH_FAULT_ACTUATOR_BLOCKED_WARNING
BT_MESH_HEALTH_FAULT_ACTUATOR_BLOCKED_ERROR
BT_MESH_HEALTH_FAULT_HOUSING_OPENED_WARNING
BT_MESH_HEALTH_FAULT_HOUSING_OPENED_ERROR
BT_MESH_HEALTH_FAULT_TAMPER_WARNING
BT_MESH_HEALTH_FAULT_TAMPER_ERROR
BT_MESH_HEALTH_FAULT_DEVICE_MOVED_WARNING
BT_MESH_HEALTH_FAULT_DEVICE_MOVED_ERROR
BT_MESH_HEALTH_FAULT_DEVICE_DROPPED_WARNING
BT_MESH_HEALTH_FAULT_DEVICE_DROPPED_ERROR
BT_MESH_HEALTH_FAULT_OVERFLOW_WARNING
BT_MESH_HEALTH_FAULT_OVERFLOW_ERROR
BT_MESH_HEALTH_FAULT_EMPTY_WARNING
BT_MESH_HEALTH_FAULT_EMPTY_ERROR
BT_MESH_HEALTH_FAULT_INTERNAL_BUS_WARNING
Health Client  The Health Client model interacts with a Health Server model to read out diagnostics and control the node's attention state.

All message passing functions in the Health Client API have cli as their first parameter. This is a pointer to the client model instance to be used in this function call. The second parameter is the ctx or message context. Message context contains netkey index, appkey index and unicast address that the target node uses.

The Health Client model is optional, and may be instantiated in any element. However, if a Health Client model is instantiated in an element other than the first, an instance must also be present in the first element.

See Health faults for a list of specification defined fault values.

API reference

**group** bt_mesh_health_cli
Health Client Model.

**Defines**

BT_MESH_MODEL_HEALTH_CLI(cli_data)
Generic Health Client model composition data entry.

**Parameters**

- cli_data – Pointer to a Health Client Model instance.

**Functions**

int bt_mesh_health_cli_set(struct bt_mesh_model *model)
Set Health client model instance to use for communication.

**Parameters**

- model – Health Client model instance from the composition data.

**Returns**

0 on success, or (negative) error code on failure.

int bt_mesh_health_fault_get(uint16_t addr, uint16_t app_idx, uint16_t cid, uint8_t *test_id, uint8_t *faults, size_t *fault_count)
Get the registered fault state for the given Company ID.

This method can be used asynchronously by setting test_id and (faults or fault_count) as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the fault_status callback in bt_mesh_health_cli struct.

See also:

Health faults

Parameters

• addr – Target node element address.
• app_idx – Application index to encrypt with.
• cid – Company ID to get the registered faults of.
• test_id – Test ID response buffer.
• faults – Fault array response buffer.
• fault_count – Fault count response buffer.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_health_fault_clear(uint16_t addr, uint16_t app_idx, uint16_t cid, uint8_t *test_id, uint8_t *faults, size_t *fault_count)

Clear the registered faults for the given Company ID.

This method can be used asynchronously by setting test_id and (faults or fault_count) as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the fault_status callback in bt_mesh_health_cli struct.

See also:

Health faults

Parameters

• addr – Target node element address.
• app_idx – Application index to encrypt with.
• cid – Company ID to clear the registered faults for.
• test_id – Test ID response buffer.
• faults – Fault array response buffer.
• fault_count – Fault count response buffer.

Returns

0 on success, or (negative) error code on failure.
int bt_mesh_health_fault_clear_unack(uint16_t addr, uint16_t app_idx, uint16_t cid)
Clear the registered faults for the given Company ID (unacked).

See also:

*Health faults*

**Parameters**

- **addr** – Target node element address.
- **app_idx** – Application index to encrypt with.
- **cid** – Company ID to clear the registered faults for.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_fault_test(uint16_t addr, uint16_t app_idx, uint16_t cid, uint8_t test_id, uint8_t *faults, size_t *fault_count)
```
Invoke a self-test procedure for the given Company ID.

This method can be used asynchronously by setting `faults` or `fault_count` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `fault_status` callback in `bt_mesh_health_cli` struct.

**Parameters**

- **addr** – Target node element address.
- **app_idx** – Application index to encrypt with.
- **cid** – Company ID to invoke the test for.
- **test_id** – Test ID response buffer.
- **faults** – Fault array response buffer.
- **fault_count** – Fault count response buffer.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_fault_test_unack(uint16_t addr, uint16_t app_idx, uint16_t cid, uint8_t test_id)
```
Invoke a self-test procedure for the given Company ID (unacked).

**Parameters**

- **addr** – Target node element address.
- **app_idx** – Application index to encrypt with.
- **cid** – Company ID to invoke the test for.
- **test_id** – Test ID response buffer.

**Returns**

0 on success, or (negative) error code on failure.
int bt_mesh_health_period_get(uint16_t addr, uint16_t app_idx, uint8_t *divisor)

Get the target node's Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by \(1 << \text{divisor}\). For example, if the target node's Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.

This method can be used asynchronously by setting divisor as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the period_status callback in `bt_mesh_health_cli` struct.

**Parameters**

- `addr` – Target node element address.
- `app_idx` – Application index to encrypt with.
- `divisor` – Health period divisor response buffer.

**Returns**

0 on success, or (negative) error code on failure.

int bt_mesh_health_period_set(uint16_t addr, uint16_t app_idx, uint8_t divisor, uint8_t *updated_divisor)

Set the target node's Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by \(1 << \text{divisor}\). For example, if the target node's Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.

This method can be used asynchronously by setting updated_divisor as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the period_status callback in `bt_mesh_health_cli` struct.

**Parameters**

- `addr` – Target node element address.
- `app_idx` – Application index to encrypt with.
- `divisor` – New Health period divisor.
- `updated_divisor` – Health period divisor response buffer.

**Returns**

0 on success, or (negative) error code on failure.

int bt_mesh_health_period_set_unack(uint16_t addr, uint16_t app_idx, uint8_t divisor)

Set the target node's Health fast period divisor (unacknowledged).

This is an unacknowledged version of this API.

**Parameters**

- `addr` – Target node element address.
- `app_idx` – Application index to encrypt with.
- `divisor` – New Health period divisor.
Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_attention_get(uint16_t addr, uint16_t app_idx, uint8_t *attention)
Get the current attention timer value.
This method can be used asynchronously by setting attention as NULL. This way the method
will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the attention_status call-back in bt_mesh_health_cli struct.

Parameters
• addr – Target node element address.
• app_idx – Application index to encrypt with.
• attention – Attention timer response buffer, measured in seconds.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_attention_set(uint16_t addr, uint16_t app_idx, uint8_t attention, uint8_t *updated_attention)
Set the attention timer.
This method can be used asynchronously by setting updated_attention as NULL. This way the method
will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the attention_status call-back in bt_mesh_health_cli struct.

Parameters
• addr – Target node element address.
• app_idx – Application index to encrypt with.
• attention – New attention timer time, in seconds.
• updated_attention – Attention timer response buffer, measured in seconds.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_attention_set_unack(uint16_t addr, uint16_t app_idx, uint8_t attention)
Set the attention timer (unacknowledged).

Parameters
• addr – Target node element address.
• app_idx – Application index to encrypt with.
• attention – New attention timer time, in seconds.

Returns
0 on success, or (negative) error code on failure.

int bt_mesh_health_cli_fault_get(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx,
uint16_t cid, uint8_t *test_id, uint8_t *faults, size_t *fault_count)
Get the registered fault state for the given Company ID.
This method can be used asynchronously by setting test_id and (faults or fault_count ) as NULL. This way the method will not wait for response and will return immediately after sending the command.
To process the response arguments of an async method, register the `fault_status` callback in `bt_mesh_health_cli` struct.

See also:

*Health faults*

Parameters

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `cid` – Company ID to get the registered faults of.
- `test_id` – Test ID response buffer.
- `faults` – Fault array response buffer.
- `fault_count` – Fault count response buffer.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_fault_clear(
    struct bt_mesh_health_cli *cli,
    struct bt_mesh_msg_ctx *ctx,
    uint16_t cid,
    uint8_t *test_id,
    uint8_t *faults,
    size_t *fault_count
)
```

Clear the registered faults for the given Company ID.

This method can be used asynchronously by setting `test_id` and (`faults` or `fault_count`) as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `fault_status` callback in `bt_mesh_health_cli` struct.

See also:

*Health faults*

Parameters

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `cid` – Company ID to clear the registered faults for.
- `test_id` – Test ID response buffer.
- `faults` – Fault array response buffer.
- `fault_count` – Fault count response buffer.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_fault_clear_unack(
    struct bt_mesh_health_cli *cli,
    struct bt_mesh_msg_ctx *ctx,
    uint16_t cid
)
```

Clear the registered faults for the given Company ID (unacked).

See also:

*Health faults*
Parameters

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `cid` – Company ID to clear the registered faults for.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_healthCli_fault_test(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid, uint8_t test_id, uint8_t *faults, size_t *fault_count)
```

Invoke a self-test procedure for the given Company ID.

This method can be used asynchronously by setting `faults` or `fault_count` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the `fault_status` callback in `bt_mesh_health_cli` struct.

Parameters

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `cid` – Company ID to invoke the test for.
- `test_id` – Test ID response buffer.
- `faults` – Fault array response buffer.
- `fault_count` – Fault count response buffer.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_fault_test_unack(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint16_t cid, uint8_t test_id)
```

Invoice a self-test procedure for the given Company ID (unacked).

Parameters

- `cli` – Client model to send on.
- `ctx` – Message context, or NULL to use the configured publish parameters.
- `cid` – Company ID to invoke the test for.
- `test_id` – Test ID response buffer.

Returns

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_get(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t *divisor)
```

Get the target node's Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by \((1 \ll \text{divisor})\). For example, if the target node's Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.
This method can be used asynchronously by setting divisor as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the period_status callback in bt_mesh_health_cli struct.

Parameters
- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- divisor – Health period divisor response buffer.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_set(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t divisor, uint8_t *updated_divisor)
```

Set the target node's Health fast period divisor.

The health period divisor is used to increase the publish rate when a fault is registered. Normally, the Health server will publish with the period in the configured publish parameters. When a fault is registered, the publish period is divided by (1 << divisor). For example, if the target node's Health server is configured to publish with a period of 16 seconds, and the Health fast period divisor is 5, the Health server will publish with an interval of 500 ms when a fault is registered.

This method can be used asynchronously by setting updated_divisor as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the period_status callback in bt_mesh_health_cli struct.

Parameters
- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- divisor – New Health period divisor.
- updated_divisor – Health period divisor response buffer.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_period_set_unack(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t divisor)
```

Set the target node's Health fast period divisor (unacknowledged).

This is an unacknowledged version of this API.

Parameters
- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- divisor – New Health period divisor.

Returns
0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_get(struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t *attention)
```

Get the current attention timer value.

This method can be used asynchronously by setting attention as NULL. This way the method will not wait for response and will return immediately after sending the command.
To process the response arguments of an async method, register the attention_status callback in `bt_mesh_health_cli` struct.

**Parameters**

- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- attention – Attention timer response buffer, measured in seconds.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_set(
    struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t attention, uint8_t *updated_attention)
```

Set the attention timer.

This method can be used asynchronously by setting `updated_attention` as NULL. This way the method will not wait for response and will return immediately after sending the command.

To process the response arguments of an async method, register the attention_status callback in `bt_mesh_health_cli` struct.

**Parameters**

- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- attention – New attention timer time, in seconds.
- updated_attention – Attention timer response buffer, measured in seconds.

**Returns**

0 on success, or (negative) error code on failure.

```c
int bt_mesh_health_cli_attention_set_unack(
    struct bt_mesh_health_cli *cli, struct bt_mesh_msg_ctx *ctx, uint8_t attention)
```

Set the attention timer (unacknowledged).

**Parameters**

- cli – Client model to send on.
- ctx – Message context, or NULL to use the configured publish parameters.
- attention – New attention timer time, in seconds.

**Returns**

0 on success, or (negative) error code on failure.

```c
int32_t bt_mesh_health_cli_timeout_get(void)
```

Get the current transmission timeout value.

**Returns**

The configured transmission timeout in milliseconds.

```c
void bt_mesh_health_cli_timeout_set(int32_t timeout)
```

Set the transmission timeout value.

**Parameters**

- timeout – The new transmission timeout.

```c
#include "health_cli.h" // Health Client Model Context
```
Public Members

struct bt_mesh_model *model

Composition data model entry pointer.

struct bt_mesh_model_pub pub

Publication structure instance

struct net_buf_simple pub_buf

Publication buffer

uint8_t pub_data[BT_MESH_MODEL_BUF_LEN(BT_MESH_MODEL_OP_2(0x80, 0x32), 3)]

Publication data

void (*period_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t divisor)

Optional callback for Health Period Status messages.
Handles received Health Period Status messages from a Health server. The divisor param represents the period divisor value.

Param cli
Health client that received the status message.

Param addr
Address of the sender.

Param divisor
Health Period Divisor value.

void (*attention_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t attention)

Optional callback for Health Attention Status messages.
Handles received Health Attention Status messages from a Health server. The attention param represents the current attention value.

Param cli
Health client that received the status message.

Param addr
Address of the sender.

Param attention
Current attention value.

void (*fault_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t test_id, uint16_t cid, uint8_t *faults, size_t fault_count)

Optional callback for Health Fault Status messages.
Handles received Health Fault Status messages from a Health server. The fault array represents all faults that are currently present in the server's element.

See also:
Health faults

Param cli
Health client that received the status message.

Param addr
Address of the sender.

Param test_id
Identifier of a most recently performed test.
**Param cid**
Company Identifier of the node.

**Param faults**
Array of faults.

**Param fault_count**
Number of faults in the fault array.

```c
void (*current_status)(struct bt_mesh_health_cli *cli, uint16_t addr, uint8_t test_id, uint16_t cid, uint8_t *faults, size_t fault_count)
```
Optional callback for Health Current Status messages.
Handles received Health Current Status messages from a Health server. The fault array represents all faults that are currently present in the server's element.

**See also:**

*Health faults*

**Param cli**
Health client that received the status message.

**Param addr**
Address of the sender.

**Param test_id**
Identifier of a most recently performed test.

**Param cid**
Company Identifier of the node.

**Param faults**
Array of faults.

**Param fault_count**
Number of faults in the fault array.

**Message**  
The Bluetooth mesh message provides set of structures, macros and functions used for preparing message buffers, managing message and acknowledged message contexts.

**API reference**

*group bt_mesh_msg*
Message.

**Defines**

*Bt.MESH_MIC_SHORT*
Length of a short Mesh MIC.

*Bt.MESH_MIC_LONG*
Length of a long Mesh MIC.

*Bt_MESH_MODEL_OP_LEN(_op)*
Helper to determine the length of an opcode.

**Parameters**

- _op – Opcode.
BT_MESH_MODEL_BUF_LEN(_op, _payload_len)
Helper for model message buffer length.
Returns the length of a Mesh model message buffer, including the opcode length and a short MIC.

Parameters
- _op – Opcode of the message.
- _payload_len – Length of the model payload.

BT_MESH_MODEL_BUF_LEN_LONG_MIC(_op, _payload_len)
Helper for model message buffer length.
Returns the length of a Mesh model message buffer, including the opcode length and a long MIC.

Parameters
- _op – Opcode of the message.
- _payload_len – Length of the model payload.

BT_MESH_MODEL_BUF_DEFINE(_buf, _op, _payload_len)
Define a Mesh model message buffer using NET_BUF_SIMPLE_DEFINE.

Parameters
- _buf – Buffer name.
- _op – Opcode of the message.
- _payload_len – Length of the model message payload.

Functions

void bt_mesh_model_msg_init(struct net_buf_simple *msg, uint32_t opcode)
Initialize a model message.
Clears the message buffer contents, and encodes the given opcode. The message buffer will be ready for filling in payload data.

Parameters
- msg – Message buffer.
- opcode – Opcode to encode.

static inline void bt_mesh_msg_ack_ctx_init(struct bt_mesh_msg_ack_ctx *ack)
Initialize an acknowledged message context.
Initializes semaphore used for synchronization between bt_mesh_msg_ack_ctx_wait and bt_mesh_msg_ack_ctx_rx calls. Call this function before using bt_mesh_msg_ack_ctx.

Parameters
- ack – Acknowledged message context to initialize.

static inline void bt_mesh_msg_ack_ctx_reset(struct bt_mesh_msg_ack_ctx *ack)
Reset the synchronization semaphore in an acknowledged message context.
This function aborts call to bt_mesh_msg_ack_ctx_wait.

Parameters
- ack – Acknowledged message context to be reset.
void bt_mesh_msg_ack_ctx_clear(struct bt_mesh_msg_ack_ctx *ack)

Clear parameters of an acknowledged message context.

This function clears the opcode, remote address and user data set by `bt_mesh_msg_ack_ctx_prepare`.

**Parameters**

- ack – Acknowledged message context to be cleared.

int bt_mesh_msg_ack_ctx_prepare(struct bt_mesh_msg_ack_ctx *ack, uint32_t op, uint16_t dst, void *user_data)

Prepare an acknowledged message context for the incoming message to wait.

This function sets the opcode, remote address of the incoming message and stores the user data. Use this function before calling `bt_mesh_msg_ack_ctx_wait`.

**Parameters**

- ack – Acknowledged message context to prepare.
- dst – Destination address of the message.
- user_data – User data for the acknowledged message context.

**Returns**

0 on success, or (negative) error code on failure.

static inline bool bt_mesh_msg_ack_ctx_busy(struct bt_mesh_msg_ack_ctx *ack)

Check if the acknowledged message context is initialized with an opcode.

**Parameters**

- ack – Acknowledged message context.

**Returns**

true if the acknowledged message context is initialized with an opcode, false otherwise.

int bt_mesh_msg_ack_ctx_wait(struct bt_mesh_msg_ack_ctx *ack, k_timeout_t timeout)

Wait for a message acknowledge.

This function blocks execution until `bt_mesh_msg_ack_ctx_rx` is called or by timeout.

**Parameters**

- ack – Acknowledged message context of the message to wait for.
- timeout – Wait timeout.

**Returns**

0 on success, or (negative) error code on failure.

static inline void bt_mesh_msg_ack_ctx_rx(struct bt_mesh_msg_ack_ctx *ack)

Mark a message as acknowledged.

This function unblocks call to `bt_mesh_msg_ack_ctx_wait`.

**Parameters**

- ack – Context of a message to be acknowledged.

bool bt_mesh_msg_ack_ctx_match(const struct bt_mesh_msg_ack_ctx *ack, uint32_t op, uint16_t addr, void **user_data)

Check if an opcode and address of a message matches the expected one.

**Parameters**

- ack – Acknowledged message context to be checked.
• addr – Source address of the incoming message.
• user_data – If not NULL, returns a user data stored in the acknowledged message context by \texttt{bt\_mesh\_msg\_ack\_ctx\_prepare}.

**Returns**
true if the incoming message matches the expected one, false otherwise.

```c
struct bt_mesh_msg_ctx
#include <msg.h> Message sending context.
```

**Public Members**

```c
uint16_t net_idx
    NetKey Index of the subnet to send the message on.

uint16_t app_idx
    AppKey Index to encrypt the message with.

uint16_t addr
    Remote address.

uint16_t recv_dst
    Destination address of a received message. Not used for sending.

int8_t recv_rssi
    RSSI of received packet. Not used for sending.

uint8_t recv_ttl
    Received TTL value. Not used for sending.

bool send_rel
    Force sending reliably by using segment acknowledgment

uint8_t send_ttl
    TTL, or BT\_MESH\_TTL\_DEFAULT for default TTL.
```

```c
struct bt_mesh_msg_ack_ctx
#include <msg.h> Acknowledged message context for tracking the status of model messages pending a response.
```

**Public Members**

```c
struct k_sem sem
    Sync semaphore.

uint32_t op
    Opcode we're waiting for.
```
uint16_t dst
   Address of the node that should respond.

void *user_data
   User specific parameter.

Provisioning Provisioning is the process of adding devices to a mesh network. It requires two devices operating in the following roles:

- The *provisioner* represents the network owner, and is responsible for adding new nodes to the mesh network.
- The *provisionee* is the device that gets added to the network through the Provisioning process. Before the provisioning process starts, the provisionee is an *unprovisioned device*.

The Provisioning module in the Zephyr Bluetooth mesh stack supports both the Advertising and GATT Provisioning bearers for the provisionee role, as well as the Advertising Provisioning bearer for the provisioner role.

The Provisioning process All Bluetooth mesh nodes must be provisioned before they can participate in a Bluetooth mesh network. The Provisioning API provides all the functionality necessary for a device to become a provisioned mesh node. Provisioning is a five-step process, involving the following steps:

- Beaconing
- Invitation
- Public key exchange
- Authentication
- Provisioning data transfer

Beaconing To start the provisioning process, the unprovisioned device must first start broadcasting the Unprovisioned Beacon. This makes it visible to nearby provisioners, which can initiate the provisioning. To indicate that the device needs to be provisioned, call `bt_mesh_prov_enable()`. The device starts broadcasting the Unprovisioned Beacon with the device UUID and the OOB information field, as specified in the `prov` parameter passed to `bt_mesh_init()`. Additionally, a Uniform Resource Identifier (URI) may be specified, which can point the provisioner to the location of some Out Of Band information, such as the device's public key or an authentication value database. The URI is advertised in a separate beacon, with a URI hash included in the unprovisioned beacon, to tie the two together.

Uniform Resource Identifier The Uniform Resource Identifier shall follow the format specified in the Bluetooth Core Specification Supplement. The URI must start with a URI scheme, encoded as a single utf-8 data point, or the special *none* scheme, encoded as 0x01. The available schemes are listed on the Bluetooth website.

Examples of encoded URIs:

<table>
<thead>
<tr>
<th>URI</th>
<th>Encoded</th>
</tr>
</thead>
<tbody>
<tr>
<td><a href="http://example.com">http://example.com</a></td>
<td>\x16//example.com</td>
</tr>
<tr>
<td><a href="https://www.zephyrproject.org/">https://www.zephyrproject.org/</a></td>
<td>\x17//www.zephyrproject.org/</td>
</tr>
<tr>
<td>just a string</td>
<td>\x01just a string</td>
</tr>
</tbody>
</table>
**Provisioning invitation** The provisioner initiates the Provisioning process by sending a Provisioning invitation. The invitations prompts the provisionee to call attention to itself using the Health Server Attention state, if available.

The Unprovisioned device automatically responds to the invite by presenting a list of its capabilities, including the supported Out of Band Authentication methods.

**Public key exchange** Before the provisioning process can begin, the provisioner and the unprovisioned device exchange public keys, either in-band or Out of Band (OOB).

In-band public key exchange is a part of the provisioning process and always supported by the unprovisioned device and provisioner.

If the application wants to support public key exchange via OOB, it needs to provide public and private keys to the mesh stack. The unprovisioned device will reflect this in its capabilities. The provisioner obtains the public key via any available OOB mechanism (e.g. the device may advertise a packet containing the public key or it can be encoded in a QR code printed on the device packaging). Note that even if the unprovisioned device has specified the public key for the Out of Band exchange, the provisioner may choose to exchange the public key in-band if it can’t retrieve the public key via OOB mechanism. In this case, a new key pair will be generated by the mesh stack for each Provisioning process.

To enable support of OOB public key on the unprovisioned device side, CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY needs to be enabled. The application must provide public and private keys before the Provisioning process is started by initializing pointers to bt_mesh_prov.public_key_be and bt_mesh_prov.private_key_be. The keys needs to be provided in big-endian bytes order.

To provide the device’s public key obtained via OOB, call bt_mesh_prov.remote_pub_key_set() on the provisioner side.

**Authentication** After the initial exchange, the provisioner selects an Out of Band (OOB) Authentication method. This allows the user to confirm that the device the provisioner connected to is actually the device they intended, and not a malicious third party.

The Provisioning API supports the following authentication methods for the provisionee:

- **Static OOB**: An authentication value is assigned to the device in production, which the provisioner can query in some application specific way.
- **Input OOB**: The user inputs the authentication value. The available input actions are listed in bt_mesh_input_action_t.
- **Output OOB**: Show the user the authentication value. The available output actions are listed in bt_mesh_output_action_t.

The application must provide callbacks for the supported authentication methods in bt_mesh_prov as well as enabling the supported actions in bt_mesh_prov.output_actions and bt_mesh_prov.input_actions.

When an Output OOB action is selected, the authentication value should be presented to the user when the output callback is called, and remain until the bt_mesh_prov.input_complete or bt_mesh_prov.complete callback is called. If the action is blink, beep or vibrate, the sequence should be repeated after a delay of three seconds or more.

When an Input OOB action is selected, the user should be prompted when the application receives the bt_mesh_prov.input callback. The user response should be fed back to the Provisioning API through bt_mesh_input_string() or bt_mesh_input_number(). If no user response is recorded within 60 seconds, the Provisioning process is aborted.

**Data transfer** After the device has been successfully authenticated, the provisioner transfers the Provisioning data:
• Unicast address
• A network key
• IV index
• Network flags
  – Key refresh
  – IV update

Additionally, a device key is generated for the node. All this data is stored by the mesh stack, and the provisioning `bt_mesh_prov_complete` callback gets called.

**Provisioning security** Depending on the choice of public key exchange mechanism and authentication method, the provisioning process can be secure or insecure.

On May 24th 2021, ANSSI disclosed a set of vulnerabilities in the Bluetooth mesh provisioning protocol that showcased how the low entropy provided by the Blink, Vibrate, Push, Twist and Input/Output numeric OOB methods could be exploited in impersonation and MITM attacks. In response, the Bluetooth SIG has reclassified these OOB methods as insecure in the Mesh Profile specification erratum 16350, as AuthValue may be brute forced in real time. To ensure secure provisioning, applications should use a static OOB value and OOB public key transfer.

**API reference**

```
group bt_mesh_prov
  Provisioning.

Enums

enum bt_mesh_output_action_t
  Available Provisioning output authentication actions.
  Values:

  enumerator BT_MESH_NO_OUTPUT = 0

  enumerator BT_MESH_BLINK = BIT(0)

  enumerator BT_MESH_BEEP = BIT(1)

  enumerator BT_MESH_VIBRATE = BIT(2)

  enumerator BT_MESH_DISPLAY_NUMBER = BIT(3)

  enumerator BT_MESH_DISPLAY_STRING = BIT(4)
```

```
enum bt_mesh_input_action_t
  Available Provisioning input authentication actions.
  Values:
```

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enumerator BT_MESH_NO_INPUT = 0
enumerator BT_MESH_PUSH = *BIT(0)
enumerator BT_MESH_TWIST = *BIT(1)
enumerator BT_MESH_ENTER_NUMBER = *BIT(2)
enumerator BT_MESH_ENTER_STRING = *BIT(3)

enum bt_mesh_prov_bearer_t
Available Provisioning bearers.
Values:
enumerator BT_MESH_PROV_ADV = *BIT(0)
enumerator BT_MESH_PROV_GATT = *BIT(1)

enum bt_mesh_prov_oob_info_t
Out of Band information location.
Values:
enumerator BT_MESH_PROV_OOB_OTHER = *BIT(0)
enumerator BT_MESH_PROV_OOB_URI = *BIT(1)
enumerator BT_MESH_PROV_OOB_2D_CODE = *BIT(2)
enumerator BT_MESH_PROV_OOB_BAR_CODE = *BIT(3)
enumerator BT_MESH_PROV_OOB_NFC = *BIT(4)
enumerator BT_MESH_PROV_OOB_NUMBER = *BIT(5)
enumerator BT_MESH_PROV_OOB_STRING = *BIT(6)
enumerator BT_MESH_PROV_OOB_ON_BOX = *BIT(11)
enumerator BT_MESH_PROV_OOB_IN_BOX = *BIT(12)
enumerator BT_MESH_PROV_OOB_ON_PAPER = *BIT(13)
enumerator BT_MESH_PROV_OOB_IN_MANUAL = *BIT(14)
enumerator BT_MESH_PROV_OOB_ON_DEV = *BIT(15)
### Functions

**int bt_mesh_input_string(const char *str)**

Provide provisioning input OOB string.

This is intended to be called after the `bt_mesh_prov` input callback has been called with `BT_MESH_ENTER_STRING` as the action.

**Parameters**

• str – String.

**Returns**

Zero on success or (negative) error code otherwise.

**int bt_mesh_input_number(uint32_t num)**

Provide provisioning input OOB number.

This is intended to be called after the `bt_mesh_prov` input callback has been called with `BT_MESH_ENTER_NUMBER` as the action.

**Parameters**

• num – Number.

**Returns**

Zero on success or (negative) error code otherwise.

**int bt_mesh_prov_remote_pub_key_set(const uint8_t public_key[64])**

Provide Device public key.

**Parameters**

• public_key – Device public key in big-endian.

**Returns**

Zero on success or (negative) error code otherwise.

**int bt_mesh_auth_method_set_input(bt_mesh_input_action_t action, uint8_t size)**

Use Input OOB authentication.

Provisioner only.

Instruct the unprovisioned device to use the specified Input OOB authentication action. When using `BT_MESH_PUSH`, `BT_MESH_TWIST` or `BT_MESH_ENTER_NUMBER`, the `bt_mesh_prov::output_number` callback is called with a random number that has to be entered on the unprovisioned device.

When using `BT_MESH_ENTER_STRING`, the `bt_mesh_prov::output_string` callback is called with a random string that has to be entered on the unprovisioned device.

**Parameters**

• action – Authentication action used by the unprovisioned device.

• size – Authentication size.

**Returns**

Zero on success or (negative) error code otherwise.

**int bt_mesh_auth_method_set_output(bt_mesh_output_action_t action, uint8_t size)**

Use Output OOB authentication.

Provisioner only.

Instruct the unprovisioned device to use the specified Output OOB authentication action. The `bt_mesh_prov::output` callback will be called.
When using `BT_MESH_BLINK`, `BT_MESH_BEEP`, `BT_MESH_VIBRATE` or `BT_MESH_DISPLAY_NUMBER`, and the application has to call `bt_mesh_input_number` with the random number indicated by the unprovisioned device.

When using `BT_MESH_DISPLAY_STRING`, the application has to call `bt_mesh_input_string` with the random string displayed by the unprovisioned device.

**Parameters**

- `action` – Authentication action used by the unprovisioned device.
- `size` – Authentication size.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_mesh_auth_method_set_static(const uint8_t *static_val, uint8_t size)
```

Use static OOB authentication.

Provisioner only.

Instruct the unprovisioned device to use static OOB authentication, and use the given static authentication value when provisioning.

**Parameters**

- `static_val` – Static OOB value.
- `size` – Static OOB value size.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_mesh_auth_method_set_none(void)
```

Don’t use OOB authentication.

Provisioner only.

Don’t use any authentication when provisioning new devices. This is the default behavior.

**Warning:** Not using any authentication exposes the mesh network to impersonation attacks, where attackers can pretend to be the unprovisioned device to gain access to the network. Authentication is strongly encouraged.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_mesh_prov_enable(bt_mesh_prov_bearer_t bearers)
```

Enable specific provisioning bearers.

Enable one or more provisioning bearers.

**Parameters**

- `bearers` – Bit-wise or of provisioning bearers.

**Returns**

Zero on success or (negative) error code otherwise.

```c
int bt_mesh_prov_disable(bt_mesh_prov_bearer_t bearers)
```

Disable specific provisioning bearers.

Disable one or more provisioning bearers.

**Parameters**

- `bearers` – Bit-wise or of provisioning bearers.


**Returns**
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_provision(const uint8_t net_key[16], uint16_t net_idx, uint8_t flags, uint32_t iv_index, uint16_t addr, const uint8_t dev_key[16])
```

Provision the local Mesh Node.

This API should normally not be used directly by the application. The only exception is for testing purposes where manual provisioning is desired without an actual external provisioner.

**Parameters**
- `net_key` – Network Key
- `net_idx` – Network Key Index
- `flags` – Provisioning Flags
- `iv_index` – IV Index
- `addr` – Primary element address
- `dev_key` – Device Key

**Returns**
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_provision_adv(const uint8_t uuid[16], uint16_t net_idx, uint16_t addr, uint8_t attention_duration)
```

Provision a Mesh Node using PB-ADV.

**Parameters**
- `uuid` – UUID
- `net_idx` – Network Key Index
- `addr` – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- `attention_duration` – The attention duration to be send to remote device

**Returns**
Zero on success or (negative) error code otherwise.

```c
int bt_mesh_provision_gatt(const uint8_t uuid[16], uint16_t net_idx, uint16_t addr, uint8_t attention_duration)
```

Provision a Mesh Node using PB-GATT.

**Parameters**
- `uuid` – UUID
- `net_idx` – Network Key Index
- `addr` – Address to assign to remote device. If addr is 0, the lowest available address will be chosen.
- `attention_duration` – The attention duration to be send to remote device

**Returns**
Zero on success or (negative) error code otherwise.

```c
bool bt_mesh_is_provisioned(void)
```

Check if the local node has been provisioned.

This API can be used to check if the local node has been provisioned or not. It can e.g. be helpful to determine if there was a stored network in flash, i.e. if the network was restored after calling `settings_load()`.  

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**Returns**

True if the node is provisioned. False otherwise.

```c
struct bt_mesh_dev_capabilities
    #include <main.h> Device Capabilities.

Public Members

uint8_t elem_count
    Number of elements supported by the device

uint16_t algorithms
    Supported algorithms and other capabilities

uint8_t pub_key_type
    Supported public key types

uint8_t static_oob
    Supported static OOB Types

bt_mesh_output_action_t output_actions
    Supported Output OOB Actions

bt_mesh_input_action_t input_actions
    Supported Input OOB Actions

uint8_t output_size
    Maximum size of Output OOB supported

uint8_t input_size
    Maximum size in octets of Input OOB supported
```

```c
struct bt_mesh_prov
    #include <main.h> Provisioning properties & capabilities.

Public Members

const uint8_t *uuid
    The UUID that's used when advertising as unprovisioned

const char *uri
    Optional URI. This will be advertised separately from the unprovisioned beacon, however the unprovisioned beacon will contain a hash of it so the two can be associated by the provisioner.

bt_mesh_prov_oob_info_t oob_info
    Out of Band information field.
```
const uint8_t *public_key_be
Pointer to Public Key in big-endian for OOB public key type support.
Remember to enable CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY when initializing this parameter.
Must be used together with bt_mesh_prov::private_key_be.

const uint8_t *private_key_be
Pointer to Private Key in big-endian for OOB public key type support.
Remember to enable CONFIG_BT_MESH_PROV_OOB_PUBLIC_KEY when initializing this parameter.
Must be used together with bt_mesh_prov::public_key_be.

const uint8_t *static_val
Static OOB value

uint8_t static_val_len
Static OOB value length

uint8_t output_size
Maximum size of Output OOB supported

uint16_t output_actions
Supported Output OOB Actions

uint8_t input_size
Maximum size of Input OOB supported

uint16_t input_actions
Supported Input OOB Actions

void (*capabilities)(const struct bt_mesh_dev_capabilities *cap)
Provisioning Capabilities.
This callback notifies the application that the provisioning capabilities of the unprovisioned device has been received.
The application can consequently call bt_mesh_auth_method_set_* to select suitable provisioning oob authentication method.
When this callback returns, the provisioner will start authentication with the chosen method.
  Param cap
capabilities supported by device.

int (*output_number)(bt_mesh_output_action_t act, uint32_t num)
Output of a number is requested.
This callback notifies the application that it should output the given number using the given action.
  Param act
  Action for outputting the number.
  Param num
  Number to be outputted.
Return
Zero on success or negative error code otherwise

int (*output_string)(const char *str)
Output of a string is requested.
This callback notifies the application that it should display the given string to the user.
Param str
String to be displayed.
Return
Zero on success or negative error code otherwise

int (*input)(bt_mesh_input_action_t act, uint8_t size)
Input is requested.
This callback notifies the application that it should request input from the user using the given action. The requested input will either be a string or a number, and the application needs to consequently call the \texttt{bt\_mesh\_input\_string()} or \texttt{bt\_mesh\_input\_number()} functions once the data has been acquired from the user.
Param act
Action for inputting data.
Param num
Maximum size of the inputted data.
Return
Zero on success or negative error code otherwise

void (*input_complete)(void)
The other device finished their OOB input.
This callback notifies the application that it should stop displaying its output OOB value, as the other party finished their OOB input.

void (*unprovisioned_beacon)(uint8_t uuid[16], bt_mesh_prov_oob_info_t oob_info,
uint32_t *uri_hash)
Unprovisioned beacon has been received.
This callback notifies the application that an unprovisioned beacon has been received.
Param uuid
UUID
Param oob_info
OOB Information
Param uri_hash
Pointer to URI Hash value. NULL if no hash was present in the beacon.

void (*unprovisioned_beacon_gatt)(uint8_t uuid[16], bt_mesh_prov_oob_info_t oob_info)
PB-GATT Unprovisioned Advertising has been received.
This callback notifies the application that an PB-GATT unprovisioned Advertising has been received.
Param uuid
UUID
Param oob_info
OOB Information

void (*link_open)(bt_mesh_prov_bearer_t bearer)
Provisioning link has been opened.
This callback notifies the application that a provisioning link has been opened on the given provisioning bearer.

**Param bearer**
Provisioning bearer.

```c
void (*link_close)(bt_mesh_prov_bearer_t bearer)
```
Provisioning link has been closed.

This callback notifies the application that a provisioning link has been closed on the given provisioning bearer.

**Param bearer**
Provisioning bearer.

```c
void (*complete)(uint16_t net_idx, uint16_t addr)
```
Provisioning is complete.

This callback notifies the application that provisioning has been successfully completed, and that the local node has been assigned the specified NetKeyIndex and primary element address.

**Param net_idx**
NetKeyIndex given during provisioning.

**Param addr**
Primary element address.

```c
void (*node_added)(uint16_t net_idx, uint8_t uuid[16], uint16_t addr, uint8_t num_elem)
```
A new node has been added to the provisioning database.

This callback notifies the application that provisioning has been successfully completed, and that a node has been assigned the specified NetKeyIndex and primary element address.

**Param net_idx**
NetKeyIndex given during provisioning.

**Param uuid**
UUID of the added node.

**Param addr**
Primary element address.

**Param num_elem**
Number of elements that this node has.

```c
void (*reset)(void)
```
Node has been reset.

This callback notifies the application that the local node has been reset and needs to be reprovisioned. The node will not automatically advertise as unprovisioned, rather the `bt_mesh_prov_enable()` API needs to be called to enable unprovisioned advertising on one or more provisioning bearers.

**Proxy**
The Proxy feature allows legacy devices like phones to access the Bluetooth mesh network through GATT. The Proxy feature is only compiled in if the ```CONFIG_BT_MESH_GATT_PROXY``` option is set. The Proxy feature state is controlled by the ```Configuration Server```, and the initial value can be set with ```bt_mesh_cfg_srv.gatt_proxy```.

**API reference**

```c
#include <bt_mesh_proxy.h>
```
Proxy.
Defines

BT_MESH_PROXY_CB_DEFINE(_name)

Register a callback structure for Proxy events.

Registers a structure with callback functions that gets called on various Proxy events.

Parameters

• _name – Name of callback structure.

Functions

int bt_mesh_proxy_identity_enable(void)

Enable advertising with Node Identity.

This API requires that GATT Proxy support has been enabled. Once called each subnet will start advertising using Node Identity for the next 60 seconds.

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_proxy_connect(uint16_t net_idx)

Allow Proxy Client to auto connect to a network.

This API allows a proxy client to auto-connect a given network.

Parameters

• net_idx – Network Key Index

Returns

0 on success, or (negative) error code on failure.

int bt_mesh_proxy_disconnect(uint16_t net_idx)

Disallow Proxy Client to auto connect to a network.

This API disallows a proxy client to connect a given network.

Parameters

• net_idx – Network Key Index

Returns

0 on success, or (negative) error code on failure.

struct bt_mesh_proxy_cb

#include <proxy.h> Callbacks for the Proxy feature.

Should be instantiated with BT_MESH_PROXY_CB_DEFINE.

Public Members

void (*identity_enabled)(uint16_t net_idx)

Started sending Node Identity beacons on the given subnet.

Param net_idx

Network index the Node Identity beacons are running on.

void (*identity_disabled)(uint16_t net_idx)

Stopped sending Node Identity beacons on the given subnet.

Param net_idx

Network index the Node Identity beacons were running on.
Heartbeat  The Heartbeat feature provides functionality for monitoring Bluetooth mesh nodes and determining the distance between nodes.

The Heartbeat feature is configured through the Configuration Server model.

Heartbeat messages  Heartbeat messages are sent as transport control packets through the network, and are only encrypted with a network key. Heartbeat messages contain the original Time To Live (TTL) value used to send the message and a bitfield of the active features on the node. Through this, a receiving node can determine how many relays the message had to go through to arrive at the receiver, and what features the node supports.

Available Heartbeat feature flags:

- `BT_MESH_FEAT_RELAY`
- `BT_MESH_FEAT_PROXY`
- `BT_MESH_FEAT_FRIEND`
- `BT_MESH_FEAT_LOW_POWER`

Heartbeat publication  Heartbeat publication is controlled through the Configuration models, and can be triggered in two ways:

Periodic publication  The node publishes a new Heartbeat message at regular intervals. The publication can be configured to stop after a certain number of messages, or continue indefinitely.

Triggered publication  The node publishes a new Heartbeat message every time a feature changes. The set of features that can trigger the publication is configurable.

The two publication types can be combined.

Heartbeat subscription  A node can be configured to subscribe to Heartbeat messages from one node at the time. To receive a Heartbeat message, both the source and destination must match the configured subscription parameters.

Heartbeat subscription is always time limited, and throughout the subscription period, the node keeps track of the number of received Heartbeats as well as the minimum and maximum received hop count.

All Heartbeats received with the configured subscription parameters are passed to the `bt_mesh_hb_cb::recv` event handler.

When the Heartbeat subscription period ends, the `bt_mesh_hb_cb::sub_end` callback gets called.

API reference

```c

// Defines

#define BT_MESH_HB_CB_DEFINE(_name)  
    
BT_MESH_HB_CB_DEFINE(_name)  
    Register a callback structure for Heartbeat events.  
    Registers a callback structure that will be called whenever Heartbeat events occur

    Parameters

    - _name – Name of callback structure.
```

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Functions

void bt_mesh_hb_pub_get(struct bt_mesh_hb_pub *get)
    Get the current Heartbeat publication parameters.

    Parameters
    • get – Heartbeat publication parameters return buffer.

void bt_mesh_hb_sub_get(struct bt_mesh_hb_sub *get)
    Get the current Heartbeat subscription parameters.

    Parameters
    • get – Heartbeat subscription parameters return buffer.

struct bt_mesh_hb_pub
    #include <heartbeat.h> Heartbeat Publication parameters

    Public Members

    uint16_t dst
        Destination address.

    uint16_t count
        Remaining publish count.

    uint8_t ttl
        Time To Live value.

    uint16_t feat
        Bitmap of features that trigger a Heartbeat publication if they change. Legal values are
        BT_MESH_FEAT_RELAY, BT_MESH_FEAT_PROXY, BT_MESH_FEAT_FRIEND and
        BT_MESH_FEAT_LOW_POWER.

    uint16_t net_idx
        Network index used for publishing.

    uint32_t period
        Publication period in seconds.

struct bt_mesh_hb_sub
    #include <heartbeat.h> Heartbeat Subscription parameters.

    Public Members

    uint32_t period
        Subscription period in seconds.

    uint32_t remaining
        Remaining subscription time in seconds.
uint16_t src
Source address to receive Heartbeats from.

uint16_t dst
Destination address to received Heartbeats on.

uint16_t count
The number of received Heartbeat messages so far.

uint8_t min_hops
Minimum hops in received messages, ie the shortest registered path from the publishing node to the subscribing node. A Heartbeat received from an immediate neighbor has hop count = 1.

uint8_t max_hops
Maximum hops in received messages, ie the longest registered path from the publishing node to the subscribing node. A Heartbeat received from an immediate neighbor has hop count = 1.

struct bt_mesh_hb_cb
#include <heartbeat.h> Heartbeat callback structure

Public Members

void (*recv)(const struct bt_mesh_hb_sub *sub, uint8_t hops, uint16_t feat)
Receive callback for heartbeats.
Gets called on every received Heartbeat that matches the current Heartbeat subscription parameters.
    Param sub
    Current Heartbeat subscription parameters.
    Param hops
    The number of hops the Heartbeat was received with.
    Param feat
    The feature set of the publishing node. The value is a bitmap of BT_MESH_FEAT_RELAY, BT_MESH_FEAT_PROXY, BT_MESH_FEAT_FRIEND and BT_MESH_FEAT_LOW_POWER.

void (*sub_end)(const struct bt_mesh_hb_sub *sub)
Subscription end callback for heartbeats.
Gets called when the subscription period ends, providing a summary of the received heart- beat messages.
    Param sub
    Current Heartbeat subscription parameters.

void (*pub_sent)(const struct bt_mesh_hb_pub *pub)
Publication sent callback for heartbeats.
Gets called when the heartbeat is successfully published.
    Param pub
    Current Heartbeat publication parameters.
Runtime Configuration  The runtime configuration API allows applications to change their runtime configuration directly, without going through the Configuration models.

Bluetooth mesh nodes should generally be configured by a central network configurator device with a Configuration Client model. Each mesh node instantiates a Configuration Server model that the Configuration Client can communicate with to change the node configuration. In some cases, the mesh node can't rely on the Configuration Client to detect or determine local constraints, such as low battery power or changes in topology. For these scenarios, this API can be used to change the configuration locally.

API reference

group bt_mesh_cfg
    Runtime Configuration.

Defines

    BT_MESH_KR_NORMAL
    BT_MESH_KR_PHASE_1
    BT_MESH_KR_PHASE_2
    BT_MESH_KR_PHASE_3
    BT_MESH_RELAY_DISABLED
    BT_MESH_RELAY_ENABLED
    BT_MESH_RELAY_NOT_SUPPORTED
    BT_MESH_BEACON_DISABLED
    BT_MESH_BEACON_ENABLED
    BT_MESH_GATT_PROXY_DISABLED
    BT_MESH_GATT_PROXY_ENABLED
    BT_MESH_GATT_PROXY_NOT_SUPPORTED
    BT_MESH_FRIEND_DISABLED
    BT_MESH_FRIEND_ENABLED
    BT_MESH_FRIEND_NOT_SUPPORTED
    BT_MESH_NODE_IDENTITY_STOPPED
nums

enum bt_mesh_feat_state
    Bluetooth mesh feature states
    Values:

    enumerator BT_MESH_FEATURE_DISABLED
        Feature is supported, but disabled.

    enumerator BT_MESH_FEATURE_ENABLED
        Feature is supported and enabled.

    enumerator BT_MESH_FEATURE_NOT_SUPPORTED
        Feature is not supported, and cannot be enabled.

Functions

void bt_mesh_beacon_set(bool beacon)
    Enable or disable sending of the Secure Network Beacon.
    Parameters
    • beacon – New Secure Network Beacon state.

bool bt_mesh_beacon_enabled(void)
    Get the current Secure Network Beacon state.
    Returns
    Whether the Secure Network Beacon feature is enabled.

int bt_mesh_default_ttl_set(uint8_t default_ttl)
    Set the default TTL value.
    The default TTL value is used when no explicit TTL value is set. Models will use the default
    TTL value when \texttt{bt\_mesh\_msg\_ctx::send\_ttl} is \texttt{BT\_MESH\_TTL\_DEFAULT}.
    Parameters
    • default_ttl – The new default TTL value. Valid values are 0x00 and 0x02 to
      \texttt{BT\_MESH\_TTL\_MAX}.
    Return values
    • 0 – Successfully set the default TTL value.
    • -EINVAL – Invalid TTL value.

uint8_t bt_mesh_default_ttl_get(void)
    Get the current default TTL value.
    Returns
    The current default TTL value.
void bt_mesh_net_transmit_set(uint8_t xmit)
    Set the Network Transmit parameters.
    The Network Transmit parameters determine the parameters local messages are transmitted
    with.

    **See also:**
    
    *BT_MESH_TRANSMIT*

    **Parameters**
    
    * xmit – New Network Transmit parameters. Use *BT_MESH_TRANSMIT* for encoding.

uint8_t bt_mesh_net_transmit_get(void)
    Get the current Network Transmit parameters.
    The *BT_MESH_TRANSMIT_COUNT* and *BT_MESH_TRANSMIT_INT* macros can be used to de-
    code the Network Transmit parameters.

    **Returns**
    
    The current Network Transmit parameters.

int bt_mesh_relay_set(enum bt_mesh_feat_state relay, uint8_t xmit)
    Configure the Relay feature.
    Enable or disable the Relay feature, and configure the parameters to transmit relayed mes-
    sages with.
    Support for the Relay feature must be enabled through the *CONFIG_BT_MESH_RELAY* configu-
    ration option.

    **See also:**
    
    *BT_MESH_TRANSMIT*

    **Parameters**
    
    * relay – New Relay feature state. Must be one of *
      *BT_MESH_FEATURE_ENABLED* and *BT_MESH_FEATURE_DISABLED*.
    * xmit – New Relay retransmit parameters. Use *BT_MESH_TRANSMIT* for encod-
      ing.

    **Return values**
    
    * 0 – Successfully changed the Relay configuration.
    * -ENOTSUP – The Relay feature is not supported.
    * -EINVAL – Invalid parameter.
    * -EALREADY – Already using the given parameters.

enum bt_mesh_feat_state bt_mesh_relay_get(void)
    Get the current Relay feature state.

    **Returns**
    
    The Relay feature state.
uint8_t bt_mesh_relay_retransmit_get(void)
Get the current Relay Retransmit parameters.

The `BT_MESH_TRANSMIT_COUNT` and `BT_MESH_TRANSMIT_INT` macros can be used to de-
code the Relay Retransmit parameters.

**Returns**
The current Relay Retransmit parameters, or 0 if relay is not supported.

int bt_mesh_gatt_proxy_set(enum bt_mesh_feat_state gatt_proxy)
Enable or disable the GATT Proxy feature.
Support for the GATT Proxy feature must be enabled through the
`CONFIG_BT_MESH_GATT_PROXY` configuration option.

**Note:** The GATT Proxy feature only controls a Proxy node's ability to relay messages to
the mesh network. A node that supports GATT Proxy will still advertise Connectable Proxy
beacons, even if the feature is disabled. The Proxy feature can only be fully disabled through
compile time configuration.

**Parameters**
- gatt_proxy – New GATT Proxy state. Must be one of
  `BT_MESH_FEATURE_ENABLED` and `BT_MESH_FEATURE_DISABLED`.

**Return values**
- 0 – Successfully changed the GATT Proxy feature state.
- -ENOTSUP – The GATT Proxy feature is not supported.
- -EINVAL – Invalid parameter.
- -EALREADY – Already in the given state.

enum bt_mesh_feat_state bt_mesh_gatt_proxy_get(void)
Get the current GATT Proxy state.

**Returns**
The GATT Proxy feature state.

int bt_mesh_friend_set(enum bt_mesh_feat_state friendship)
Enable or disable the Friend feature.
Any active friendships will be terminated immediately if the Friend feature is disabled.
Support for the Friend feature must be enabled through the `CONFIG_BT_MESH_FRIEND` config-
uration option.

**Parameters**
- friendship – New Friend feature state. Must be one of
  `BT_MESH_FEATURE_ENABLED` and `BT_MESH_FEATURE_DISABLED`.

**Return values**
- 0 – Successfully changed the Friend feature state.
- -ENOTSUP – The Friend feature is not supported.
- -EINVAL – Invalid parameter.
- -EALREADY – Already in the given state.
enum bt_mesh_feat_state bt_mesh_friend_get(void)
    Get the current Friend state.

    Returns
    The Friend feature state.

Bluetooth Mesh Shell The Bluetooth mesh shell subsystem provides a set of Bluetooth mesh shell commands for the Shell module. It allows for testing and exploring the Bluetooth mesh API through an interactive interface, without having to write an application.

The Bluetooth mesh shell interface provides access to most Bluetooth mesh features, including provisioning, configuration, and message sending.

Prerequisites The Bluetooth mesh shell subsystem depends on the application to create the composition data and do the mesh initialization.

Application The Bluetooth mesh shell subsystem is most easily used through the Bluetooth mesh shell application under tests/bluetooth/mesh_shell. See Shell for information on how to connect and interact with the Bluetooth mesh shell application.

Basic usage The Bluetooth mesh shell subsystem adds a single mesh command, which holds a set of sub-commands. Every time the device boots up, make sure to call mesh init before any of the other Bluetooth mesh shell commands can be called:

```
uart:~$ mesh init
```

This is done to ensure that all available log will be printed to the shell output.

Provisioning The mesh node must be provisioned to become part of the network. This is only necessary the first time the device boots up, as the device will remember its provisioning data between reboots.

The simplest way to provision the device is through self-provisioning. To do this the user must provision the device with the default network key and address 0x0001, execute:

```
uart:~$ mesh prov local 0 0x0001
```

Since all mesh nodes use the same values for the default network key, this can be done on multiple devices, as long as they’re assigned non-overlapping unicast addresses. Alternatively, to provision the device into an existing network, the unprovisioned beacon can be enabled with mesh prov pb-adv on or mesh prov pb-gatt on. The beacons can be picked up by an external provisioner, which can provision the node into its network.

Once the mesh node is part of a network, its transmission parameters can be controlled by the general configuration commands:

- To set the destination address, call mesh target dst <addr>.
- To set the network key index, call mesh target net <NetIdx>.
- To set the application key index, call mesh target app <AppIdx>.

By default, the transmission parameters are set to send messages to the provisioned address and network key.

6.1. Bluetooth
Configuration  By setting the destination address to the local unicast address (0x0001 in the `mesh local` command above), we can perform self-configuration through any of the `Models` commands.

A good first step is to read out the node’s own composition data:

```
uart:~$ mesh models cfg get-comp
```

This prints a list of the composition data of the node, including a list of its model IDs.

Next, since the device has no application keys by default, it’s a good idea to add one:

```
uart:~$ mesh models cfg appkey add 0 0
```

**Message sending**  With an application key added (see above), the mesh node’s transition parameters are all valid, and the Bluetooth mesh shell can send raw mesh messages through the network.

For example, to send a Generic OnOff Set message, call:

```
uart:~$ mesh test net-send 82020100
```

**Note:** All multibyte fields model messages are in little endian, except the opcode.

The message will be sent to the current destination address, using the current network and application key indexes. As the destination address points to the local unicast address by default, the device will only send packets to itself. To change the destination address to the All Nodes broadcast address, call:

```
uart:~$ mesh target dst 0xffff
```

With the destination address set to 0xffff, any other mesh nodes in the network with the configured network and application keys will receive and process the messages we send.

**Note:** To change the configuration of the device, the destination address must be set back to the local unicast address before issuing any configuration commands.

Sending raw mesh packets is a good way to test model message handler implementations during development, as it can be done without having to implement the sending model. By default, only the reception of the model messages can be tested this way, as the Bluetooth mesh shell only includes the foundation models. To receive a packet in the mesh node, you have to add a model with a valid opcode handler list to the composition data in `subsys/bluetooth/mesh/shell.c`, and print the incoming message to the shell in the handler callback.

**Parameter formats**  The Bluetooth mesh shell commands are parsed with a variety of formats:

<table>
<thead>
<tr>
<th>Type</th>
<th>Description</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Integers</td>
<td>The default format unless something else is specified. Can be either decimal or hexadecimal.</td>
<td>1234, 0xabcd01234</td>
</tr>
<tr>
<td>Hexstrings</td>
<td>For raw byte arrays, like UUIDs, key values and message payloads, the parameters should be formatted as an unbroken string of hexadecimal values without any prefix.</td>
<td>deadbeef01234</td>
</tr>
<tr>
<td>Booleans</td>
<td>Boolean values are denoted in the API documentation as <code>&lt;val: on, off&gt;</code>.</td>
<td>on, off, enabled, disabled, 1, 0</td>
</tr>
</tbody>
</table>
Commands  The Bluetooth mesh shell implements a large set of commands. Some of the commands accept parameters, which are mentioned in brackets after the command name. For example, mesh lpn set <value: off, on>. Mandatory parameters are marked with angle brackets (e.g. <NetKeyIndex>), and optional parameters are marked with square brackets (e.g. [destination address]).

The Bluetooth mesh shell commands are divided into the following groups:

- General configuration
- Target
- Low Power Node
- Testing
- Provisioning
- Proxy
- Models
- Configuration database

Note: Some commands depend on specific features being enabled in the compile time configuration of the application. Not all features are enabled by default. The list of available Bluetooth mesh shell commands can be shown in the shell by calling mesh without any arguments.

General configuration

mesh init
Initialize the mesh shell. This command must be run before any other mesh command.

mesh reset-local
Reset the local mesh node to its initial unprovisioned state. This command will also clear the Configuration Database (CDB) if present.

Target  The target commands enables the user to monitor and set the target destination address, network index and application index for the shell. These parameters are used by several commands, like provisioning, Configuration Client, etc.

mesh target dst [destination address]
Get or set the message destination address. The destination address determines where mesh packets are sent with the shell, but has no effect on modules outside the shell's control.

- destination address: If present, sets the new 16-bit mesh destination address. If omitted, the current destination address is printed.

mesh target net [NetIdx]
Get or set the message network index. The network index determines which network key is used to encrypt mesh packets that are sent with the shell, but has no effect on modules outside the shell's control. The network key must already be added to the device, either through provisioning or by a Configuration Client.
• **NetIdx**: If present, sets the new network index. If omitted, the current network index is printed.

```
mesh target app [AppIdx]
```

Get or set the message application index. The application index determines which application key is used to encrypt mesh packets that are sent with the shell, but has no effect on modules outside the shell’s control. The application key must already be added to the device by a Configuration Client, and must be bound to the current network index.

• **AppIdx**: If present, sets the new application index. If omitted, the current application index is printed.

### Low Power Node

```
mesh lpn set <value: off, on>
```

Enable or disable Low Power operation. Once enabled, the device will turn off its radio and start polling for friend nodes.

• **value**: Sets whether Low Power operation is enabled.

```
mesh lpn poll
```

Perform a poll to the friend node, to receive any pending messages. Only available when LPN is enabled.

### Testing

```
mesh test net-send <Hex string>
```

Send a raw mesh message with the current destination address, network and application index. The message opcode must be encoded manually.

• **hex string**: Raw hexadecimal representation of the message to send.

```
mesh test iv-update
```

Force an IV update.

```
mesh test iv-update-test <value: off, on>
```

Set the IV update test mode. In test mode, the IV update timing requirements are bypassed.

• **value**: Enable or disable the IV update test mode.

```
mesh test rpl-clear
```

Clear the replay protection list, forcing the node to forget all received messages.

**Warning:** Clearing the replay protection list breaks the security mechanisms of the mesh node, making it susceptible to message replay attacks. This should never be performed in a real deployment.

### Health Server Test
mesh test health-srv add-fault <Fault ID>

Register a new Health Server Fault for the Linux Foundation Company ID.

- Fault ID: ID of the fault to register (0x0001 to 0xFFFF)

mesh test health-srv del-fault [Fault ID]

Remove registered Health Server faults for the Linux Foundation Company ID.

- Fault ID: If present, the given fault ID will be deleted. If omitted, all registered faults will be cleared.

**Provisioning** To allow a device to broadcast connectable unprovisioned beacons, the CONFIG_BT_MESH_PROVDEVICE configuration option must be enabled, along with the CONFIG_BT_MESH_PB_GATT option.

mesh prov pb-gatt <val: off, on>

Start or stop advertising a connectable unprovisioned beacon. The connectable unprovisioned beacon allows the mesh node to be discovered by nearby GATT based provisioners, and provisioned through the GATT bearer.

- val: Enable or disable provisioning with GATT

To allow a device to broadcast unprovisioned beacons, the CONFIG_BT_MESH_PROVDEVICE configuration option must be enabled, along with the CONFIG_BT_MESH_PB_ADV option.

mesh prov pb-adv <val: off, on>

Start or stop advertising the unprovisioned beacon. The unprovisioned beacon allows the mesh node to be discovered by nearby advertising-based provisioners, and provisioned through the advertising bearer.

- val: Enable or disable provisioning with advertiser

To allow a device to provision devices, the CONFIG_BT_MESH_PROVISIONER and CONFIG_BT_MESH_PB_ADV configuration options must be enabled.

mesh prov remote-adv <UUID> <NetKeyIndex> <addr> <AttentionDuration>

Provision a nearby device into the mesh. The mesh node starts scanning for unprovisioned beacons with the given UUID. Once found, the unprovisioned device will be added to the mesh network with the given unicast address, and given the network key indicated by NetKeyIndex.

- UUID: UUID of the unprovisioned device.
- NetKeyIndex: Index of the network key to pass to the device.
- addr: First unicast address to assign to the unprovisioned device. The device will occupy as many addresses as it has elements, and all must be available.
- AttentionDuration: The duration in seconds the unprovisioned device will identify itself for, if supported. See Attention state for details.

To allow a device to provision devices over GATT, the CONFIG_BT_MESH_PROVISIONER and CONFIG_BT_MESH_PB_GATT_CLIENT configuration options must be enabled.
mesh prov remote-gatt <UUID> <NetKeyIndex> <addr> <AttentionDuration>

Provision a nearby device into the mesh. The mesh node starts scanning for connectable advertising for PB-GATT with the given UUID. Once found, the unprovisioned device will be added to the mesh network with the given unicast address, and given the network key indicated by NetKeyIndex.

- **UUID**: UUID of the unprovisioned device.
- **NetKeyIndex**: Index of the network key to pass to the device.
- **addr**: First unicast address to assign to the unprovisioned device. The device will occupy as many addresses as it has elements, and all must be available.
- **AttentionDuration**: The duration in seconds the unprovisioned device will identify itself for, if supported. See Attention state for details.

mesh prov uuid [UUID: 1-16 hex values]

Get or set the mesh node’s UUID, used in the unprovisioned beacons.

- **UUID**: If present, new 128-bit UUID value. Any missing bytes will be zero. If omitted, the current UUID will be printed. To enable this command, the BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.

mesh prov input-num <number>

Input a numeric OOB authentication value. Only valid when prompted by the shell during provisioning. The input number must match the number presented by the other participant in the provisioning.

- **number**: Decimal authentication number.

mesh prov input-str <string>

Input an alphanumeric OOB authentication value. Only valid when prompted by the shell during provisioning. The input string must match the string presented by the other participant in the provisioning.

- **string**: Unquoted alphanumeric authentication string.

mesh prov static-oob [val: 1-16 hex values]

Set or clear the static OOB authentication value. The static OOB authentication value must be set before provisioning starts to have any effect. The static OOB value must be same on both participants in the provisioning. To enable this command, the BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.

- **val**: If present, indicates the new hexadecimal value of the static OOB. If omitted, the static OOB value is cleared.

mesh prov local <NetKeyIndex> <addr> [IVIndex]

Provision the mesh node itself. If the Configuration database is enabled, the network key must be created. Otherwise, the default key value is used.

- **NetKeyIndex**: Index of the network key to provision.
- **addr**: First unicast address to assign to the device. The device will occupy as many addresses as it has elements, and all must be available.
- **IVIndex**: Indicates the current network IV index. Defaults to 0 if omitted.
mesh prov beacon-listen <val: off, on>

Enable or disable printing of incoming unprovisioned beacons. Allows a provisioner device to detect nearby unprovisioned devices and provision them. To enable this command, the BT_MESH_SHELL_PROV_CTX_INSTANCE option must be enabled.

- **val**: Whether to enable the unprovisioned beacon printing.

mesh prov remote-pub-key <PubKey>

Provide Device public key.

- **PubKey**: Device public key in big-endian.

mesh prov auth-method input <Action> <Size>

From the provisioner device, instruct the unprovisioned device to use the specified Input OOB authentication action.

- **Action**: Input action. **Allowed values**:
  - 0: No input action.
  - 1: Push action set.
  - 2: Twist action set.
  - 4: Enter number action set.
  - 8: Enter String action set.
- **Size**: Authentication size.

mesh prov auth-method output <Action> <Size>

From the provisioner device, instruct the unprovisioned device to use the specified Output OOB authentication action.

- **Action**: Output action. **Allowed values**:
  - 0: No output action.
  - 1: Blink action set.
  - 2: Vibrate action set.
  - 4: Display number action set.
  - 8: Display String action set.
- **Size**: Authentication size.

mesh prov auth-method static <Value>

From the provisioner device, instruct the unprovisioned device to use static OOB authentication, and use the given static authentication value when provisioning.

- **Value**: Static OOB value.

mesh prov auth-method none <Value>

From the provisioner device, don't use any authentication when provisioning new devices. This is the default behavior.
Proxy  The Proxy Server module is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_GATT_PROXY configuration option.

mesh proxy identity-enable
Enable the Proxy Node Identity beacon, allowing Proxy devices to connect explicitly to this device. The beacon will run for 60 seconds before the node returns to normal Proxy beacons.

The Proxy Client module is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_PROXY_CLIENT configuration option.

mesh proxy connect <NetKeyIndex>
Auto-Connect a nearby proxy server into the mesh.
  • NetKeyIndex: Index of the network key to connect.

mesh proxy disconnect <NetKeyIndex>
Disconnect the existing proxy connection.
  • NetKeyIndex: Index of the network key to disconnect.

Models

Configuration Client  The Configuration Client model is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_CFG_CLI configuration option. This is implemented as a separate module (mesh models cfg) inside the mesh models subcommand list. This module will work on any instance of the Configuration Client model if the mentioned shell configuration options is enabled, and as long as the Configuration Client model is present in the model composition of the application. This shell module can be used for configuring itself and other nodes in the mesh network.

The Configuration Client uses general message parameters set by mesh target dst and mesh target net to target specific nodes. When the Bluetooth mesh shell node is provisioned, given that the BT_MESH_SHELL_PROV_CTX_INSTANCE option is enabled with the shell provisioning context initialized, the Configuration Client model targets itself by default. Similarly, when another node has been provisioned by the Bluetooth mesh shell, the Configuration Client model targets the new node. In most common use-cases, the Configuration Client is depending on the provisioning features and the Configuration database to be fully functional. The Configuration Client always sends messages using the Device key bound to the destination address, so it will only be able to configure itself and the mesh nodes it provisioned. The following steps are an example of how you can set up a device to start using the Configuration Client commands:

  • Initialize the client node (mesh init).
  • Create the CDB (mesh cdb create).
  • Provision the local device (mesh prov local).
  • The shell module should now target itself.
  • Monitor the composition data of the local node (mesh models cfg get-comp).
  • Configure the local node as desired with the Configuration Client commands.
  • Provision other devices (mesh prov beacon-listen) (mesh prov remote-adv) (mesh prov remote-gatt).
  • The shell module should now target the newly added node.
  • Monitor the newly provisioned nodes and their addresses (mesh cdb show).
  • Monitor the composition data of the target device (mesh models cfg get-comp).
• Configure the node as desired with the Configuration Client commands.

**mesh models cfg target get**
Get the target Configuration server for the Configuration Client model.

**mesh models cfg help**
Print information for the Configuration Client shell module.

**mesh models cfg reset**
Reset the target device.

**mesh models cfg timeout [timeout in seconds]**
Get and set the Config Client model timeout used during message sending.

• timeout in seconds: If present, set the Config Client model timeout in seconds. If omitted, the current timeout is printed.

**mesh models cfg get-comp [page]**
Read a composition data page. The full composition data page will be printed. If the target does not have the given page, it will return the last page before it.

• page: The composition data page to request. Defaults to 0 if omitted.

**mesh models cfg beacon [val: off, on]**
Get or set the network beacon transmission.

• val: If present, enables or disables sending of the network beacon. If omitted, the current network beacon state is printed.

**mesh models cfg ttl [ttl: 0x00, 0x02-0x7f]**
Get or set the default TTL value.

• ttl: If present, sets the new default TTL value. If omitted, the current default TTL value is printed.

**mesh models cfg friend [val: off, on]**
Get or set the Friend feature.

• val: If present, enables or disables the Friend feature. If omitted, the current Friend feature state is printed:
  – 0x00: The feature is supported, but disabled.
  – 0x01: The feature is enabled.
  – 0x02: The feature is not supported.
mesh models cfg gatt-proxy [val: off, on]
Get or set the GATT Proxy feature.
• val: If present, enables or disables the GATT Proxy feature. If omitted, the current GATT Proxy feature state is printed:
  – 0x00: The feature is supported, but disabled.
  – 0x01: The feature is enabled.
  – 0x02: The feature is not supported.

mesh models cfg relay [val: off, on] [count: 0-7] [interval: 10-320]
Get or set the Relay feature and its parameters.
• val: If present, enables or disables the Relay feature. If omitted, the current Relay feature state is printed:
  – 0x00: The feature is supported, but disabled.
  – 0x01: The feature is enabled.
  – 0x02: The feature is not supported.
• count: Sets the new relay retransmit count if val is on. Ignored if val is off. Defaults to 2 if omitted.
• interval: Sets the new relay retransmit interval in milliseconds if val is on. Ignored if val is off. Defaults to 20 if omitted.

mesh models cfg node-id <NetKeyIndex> [Identity]
Get or Set of current Node Identity state of a subnet.
• NetKeyIndex: The network key index to Get/Set.
• Identity: If present, sets the identity of Node Identity state.

mesh models cfg polltimeout-get <LPN Address>
Get current value of the PollTimeout timer of the LPN within a Friend node.
• addr Address of Low Power node.

mesh models cfg net-transmit-param [count: 0-7] [interval: 10-320]
Get or set the network transmit parameters.
• count: Sets the number of additional network transmits for every sent message.
• interval: Sets the new network retransmit interval in milliseconds.

mesh models cfg netkey add <NetKeyIndex> [val]
Add a network key to the target node. Adds the key to the Configuration Database if enabled.
• NetKeyIndex: The network key index to add.
• val: If present, sets the key value as a 128-bit hexadecimal value. Any missing bytes will be zero. Only valid if the key does not already exist in the Configuration Database. If omitted, the default key value is used.
mesh models cfg netkey upd <NetKeyIndex> [val]

Update a network key to the target node.

• NetKeyIndex: The network key index to updated.
• val: If present, sets the key value as a 128-bit hexadecimal value. Any missing bytes will be zero. If omitted, the default key value is used.

mesh models cfg netkey get

Get a list of known network key indexes.

mesh models cfg netkey del <NetKeyIndex>

Delete a network key from the target node.

• NetKeyIndex: The network key index to delete.

mesh models cfg appkey add <NetKeyIndex> <AppKeyIndex> [val]

Add an application key to the target node. Adds the key to the Configuration Database if enabled.

• NetKeyIndex: The network key index the application key is bound to.
• AppKeyIndex: The application key index to add.
• val: If present, sets the key value as a 128-bit hexadecimal value. Any missing bytes will be zero. Only valid if the key does not already exist in the Configuration Database. If omitted, the default key value is used.

mesh models cfg appkey upd <NetKeyIndex> <AppKeyIndex> [val]

Update an application key to the target node.

• NetKeyIndex: The network key index the application key is bound to.
• AppKeyIndex: The application key index to update.
• val: If present, sets the key value as a 128-bit hexadecimal value. Any missing bytes will be zero. If omitted, the default key value is used.

mesh models cfg appkey get <NetKeyIndex>

Get a list of known application key indexes bound to the given network key index.

• NetKeyIndex: Network key indexes to get a list of application key indexes from.

mesh models cfg appkey del <NetKeyIndex> <AppKeyIndex>

Delete an application key from the target node.

• NetKeyIndex: The network key index the application key is bound to.
• AppKeyIndex: The application key index to delete.
mesh models cfg model app-bind <addr> <AppIndex> <Model ID> [Company ID]

Bind an application key to a model. Models can only encrypt and decrypt messages sent with application keys they are bound to.

- **addr**: Address of the element the model is on.
- **AppIndex**: The application key to bind to the model.
- **Model ID**: The model ID of the model to bind the key to.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model app-unbind <addr> <AppIndex> <Model ID> [Company ID]

Unbind an application key from a model.

- **addr**: Address of the element the model is on.
- **AppIndex**: The application key to unbind from the model.
- **Model ID**: The model ID of the model to unbind the key from.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model app-get <elem addr> <Model ID> [Company ID]

Get a list of application keys bound to a model.

- **elem addr**: Address of the element the model is on.
- **Model ID**: The model ID of the model to get the bound keys of.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model pub <addr> <mod id> [cid] [<PubAddr> <AppKeyIndex> <cred: off, on> <ttl> <period> <count> <interval>]

Get or set the publication parameters of a model. If all publication parameters are included, they become the new publication parameters of the model. If all publication parameters are omitted, print the current publication parameters of the model.

- **addr**: Address of the element the model is on.
- **Model ID**: The model ID of the model to get the bound keys of.
- **cid**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

Publication parameters:

- **PubAddr**: The destination address to publish to.
- **AppKeyIndex**: The application key index to publish with.
- **cred**: Whether to publish with Friendship credentials when acting as a Low Power Node.
- **ttl**: TTL value to publish with (0x00 to 0x07f).
- **period**: Encoded publication period, or 0 to disable periodic publication.
- **count**: Number of retransmission for each published message (0 to 7).
- **interval**: The interval between each retransmission, in milliseconds. Must be a multiple of 50.
mesh models cfg model pub-va <addr> <UUID> <AppKeyIndex> <cred: off, on> <ttl> <period> <count> <interval> <mod id> [cid]

Set the publication parameters of a model.

- **addr**: Address of the element the model is on.
- **Model ID**: The model ID of the model to get the bound keys of.
- **cid**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

Publication parameters:

- **UUID**: The destination virtual address to publish to.
- **AppKeyIndex**: The application key index to publish with.
- **cred**: Whether to publish with Friendship credentials when acting as a Low Power Node.
- **ttl**: TTL value to publish with (0x00 to 0x07f).
- **period**: Encoded publication period, or 0 to disable periodic publication.
- **count**: Number of retransmission for each published message (0 to 7).
- **interval**: The interval between each retransmission, in milliseconds. Must be a multiple of 50.

mesh models cfg model sub-add <elem addr> <sub addr> <Model ID> [Company ID]

Subscription the model to a group address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.

- **elem addr**: Address of the element the model is on.
- **sub addr**: 16-bit group address the model should subscribe to (0xc000 to 0xFEFF).
- **Model ID**: The model ID of the model to add the subscription to.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-del <elem addr> <sub addr> <Model ID> [Company ID]

Unsubscribe a model from a group address.

- **elem addr**: Address of the element the model is on.
- **sub addr**: 16-bit group address the model should remove from its subscription list (0xc000 to 0xFEFF).
- **Model ID**: The model ID of the model to add the subscription to.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-add-va <elem addr> <Label UUID> <Model ID> [Company ID]

Subscribe the model to a virtual address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.

- **elem addr**: Address of the element the model is on.
- **Label UUID**: 128-bit label UUID of the virtual address to subscribe to. Any omitted bytes will be zero.
• Model ID: The model ID of the model to add the subscription to.
• Company ID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-del-va <elem addr> <Label UUID> <Model ID> [Company ID]

Unsubscribe a model from a virtual address.
• elem addr: Address of the element the model is on.
• Label UUID: 128-bit label UUID of the virtual address to remove the subscription of. Any omitted bytes will be zero.
• Model ID: The model ID of the model to add the subscription to.
• Company ID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-ow <elem addr> <sub addr> <Model ID> [Company ID]

Overwrite all model subscriptions with a single new group address.
• elem addr: Address of the element the model is on.
• sub addr: 16-bit group address the model should added to the subscription list (0xc000 to 0xFEFF).
• Model ID: The model ID of the model to add the subscription to.
• Company ID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-ow-va <elem addr> <Label UUID> <Model ID> [Company ID]

Overwrite all model subscriptions with a single new virtual address. Models only receive messages sent to their unicast address or a group or virtual address they subscribe to. Models may subscribe to multiple group and virtual addresses.
• elem addr: Address of the element the model is on.
• Label UUID: 128-bit label UUID of the virtual address as the new Address to be added to the subscription list. Any omitted bytes will be zero.
• Model ID: The model ID of the model to add the subscription to.
• Company ID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

mesh models cfg model sub-del-all <elem addr> <Model ID> [Company ID]

Remove all group and virtual address subscriptions from of a model.
• elem addr: Address of the element the model is on.
• Model ID: The model ID of the model to Unsubscribe all.
• Company ID: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.
**mesh models cfg model sub-get <elem addr> <Model ID> [Company ID]**

Get a list of addresses the model subscribes to.

- **elem addr**: Address of the element the model is on.
- **Model ID**: The model ID of the model to get the subscription list of.
- **Company ID**: If present, determines the Company ID of the model. If omitted, the model is a Bluetooth SIG defined model.

**mesh models cfg krp <NetKeyIdx> [Phase]**

Get or set the key refresh phase of a subnet.

- **NetKeyIdx**: The identified network key used to Get/Set the current Key Refresh Phase state.
- **Phase**: New Key Refresh Phase. Valid phases are 0, 1 or 2.

**mesh models cfg hb-sub [<src> <dst> <period>]**

Get or set the Heartbeat subscription parameters. A node only receives Heartbeat messages matching the Heartbeat subscription parameters. Sets the Heartbeat subscription parameters if present, or prints the current Heartbeat subscription parameters if called with no parameters.

- **src**: Unicast source address to receive Heartbeat messages from.
- **dst**: Destination address to receive Heartbeat messages on.
- **period**: Logarithmic representation of the Heartbeat subscription period:
  - 0: Heartbeat subscription will be disabled.
  - 1 to 17: The node will subscribe to Heartbeat messages for $2^{(period - 1)}$ seconds.

**mesh models cfg hb-pub [<dst> <count> <period> <ttl> <features> <NetKeyIndex>]**

Get or set the Heartbeat publication parameters. Sets the Heartbeat publication parameters if present, or prints the current Heartbeat publication parameters if called with no parameters.

- **dst**: Destination address to publish Heartbeat messages to.
- **count**: Logarithmic representation of the number of Heartbeat messages to publish periodically:
  - 0: Heartbeat messages are not published periodically.
  - 1 to 17: The node will periodically publish $2^{(count - 1)}$ Heartbeat messages.
  - 255: Heartbeat messages will be published periodically indefinitely.
- **period**: Logarithmic representation of the Heartbeat publication period:
  - 0: Heartbeat messages are not published periodically.
  - 1 to 17: The node will publish Heartbeat messages every $2^{(period - 1)}$ seconds.
- **ttl**: The TTL value to publish Heartbeat messages with (0x00 to 0x7f).
- **features**: Bitfield of features that should trigger a Heartbeat publication when changed:
  - Bit 0: Relay feature.
  - Bit 1: Proxy feature.
  - Bit 2: Friend feature.
– Bit 3: Low Power feature.

- NetKeyIndex: Index of the network key to publish Heartbeat messages with.

**Health Client**  
The Health Client model is an optional mesh subsystem that can be enabled through the `CONFIG_BT_MESH_HEALTH_CLI` configuration option. This is implemented as a separate module (`mesh models health`) inside the `mesh models` subcommand list. This module will work on any instance of the Health Client model if the mentioned shell configuration options is enabled, and as long as one or more Health Client model(s) is present in the model composition of the application. This shell module can be used to trigger interaction between Health Clients and Servers on devices in a Mesh network.

By default, the module will choose the first Health Client instance in the model composition when using the Health Client commands. To choose a specific Health Client instance the user can utilize the commands `mesh models health instance set` and `mesh models health instance get-all`.

The Health Client may use the general messages parameters set by `mesh target dst`, `mesh target net` and `mesh target app` to target specific nodes. If the shell target destination address is set to zero, the targeted Health Client will attempt to publish messages using its configured publication parameters.

```
mesh models health instance set <Elem_idx>

Set the Health Client model instance to use.

- Elem_idx: Element index of Health Client model.
```

```
mesh models health instance get-all

Prints all available Health Client model instances on the device.
```

```
mesh models health fault-get <Company ID>

Get a list of registered faults for a Company ID.

- Company ID: Company ID to get faults for.
```

```
mesh models health fault-clear <Company ID>

Clear the list of faults for a Company ID.

- Company ID: Company ID to clear the faults for.
```

```
mesh models health fault-clear-unack <Company ID>

Clear the list of faults for a Company ID without requesting a response.

- Company ID: Company ID to clear the faults for.
```

```
mesh models health fault-test <Company ID> <Test ID>

Invoke a self-test procedure, and show a list of triggered faults.

- Company ID: Company ID to perform self-tests for.
- Test ID: Test to perform.
```
mesh models health fault-test-unack <Company ID> <Test ID>

Invoke a self-test procedure without requesting a response.
- Company ID: Company ID to perform self-tests for.
- Test ID: Test to perform.

mesh models health period-get

Get the current Health Server publish period divisor.

mesh models health period-set <divisor>

Set the current Health Server publish period divisor. When a fault is detected, the Health Server will start publishing fault status with a reduced interval. The reduced interval is determined by the Health Server publish period divisor: Fault publish period = Publish period / $2^{\text{divisor}}$.
- divisor: The new Health Server publish period divisor.

mesh models health period-set-unack <divisor>

Set the current Health Server publish period divisor. When a fault is detected, the Health Server will start publishing fault status with a reduced interval. The reduced interval is determined by the Health Server publish period divisor: Fault publish period = Publish period / $2^{\text{divisor}}$.
- divisor: The new Health Server publish period divisor.

mesh models health attention-get

Get the current Health Server attention state.

mesh models health attention-set <timer>

Enable the Health Server attention state for some time.
- timer: Duration of the attention state, in seconds (0 to 255)

mesh models health attention-set-unack <timer>

Enable the Health Server attention state for some time without requesting a response.
- timer: Duration of the attention state, in seconds (0 to 255)

**Configuration database** The Configuration database is an optional mesh subsystem that can be enabled through the CONFIG_BT_MESH_CDB configuration option. The Configuration database is only available on provisioner devices, and allows them to store all information about the mesh network. To avoid conflicts, there should only be one mesh node in the network with the Configuration database enabled. This node is the Configurator, and is responsible for adding new nodes to the network and configuring them.

mesh cdb create [NetKey]

Create a Configuration database.
- NetKey: Optional network key value of the primary network key (NetKeyIndex=0). Defaults to the default key value if omitted.
mesh cdb clear
Clear all data from the Configuration database.

mesh cdb show
Show all data in the Configuration database.

mesh cdb node-add <UUID> <addr> <num-elem> <NetKeyIdx> [DevKey]
Manually add a mesh node to the configuration database. Note that devices provisioned with mesh provision and mesh provision-adv will be added automatically if the Configuration Database is enabled and created.

- UUID: 128-bit hexadecimal UUID of the node. Any omitted bytes will be zero.
- addr: Unicast address of the node, or 0 to automatically choose the lowest available address.
- num-elem: Number of elements on the node.
- NetKeyIdx: The network key the node was provisioned with.
- DevKey: Optional 128-bit device key value for the device. If omitted, a random value will be generated.

mesh cdb node-del <addr>
Delete a mesh node from the Configuration database. If possible, the node should be reset with mesh reset before it is deleted from the Configuration database, to avoid unexpected behavior and uncontrolled access to the network.

- addr: Address of the node to delete.

mesh cdb subnet-add <NetKeyIdx> [<NetKey>]
Add a network key to the Configuration database. The network key can later be passed to mesh nodes in the network. Note that adding a key to the Configuration database does not automatically add it to the local node's list of known network keys.

- NetKeyIdx: Key index of the network key to add.
- NetKey: Optional 128-bit network key value. Any missing bytes will be zero. If omitted, a random value will be generated.

mesh cdb subnet-del <NetKeyIdx>
Delete a network key from the Configuration database.

- NetKeyIdx: Key index of the network key to delete.

mesh cdb app-key-add <NetKeyIdx> <AppKeyIdx> [<AppKey>]
Add an application key to the Configuration database. The application key can later be passed to mesh nodes in the network. Note that adding a key to the Configuration database does not automatically add it to the local node's list of known application keys.

- NetKeyIdx: Network key index the application key is bound to.
- AppKeyIdx: Key index of the application key to add.
- AppKey: Optional 128-bit application key value. Any missing bytes will be zero. If omitted, a random value will be generated.
mesh cdb app-key-del <AppKeyId>

Delete an application key from the Configuration database.
  • AppKeyId: Key index of the application key to delete.

Bluetooth Microphone Control

API Reference

group bt_gatt_micp
  Microphone Input Control Profile (MICP)
  [Experimental] Users should note that the APIs can change as a part of ongoing development.

Defines

BT_MICP_MIC_DEV_AICS_CNT

BT_MICP_ERR_MUTE_DISABLED
  Application error codes

BT_MICP_ERR_VAL_OUT_OF_RANGE

BT_MICP_MUTE_UNMUTED
  Microphone Input Control Profile mute states

BT_MICP_MUTE_MUTED

BT_MICP_MUTE_DISABLED

Functions

int bt_micp_mic_dev_register(struct bt_micp_mic_dev_register_param *param)
  Initialize the Microphone Input Control Profile Microphone Device.
  This will enable the Microphone Input Control Service instance and make it discoverable by Microphone Controllers.
  Parameters
    • param – Pointer to an initialization structure.
  Returns
    0 if success, errno on failure.

int bt_micp_mic_dev_included_get(struct bt_micp_included *included)
  Get Microphone Device included services.
  Requires that CONFIG_BT_MICP_MIC_DEV_AICS is enabled.
  Parameters
    • included – Pointer to store the result in.
Returns
0 if success, errno on failure.

int bt_micp_mic_dev_unmute(void)
Unmute the Microphone Device.

Returns
0 on success, GATT error value on fail.

int bt_micp_mic_dev_mute(void)
Mute the Microphone Device.

Returns
0 on success, GATT error value on fail.

int bt_micp_mic_dev_mute_disable(void)
Disable the mute functionality on the Microphone Device.
Can be reenabled by called bt_micp_mic_dev_mute or bt_micp_mic_dev_unmute.

Returns
0 on success, GATT error value on fail.

int bt_micp_mic_dev_mute_get(void)
Read the mute state on the Microphone Device.

Returns
0 on success, GATT error value on fail.

int bt_micp_mic_ctlr_included_get(struct bt_micp_mic_ctlr *mic_ctlr, struct bt_micp_included *included)
Get Microphone Input Control Profile included services.
Returns a pointer to a struct that contains information about the Microphone Input Control Profile included services instances, such as pointers to the Audio Input Control Service instances.
Requires that CONFIG_BT_MICP_MIC_CTLR_AICS is enabled.

Parameters
• mic_ctlr – Microphone Controller instance pointer.
• included – [out] Pointer to store the result in.

Returns
0 if success, errno on failure.

int bt_micp_mic_ctlr_conn_get(const struct bt_micp_mic_ctlr *mic_ctlr, struct bt_conn **conn)
Get the connection pointer of a Microphone Controller instance.
Get the Bluetooth connection pointer of a Microphone Controller instance.

Parameters
• mic_ctlr – Microphone Controller instance pointer.
• conn – Connection pointer.

Returns
0 if success, errno on failure.

int bt_micp_mic_ctlr_discover(struct bt_conn *conn, struct bt_micp_mic_ctlr **mic_ctlr)
Discover Microphone Input Control Service.
This will start a GATT discovery and setup handles and subscriptions. This shall be called once before any other actions can be executed for the peer device, and the bt_micp_mic_ctlr_cb::discover callback will notify when it is possible to start remote operations.
Parameters
- `conn` – The connection to initialize the profile for.
- `mic_ctlr` – [out] Valid remote instance object on success.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_unmute(struct bt_micp_mic_ctlr *mic_ctlr)
```
Unmute a remote Microphone Device.

Parameters
- `mic_ctlr` – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_mute(struct bt_micp_mic_ctlr *mic_ctlr)
```
Mute a remote Microphone Device.

Parameters
- `mic_ctlr` – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_mute_get(struct bt_micp_mic_ctlr *mic_ctlr)
```
Read the mute state of a remote Microphone Device.

Parameters
- `mic_ctlr` – Microphone Controller instance pointer.

Returns
0 on success, GATT error value on fail.

```c
int bt_micp_mic_ctlr_cb_register(struct bt_micp_mic_ctlr_cb *cb)
```
Registers the callbacks used by Microphone Controller.

This can only be done as the client.

Parameters
- `cb` – The callback structure.

Returns
0 if success, errno on failure.

```c
struct bt_micp_mic_dev_register_param
#include <micp.h>  // Register parameters structure for Microphone Input Control Service.
```

Public Members

```c
struct bt_micp_mic_dev_cb *cb
```
Microphone Input Control Profile callback structure.
struct bt_micp_included

#include <micp.h> Microphone Input Control Profile included services.

Used for to represent the Microphone Input Control Profile included service instances, for either a Microphone Controller or a Microphone Device. The instance pointers either represent local service instances, or remote service instances.

Public Members

uint8_t aics_cnt

Number of Audio Input Control Service instances

struct bt_aics **aics

Array of pointers to Audio Input Control Service instances

struct bt_micp_mic_dev_cb

#include <micp.h>

Public Members

void (*mute)(uint8_t mute)

Callback function for Microphone Device mute.

Called when the value is read with bt_micp_mic_dev_mute_get(), or if the value is changed by either the Microphone Device or a Microphone Controller.

Param mute

The mute setting of the Microphone Input Control Service.

struct bt_micp_mic_ctlr_cb

#include <micp.h>

Public Members

void (*mute)(struct bt_micp_mic_ctlr *mic_ctlr, int err, uint8_t mute)

Callback function for Microphone Input Control Profile mute.

Called when the value is read, or if the value is changed by either the Microphone Device or a Microphone Controller.

Param mic_ctlr

Microphone Controller instance pointer.

Param err

Error value. 0 on success, GATT error or errno on fail. For notifications, this will always be 0.

Param mute

The mute setting of the Microphone Input Control Service.

void (*discover)(struct bt_micp_mic_ctlr *mic_ctlr, int err, uint8_t aics_count)

Callback function for bt_micp_mic_ctlr_discover().

Param mic_ctlr

Microphone Controller instance pointer.
**Param err**
- Error value. 0 on success, GATT error or errno on fail.

**Param aics_count**
- Number of Audio Input Control Service instances on peer device.

```c
void (*mute_written)(struct bt_micp_mic_ctlr *mic_ctlr, int err)
```
- Callback function for Microphone Input Control Profile mute/unmute.

**Param mic_ctlr**
- Microphone Controller instance pointer.

**Param err**
- Error value. 0 on success, GATT error or errno on fail.

```c
void (*unmute_written)(struct bt_micp_mic_ctlr *mic_ctlr, int err)
```
- Callback function for Microphone Input Control Profile mute/unmute.

**Param mic_ctlr**
- Microphone Controller instance pointer.

**Param err**
- Error value. 0 on success, GATT error or errno on fail.

---

**Serial Port Emulation (RFCOMM)**

**API Reference**

**group bt_rfcomm**

RFCOMM.

**Typedefs**

```c
typedef enum bt_rfcomm_role bt_rfcomm_role_t
```
- Role of RFCOMM session and dlc. Used only by internal APIs.

**Enums**

```c
enum [anonymous]
```
- **Values:**

  ```c
  enumerator BT_RFCOMM_CHAN_HFP_HF = 1
  
  enumerator BT_RFCOMM_CHAN_HFP_AG
  
  enumerator BT_RFCOMM_CHAN_HSP_AG
  
  enumerator BT_RFCOMM_CHAN_HSP_HS
  
  enumerator BT_RFCOMM_CHAN_SPP
  
  enum bt_rfcomm_role
  ```
- Role of RFCOMM session and dlc. Used only by internal APIs.

- **Values:**
enumerator BT_RFCOMM_ROLE_ACCEPTOR

enumerator BT_RFCOMM_ROLE_INITIATOR

Functions

int bt_rfcomm_server_register(struct bt_rfcomm_server *server)
Register RFCOMM server.
Register RFCOMM server for a channel, each new connection is authorized using the accept() callback which in case of success shall allocate the dlc structure to be used by the new connection.

Parameters
• server – Server structure.

Returns
0 in case of success or negative value in case of error.

int bt_rfcomm_dlc_connect(struct bt_conn *conn, struct bt_rfcomm_dlc *dlc, uint8_t channel)
Connect RFCOMM channel.
Connect RFCOMM dlc by channel, once the connection is completed dlc connected() callback will be called. If the connection is rejected disconnected() callback is called instead.

Parameters
• conn – Connection object.
• dlc – Dlc object.
• channel – Server channel to connect to.

Returns
0 in case of success or negative value in case of error.

int bt_rfcomm_dlc_send(struct bt_rfcomm_dlc *dlc, struct net_buf *buf)
Send data to RFCOMM.
Send data from buffer to the dlc. Length should be less than or equal to mtu.

Parameters
• dlc – Dlc object.
• buf – Data buffer.

Returns
Bytes sent in case of success or negative value in case of error.

int bt_rfcomm_dlc_disconnect(struct bt_rfcomm_dlc *dlc)
Disconnect RFCOMM dlc.
Disconnect RFCOMM dlc, if the connection is pending it will be canceled and as a result the dlc disconnected() callback is called.

Parameters
• dlc – Dlc object.

Returns
0 in case of success or negative value in case of error.
struct net_buf *bt_rfcomm_create_pdu(struct net_buf_pool *pool)
Allocate the buffer from pool after reserving head room for RFCOMM, L2CAP and ACL headers.

Parameters

• pool – Which pool to take the buffer from.

Returns

New buffer.

struct bt_rfcomm_dlc_ops
#include <rfcomm.h> RFCOMM DLC operations structure.

Public Members

void (*connected)(struct bt_rfcomm_dlc *dlc)
DLC connected callback
If this callback is provided it will be called whenever the connection completes.
    Param dlc
                          The dlc that has been connected

void (*disconnected)(struct bt_rfcomm_dlc *dlc)
DLC disconnected callback
If this callback is provided it will be called whenever the dlc is disconnected, including when a connection gets rejected or cancelled (both incoming and outgoing)
    Param dlc
                          The dlc that has been Disconnected

void (*recv)(struct bt_rfcomm_dlc *dlc, struct net_buf *buf)
DLC recv callback
    Param dlc
                          The dlc receiving data.
    Param buf
                         Buffer containing incoming data.

struct bt_rfcomm_dlc
#include <rfcomm.h> RFCOMM DLC structure.

struct bt_rfcomm_server
#include <rfcomm.h>

Public Members

uint8_t channel
Server Channel

int (*accept)(struct bt_conn *conn, struct bt_rfcomm_dlc **dlc)
Server accept callback
This callback is called whenever a new incoming connection requires authorization.
**Param conn**
The connection that is requesting authorization

**Param dlc**
Pointer to received the allocated dlc

**Return**
0 in case of success or negative value in case of error.

---

**Bluetooth standard services**

**Battery Service**

* group bt_bas  
Battery Service (BAS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Functions**

```c
uint8_t bt_bas_get_battery_level(void)
Read battery level value.
Read the characteristic value of the battery level

**Returns**
The battery level in percent.
```

```c
int bt_bas_set_battery_level(uint8_t level)
Update battery level value.
Update the characteristic value of the battery level This will send a GATT notification to all current subscribers.

**Parameters**
- level – The battery level in percent.

**Returns**
Zero in case of success and error code in case of error.
```

**Heart Rate Service**

* group bt_hrs  
Heart Rate Service (HRS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Functions**

```c
int bt_hrs_notify(uint16_t heartrate)
Notify heart rate measurement.
This will send a GATT notification to all current subscribers.

**Parameters**
- heartrate – The heartrate measurement in beats per minute.

**Returns**
Zero in case of success and error code in case of error.
```
Immediate Alert Service

**group bt_ias**

Immediate Alert Service (IAS)

[Experimental] Users should note that the APIs can change as a part of ongoing development.

**Defines**

`BT_IAS_CB_DEFINE(_name)`

Register a callback structure for immediate alert events.

**Parameters**

- `_name` – Name of callback structure.

** Enums**

`enum bt_ias_alert_lvl`

**Values:**

- `enumerator BT_IAS_ALERT_LVL_NO_ALERT`  
  No alerting should be done on device

- `enumerator BT_IAS_ALERT_LVL_MILD_ALERT`  
  Device shall alert

- `enumerator BT_IAS_ALERT_LVL_HIGH_ALERT`  
  Device should alert in strongest possible way

**Functions**

`int bt_ias_local_alert_stop(void)`  
Method for stopping alert locally.

**Returns**

Zero in case of success and error code in case of error.

`int bt_ias_client_alert_write(struct bt_conn *conn, enum bt_ias_alert_lvl)`  
Set alert level.

**Parameters**

- `conn` – Bluetooth connection object
- `bt_ias_alert_lvl` – Level of alert to write

**Returns**

Zero in case of success and error code in case of error.

`int bt_ias_discover(struct bt_conn *conn)`  
Discover Immediate Alert Service.

**Parameters**

- `conn` – Bluetooth connection object

**Returns**

Zero in case of success and error code in case of error.
int bt_ias_client_cb_register(const struct bt_ias_client_cb *cb)
    Register Immediate Alert Client callbacks.

    Parameters
    • cb – The callback structure

    Returns
    Zero in case of success and error code in case of error.

struct bt_ias_cb
#include <ias.h>  Immediate Alert Service callback structure.

Public Members

void (*no_alert)(void)
    Callback function to stop alert.
    This callback is called when peer commands to disable alert.

void (*mild_alert)(void)
    Callback function for alert level value.
    This callback is called when peer commands to alert.

void (*high_alert)(void)
    Callback function for alert level value.
    This callback is called when peer commands to alert in the strongest possible way.

struct bt_ias_client_cb
#include <ias.h>

Public Members

void (*discover)(struct bt_conn *conn, int err)
    Callback function for bt_ias_discover.
    This callback is called when discovery procedure is complete.
    
    Param conn
    Bluetooth connection object.
    
    Param err
    0 on success, ATT error or negative errno otherwise

Object Transfer Service

group bt_ots
    Object Transfer Service (OTS)
    [Experimental] Users should note that the APIs can change as a part of ongoing development.
Defines

**BT_OTS_OBJ_ID_SIZE**
Size of OTS object ID (in bytes).

**BT_OTS_OBJ_ID_MIN**
Minimum allowed value for object ID (except ID for directory listing)

**BT_OTS_OBJ_ID_MAX**
Maximum allowed value for object ID (except ID for directory listing)

**OTS_OBJ_ID_DIR_LIST**
ID of the Directory Listing Object.

**BT_OTS_OBJ_ID_MASK**
Mask for OTS object IDs, preserving the 48 bits.

**BT_OTS_OBJ_ID_STR_LEN**
Length of OTS object ID string (in bytes).

**BT_OTS_OBJ_SET_PROP_DELETE(prop)**
Set **BT_OTS_OBJ_PROP_DELETE** property.

**Parameters**
• prop – Object properties.

**BT_OTS_OBJ_SET_PROP_EXECUTE(prop)**
Set **BT_OTS_OBJ_PROP_EXECUTE** property.

**Parameters**
• prop – Object properties.

**BT_OTS_OBJ_SET_PROP_READ(prop)**
Set **BT_OTS_OBJ_PROP_READ** property.

**Parameters**
• prop – Object properties.

**BT_OTS_OBJ_SET_PROP_WRITE(prop)**
Set **BT_OTS_OBJ_PROP_WRITE** property.

**Parameters**
• prop – Object properties.

**BT_OTS_OBJ_SET_PROP_APPEND(prop)**
Set **BT_OTS_OBJ_PROP_APPEND** property.

**Parameters**
• prop – Object properties.

**BT_OTS_OBJ_SET_PROP_TRUNCATE(prop)**
Set **BT_OTS_OBJ_PROP_TRUNCATE** property.

**Parameters**
• prop – Object properties.
BT_OTS_OBJ_SET_PROP_PATCH(prop)
    Set $BT_OTS_OBJ_PROP_PATCH$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_SET_PROP_MARKED(prop)
    Set $BT_OTS_OBJ_SET_PROP_MARKED$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_DELETE(prop)
    Get $BT_OTS_OBJ_PROP_DELETE$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_EXECUTE(prop)
    Get $BT_OTS_OBJ_PROP_EXECUTE$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_READ(prop)
    Get $BT_OTS_OBJ_PROP_READ$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_WRITE(prop)
    Get $BT_OTS_OBJ_PROP_WRITE$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_APPEND(prop)
    Get $BT_OTS_OBJ_PROP_APPEND$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_TRUNCATE(prop)
    Get $BT_OTS_OBJ_PROP_TRUNCATE$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_PATCH(prop)
    Get $BT_OTS_OBJ_PROP_PATCH$ property.

Parameters
    • prop – Object properties.

BT_OTS_OBJ_GET_PROP_MARKED(prop)
    Get $BT_OTS_OBJ_PROP_MARKED$ property.

Parameters
    • prop – Object properties.
BT_OTS_OACP_SET_FEAT_CREATE(feat)
    Set `BT_OTS_OACP_SET_FEAT_CREATE` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_DELETE(feat)
    Set `BT_OTS_OACP_FEAT_DELETE` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_CHECKSUM(feat)
    Set `BT_OTS_OACP_FEAT_CHECKSUM` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_EXECUTE(feat)
    Set `BT_OTS_OACP_FEAT_EXECUTE` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_READ(feat)
    Set `BT_OTS_OACP_FEAT_READ` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_WRITE(feat)
    Set `BT_OTS_OACP_FEAT_WRITE` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_APPEND(feat)
    Set `BT_OTS_OACP_FEAT_APPEND` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_TRUNCATE(feat)
    Set `BT_OTS_OACP_FEAT_TRUNCATE` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_PATCH(feat)
    Set `BT_OTS_OACP_FEAT_PATCH` feature.
    
    Parameters
    • `feat` – OTS features.

BT_OTS_OACP_SET_FEAT_ABORT(feat)
    Set `BT_OTS_OACP_FEAT_ABORT` feature.
    
    Parameters
    • `feat` – OTS features.
Get `BT_OTS_OACP_FEAT_CREATE` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_DELETE` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_CHECKSUM` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_EXECUTE` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_READ` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_WRITE` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_APPEND` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_TRUNCATE` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_PATCH` feature.

**Parameters**

- `feat` – OTS features.

Get `BT_OTS_OACP_FEAT_ABORT` feature.

**Parameters**

- `feat` – OTS features.
BT_OTS_OLCP_SET_FEAT_GO_TO(\texttt{feat})
Set \texttt{BT_OTS_OLCP_FEAT_GO_TO} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_SET_FEAT_ORDER(\texttt{feat})
Set \texttt{BT_OTS_OLCP_FEAT_ORDER} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_SET_FEAT_NUM_REQ(\texttt{feat})
Set \texttt{BT_OTS_OLCP_FEAT_NUM_REQ} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_SET_FEAT_CLEAR(\texttt{feat})
Set \texttt{BT_OTS_OLCP_FEAT_CLEAR} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_GET_FEAT_GO_TO(\texttt{feat})
Get \texttt{BT_OTS_OLCP_GET_FEAT_GO_TO} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_GET_FEAT_ORDER(\texttt{feat})
Get \texttt{BT_OTS_OLCP_GET_FEAT_ORDER} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_GET_FEAT_NUM_REQ(\texttt{feat})
Get \texttt{BT_OTS_OLCP_GET_FEAT_NUM_REQ} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_OLCP_GET_FEAT_CLEAR(\texttt{feat})
Get \texttt{BT_OTS_OLCP_GET_FEAT_CLEAR} feature.

Parameters
• \texttt{feat} – OTS features.

BT_OTS_DATE_TIME_FIELD_SIZE

BT_OTS_STOP

BT_OTS_CONTINUE

6.1. Bluetooth
**Typedefs**

typedef int (*bt_ots_client_dirlisting_cb)(struct `bt_ots_obj_metadata` *meta)

Directory listing object metadata callback.

If a directory listing is decoded using `bt_ots_client_decode_dirlisting()`, this callback will be called for each object in the directory listing.

**Param meta**
The metadata of the decoded object

**Return**
int `BT_OTS_STOP` or `BT_OTS_CONTINUE`. `BT_OTS_STOP` can be used to stop the decoding.

**Enums**

enum [anonymous]
Properties of an OTS object.

**Values:**

enumerator `BT_OTS_OBJ_PROP_DELETE` = 0
Bit 0 Deletion of this object is permitted

enumerator `BT_OTS_OBJ_PROP_EXECUTE` = 1
Bit 1 Execution of this object is permitted

enumerator `BT_OTS_OBJ_PROP_READ` = 2
Bit 2 Reading this object is permitted

enumerator `BT_OTS_OBJ_PROP_WRITE` = 3
Bit 3 Writing data to this object is permitted

enumerator `BT_OTS_OBJ_PROP_APPEND` = 4
Bit 4 Appending data to this object is permitted.

Appending data increases its Allocated Size.

enumerator `BT_OTS_OBJ_PROP_TRUNCATE` = 5
Bit 5 Truncation of this object is permitted

enumerator `BT_OTS_OBJ_PROP_PATCH` = 6
Bit 6 Patching this object is permitted.

Patching this object overwrites some of the object’s existing contents.
enumerator BT_OTS_OBJ_PROP_MARKED = 7
   Bit 7 This object is a marked object

enum [anonymous]
   Object Action Control Point Feature bits.
   Values:

   enumerator BT_OTS_OACP_FEAT_CREATE = 0
      Bit 0 OACP Create Op Code Supported

   enumerator BT_OTS_OACP_FEAT_DELETE = 1
      Bit 1 OACP Delete Op Code Supported

   enumerator BT_OTS_OACP_FEAT_CHECKSUM = 2
      Bit 2 OACP Calculate Checksum Op Code Supported

   enumerator BT_OTS_OACP_FEAT_EXECUTE = 3
      Bit 3 OACP Execute Op Code Supported

   enumerator BT_OTS_OACP_FEAT_READ = 4
      Bit 4 OACP Read Op Code Supported

   enumerator BT_OTS_OACP_FEAT_WRITE = 5
      Bit 5 OACP Write Op Code Supported

   enumerator BT_OTS_OACP_FEAT_APPEND = 6
      Bit 6 Appending Additional Data to Objects Supported

   enumerator BT_OTS_OACP_FEAT_TRUNCATE = 7
      Bit 7 Truncation of Objects Supported

   enumerator BT_OTS_OACP_FEAT_PATCH = 8
      Bit 8 Patching of Objects Supported

   enumerator BT_OTS_OACP_FEAT_ABORT = 9
      Bit 9 OACP Abort Op Code Supported

enum bt_ots_oacp_write_op_mode
   Values:

   enumerator BT_OTS_OACP_WRITE_OP_MODE_NONE = 0

   enumerator BT_OTS_OACP_WRITE_OP_MODE_TRUNCATE = BIT(1)

enum [anonymous]
   Object List Control Point Feature bits.
   Values:
enumerator BT_OTS_OLCP_FEAT_GO_TO = 0
    Bit 0 OLCP Go To Op Code Supported
enumerator BT_OTS_OLCP_FEAT_ORDER = 1
    Bit 1 OLCP Order Op Code Supported
enumerator BT_OTS_OLCP_FEAT_NUM_REQ = 2
    Bit 2 OLCP Request Number of Objects Op Code Supported
enumerator BT_OTS_OLCP_FEAT_CLEAR = 3
    Bit 3 OLCP Clear Marking Op Code Supported

enum [anonymous]
    Object metadata request bit field values.
    Values:

    enumerator BT_OTS_METADATA_REQ_NAME = BIT(0)
        Request object name.
enumerator BT_OTS_METADATA_REQ_TYPE = BIT(1)
    Request object type.
enumerator BT_OTS_METADATA_REQ_SIZE = BIT(2)
    Request object size.
enumerator BT_OTS_METADATA_REQ_CREATED = BIT(3)
    Request object first created time.
enumerator BT_OTS_METADATA_REQ_MODIFIED = BIT(4)
    Request object last modified time.
enumerator BT_OTS_METADATA_REQ_ID = BIT(5)
    Request object ID.
enumerator BT_OTS_METADATA_REQ_PROPS = BIT(6)
    Request object properties.
enumerator BT_OTS_METADATA_REQ_ALL = 0x7F
    Request all object metadata.

Functions

int bt_ots_obj_add(struct bt_ots *ots, const struct bt_ots_obj_add_param *param)
    Add an object to the OTS instance.
    This function adds an object to the OTS database. When the object is being added, a callback
    obj_created() is called to notify the user about a new object ID.

    Parameters
        • ots – OTS instance.
• param – Object addition parameters.

Returns
ID of created object in case of success.

Returns
negative value in case of error.

int bt_ots_obj_delete(struct bt_ots *ots, uint64_t id)
Delete an object from the OTS instance.
This function deletes an object from the OTS database. When the object is deleted a callback
obj_deleted() is called to notify the user about this event. At this point, it is possible to free
allocated buffer for object data.

Parameters
• ots – OTS instance.
• id – ID of the object to be deleted (uint48).

Returns
0 in case of success or negative value in case of error.

void *bt_ots_svc_decl_get(struct bt_ots *ots)
Get the service declaration attribute.
This function is enabled for CONFIG_BT_OTS_SECONDARY_SVC configuration. The first ser-
vice attribute can be included in any other GATT service.

Parameters
• ots – OTS instance.

Returns
The first OTS attribute instance.

int bt_ots_init(struct bt_ots *ots, struct bt_ots_init *ots_init)
Initialize the OTS instance.

Parameters
• ots – OTS instance.
• ots_init – OTS initialization descriptor.

Returns
0 in case of success or negative value in case of error.

struct bt_ots *bt_ots_free_instance_get(void)
Get a free instance of OTS from the pool.

Returns
OTS instance in case of success or NULL in case of error.

int bt_ots_client_register(struct bt_ots_client *ots_inst)
Register an Object Transfer Service Instance.
Register an Object Transfer Service instance discovered on the peer. Call this function when
an OTS instance is discovered (discovery is to be handled by the higher layer).

Parameters

Returns
int 0 if success, ERRNO on failure.
uint8_t bt_ots_client_indicate_handler(struct bt_conn *conn, struct bt_gatts_subscribe_params *params, const void *data, uint16_t length)

OTS Indicate Handler function. Set this function as callback for indicate handler when discovering OTS.

**Parameters**

- **conn** – Connection object. May be NULL, indicating that the peer is being unpaired.
- **params** – Subscription parameters.
- **data** – Attribute value data. If NULL then subscription was removed.
- **length** – Attribute value length.

int bt_ots_client_read_feature(struct bt_ots_client *otc_inst, struct bt_conn *conn)

Read the OTS feature characteristic.

**Parameters**

- **otc_inst** – Pointer to the OTC instance.
- **conn** – Pointer to the connection object.

**Returns**

int 0 if success, ERRNO on failure.

int bt_ots_client_select_id(struct bt_ots_client *otc_inst, struct bt_conn *conn, uint64_t obj_id)

Select an object by its Object ID.

**Parameters**

- **otc_inst** – Pointer to the OTC instance.
- **conn** – Pointer to the connection object.
- **obj_id** – Object’s ID.

**Returns**

int 0 if success, ERRNO on failure.

int bt_ots_client_select_first(struct bt_ots_client *otc_inst, struct bt_conn *conn)

Select the first object.

**Parameters**

- **otc_inst** – Pointer to the OTC instance.
- **conn** – Pointer to the connection object.

**Returns**

int 0 if success, ERRNO on failure.

int bt_ots_client_select_last(struct bt_ots_client *otc_inst, struct bt_conn *conn)

Select the last object.

**Parameters**

- **otc_inst** – Pointer to the OTC instance.
- **conn** – Pointer to the connection object.

**Returns**

int 0 if success, ERRNO on failure.
int bt_ots_client_select_next(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Select the next object.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_select_prev(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Select the previous object.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_read_object_metadata(struct bt_ots_client *otc_inst, struct bt_conn *conn,
uint8_t metadata)
Read the metadata of the current object.
The metadata are returned in the obj_metadata_read() callback.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.
• metadata – Bitfield (BT_OTS_METADATA_REQ_*) of the metadata to read.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_read_object_data(struct bt_ots_client *otc_inst, struct bt_conn *conn)
Read the data of the current selected object.
This will trigger an OACP read operation for the current size of the object with a 0 offset and then expect receiving the content via the L2CAP CoC.
The data of the object are returned in the obj_data_read() callback.

Parameters
• otc_inst – Pointer to the OTC instance.
• conn – Pointer to the connection object.

Returns
int 0 if success, ERRNO on failure.

int bt_ots_client_write_object_data(struct bt_ots_client *otc_inst, struct bt_conn *conn,
const void *buf, size_t len, off_t offset, enum
bt_ots_oacp_write_op_mode mode)
Write the data of the current selected object.
This will trigger an OACP write operation for the current size of the object with a specified offset and then expect transferring the content via the L2CAP CoC.
The length of the data written to object is returned in the obj_data_written() callback.

Parameters
• otc_inst – Pointer to the OTC instance.
• `conn` – Pointer to the connection object.
• `buf` – Pointer to the data buffer to be written.
• `len` – Size of data.
• `offset` – Offset to write, usually 0.
• `mode` – Mode Parameter for OACP Write Op Code. See `bt_ots_oacp_write_op_mode`.

Returns
int 0 if success, ERRNO on failure.

```c
int bt_ots_client_decode_dirlisting(uint8_t *data, uint16_t length, bt_ots_client_dirlisting_cb cb)
```
Decode Directory Listing object into object metadata.
If the Directory Listing object contains multiple objects, then the callback will be called for each of them.

Parameters
• `data` – The data received for the directory listing object.
• `length` – Length of the data.
• `cb` – The callback that will be called for each object.

```c
static inline int bt_ots_obj_id_to_str(uint64_t obj_id, char *str, size_t len)
```
Converts binary OTS Object ID to string.

Parameters
• `obj_id` – Object ID.
• `str` – Address of user buffer with enough room to store formatted string containing binary Object ID.
• `len` – Length of data to be copied to user string buffer. Refer to `BT_OTS_OBJ_ID_STR_LEN` about recommended value.

Returns
Number of successfully formatted bytes from binary ID.

```c
void bt_ots_metadata_display(struct bt_ots_obj_metadata *metadata, uint16_t count)
```
Displays one or more object metadata as text with LOG_INF.

Parameters
• `metadata` – Pointer to the first (or only) metadata in an array.
• `count` – Number of metadata objects to display information of.

```c
struct bt_ots_obj_type
#include <ots.h> Type of an OTS object.
```

```c
struct bt_ots_obj_size
#include <ots.h> Descriptor for OTS Object Size parameter.
```

Public Members

```c
uint32_t cur
Current Size.
```
### Public Members

#### uint32_t alloc

Allocated Size.

#### struct bt_ots_feat

*include <ots.h>* Features of the OTS.

#### struct bt_ots_date_time

*include <ots.h>* Date and Time structure.

#### struct bt_ots_obj_metadata

*include <ots.h>* Metadata of an OTS object.

Used by the server as a descriptor for OTS object initialization. Used by the client to present object metadata to the application.

### Public Members

#### struct bt_ots_obj_type type

Object Type.

#### struct bt_ots_obj_size size

Object Size.

#### uint32_t props

Object Properties.

#### struct bt_ots_obj_add_param

*include <ots.h>* Descriptor for OTS object addition.

### Public Members

#### uint32_t size

Object size to allocate.

#### struct bt_ots_obj_type type

Object type.

#### struct bt_ots_obj_created_desc

*include <ots.h>* Descriptor for OTS created object.

Descriptor for OTS object created by the application. This descriptor is returned by `bt_ots_cb::obj_created` callback which contains further documentation on distinguishing between server and client object creation.

### Public Members
char *name
Object name.
The object name as a NULL terminated string.
When the server creates a new object the name shall be > 0 and <= BT_OTS_OBJ_MAX_NAME_LEN When the client creates a new object the name shall be an empty string

struct bt_ots_obj_size size
Object size.
bt_ots_obj_size::alloc shall be >= bt_ots_obj_add_param::size
When the server creates a new object bt_ots_obj_size::cur shall be <= bt_ots_obj_add_param::size When the client creates a new object bt_ots_obj_size::cur shall be 0

uint32_t props
Object properties.

struct bt_ots_cb
#include <ots.h> OTS callback structure.

Public Members

int (*obj_created)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const struct bt_ots_obj_add_param *add_param, struct bt_ots_obj_created_desc *created_desc)
Object created callback.
This callback is called whenever a new object is created. Application can reject this request by returning an error when it does not have necessary resources to hold this new object. This callback is also triggered when the server creates a new object with bt_ots_obj_add() API.

Param ots
OTS instance.

Param conn
The connection that is requesting object creation or NULL if object is created by bt_ots_obj_add().

Param id
Object ID.

Param add_param
Object creation requested parameters.

Param created_desc
Created object descriptor that shall be filled by the receiver of this callback.

Return
0 in case of success or negative value in case of error.

Return
-ENOTSUP if object type is not supported

Return
-ENOMEM if no available space for new object.

Return
-EINVAL if an invalid parameter is provided

Return
other negative values are treated as a generic operation failure
int (*obj_deleted)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id)

Object deleted callback.

This callback is called whenever an object is deleted. It is also triggered when the server deletes an object with bt_ots_obj_delete() API.

**Param**
- **ots**: OTS instance.
- **conn**: The connection that deleted the object or NULL if this request came from the server.
- **id**: Object ID.

**RetVal**
- When an error is indicated by using a negative value, the object delete procedure is aborted and a corresponding failed status is returned to the client.
- **Return**: 0 in case of success.
- -EBUSY if the object is locked. This is generally not expected to be returned by the application as the OTS layer tracks object accesses. An object locked status is returned to the client.
- Other negative values in case of error. A generic operation failed status is returned to the client.

void (*obj_selected)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id)

Object selected callback.

This callback is called on successful object selection.

**Param**
- **ots**: OTS instance.
- **conn**: The connection that selected new object.
- **id**: Object ID.

ssize_t (*obj_read)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, void **data, size_t len, off_t offset)

Object read callback.

This callback is called multiple times during the Object read operation. OTS module will keep requesting successive Object fragments from the application until the read operation is completed. The end of read operation is indicated by NULL data parameter.

**Param**
- **ots**: OTS instance.
- **conn**: The connection that read object.
- **id**: Object ID.
- **data**: In: NULL once the read operations is completed. Out: Next chunk of data to be sent.
- **len**: Remaining length requested by the client.
- **offset**: Object data offset.

**Return**
- Data length to be sent via data parameter. This value shall be smaller or equal
to the len parameter.

Return
Negative value in case of an error.

ssize_t (*obj_write)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const void *data, size_t len, off_t offset, size_t rem)
Object write callback.

This callback is called multiple times during the Object write operation. OTS module will keep providing successive Object fragments to the application until the write operation is completed. The offset and length of each write fragment is validated by the OTS module to be within the allocated size of the object. The remaining length indicates data length remaining to be written and will decrease each write iteration until it reaches 0 in the last write fragment.

Param ots
OTS instance.

Param conn
The connection that wrote object.

Param id
Object ID.

Param data
Next chunk of data to be written.

Param len
Length of the current chunk of data in the buffer.

Param offset
Object data offset.

Param rem
Remaining length in the write operation.

Return
Number of bytes written in case of success, if the number of bytes written does not match len, -EIO is returned to the L2CAP layer.

Return
A negative value in case of an error.

Return
-EINPROGRESS has a special meaning and is unsupported at the moment. It should not be returned.

void (*obj_name_written)(struct bt_ots *ots, struct bt_conn *conn, uint64_t id, const char *cur_name, const char *new_name)
Object name written callback.

This callback is called when the object name is written. This is a notification to the application that the object name will be updated by the OTS service implementation.

Param ots
OTS instance.

Param conn
The connection that wrote object name.

Param id
Object ID.

Param cur_name
Current object name.

Param new_name
New object name.
#include <ots.h> OTS client instance.

struct bt_ots_client_cb
#include <ots.h> OTS client callback structure

Public Members

void (*obj_selected)(struct bt_ots_client *ots_inst, struct bt_conn *conn, int err)
   Callback function when a new object is selected.
   Called when the a new object is selected and the current object has changed. The
   cur_object in ots_inst will have been reset, and metadata should be read again with
   bt_ots_client_read_object_metadata().
   Param ots_inst
       Pointer to the OTC instance.
   Param conn
       The connection to the peer device.
   Param err
       Error code (bt_otsOlcp_res_code).

int (*obj_data_read)(struct bt_ots_client *ots_inst, struct bt_conn *conn, uint32_t offset,
                                  uint32_t len, uint8_t *data_p, bool is_complete)
   Callback function for the data of the selected object.
   Called when the data of the selected object are read using
   bt_ots_client_read_object_data().
   Param ots_inst
       Pointer to the OTC instance.
   Param conn
       The connection to the peer device.
   Param offset
       Offset of the received data.
   Param len
       Length of the received data.
   Param data_p
       Pointer to the received data.
   Param is_complete
       Indicate if the whole object has been received.
   Return
       int BT_OTS_STOP or BT_OTS_CONTINUE. BT_OTS_STOP can be used to stop
       reading.

void (*obj_metadata_read)(struct bt_ots_client *ots_inst, struct bt_conn *conn, int err,
                                  uint8_t metadata_read)
   Callback function for metadata of the selected object.
   Called when metadata of the selected object are read using
   bt_ots_client_read_object_metadata(). Not all of the metadata may have been
   initialized.
   Param ots_inst
       Pointer to the OTC instance.
   Param conn
       The connection to the peer device.
   Param err
       Error value. 0 on success, GATT error or ERRNO on fail.
**Param metadata_read**

Bitfield of the metadata that was successfully read.

```c
void (*obj_data_written)(struct bt_ots_client *ots_inst, struct bt_conn *conn, size_t len)
```

Callback function for the data of the write object.

Called when the data of the selected object is written using `bt_ots_client_write_object_data()`.

**Param ots_inst**

Pointer to the OTC instance.

**Param conn**

The connection to the peer device.

**Param len**

Length of the written data.

---

**Service Discovery Protocol (SDP)**

**API Reference**

**group bt_sdp**

Service Discovery Protocol (SDP)

---

**Defines**

- `BT_SDP_SDP_SERVER_SVCLASS`
- `BT_SDP_BROWSE_GRP_DESC_SVCLASS`
- `BT_SDP_PUBLIC_BROWSE_GROUP`
- `BT_SDP_SERIAL_PORT_SVCLASS`
- `BT_SDP_LAN_ACCESS_SVCLASS`
- `BT_SDP_DIALUP_NET_SVCLASS`
- `BT_SDP_IRMC_SYNC_SVCLASS`
- `BT_SDP_OBEX_OBJPUSH_SVCLASS`
- `BT_SDP_OBEX_FILETRANS_SVCLASS`
- `BT_SDP_IRMC_SYNC_CMD_SVCLASS`
- `BT_SDP_HEADSET_SVCLASS`
- `BT_SDP_CORDLESS_TELEPHONY_SVCLASS`
BT_SDP_AUDIO_SOURCE_SVCLASS
BT_SDP_AUDIO_SINK_SVCLASS
BT_SDP_AV_REMOTE_TARGET_SVCLASS
BT_SDP_ADVANCED_AUDIO_SVCLASS
BT_SDP_AV_REMOTE_SVCLASS
BT_SDP_AV_REMOTE_CONTROLLER_SVCLASS
BT_SDP_INTERCOM_SVCLASS
BT_SDP_FAX_SVCLASS
BT_SDP_HEADSET_AGW_SVCLASS
BT_SDP_WAP_SVCLASS
BT_SDP_WAP_CLIENT_SVCLASS
BT_SDP_PANU_SVCLASS
BT_SDP_NAP_SVCLASS
BT_SDP_GN_SVCLASS
BT_SDP_DIRECT_PRINTING_SVCLASS
BT_SDP_REFERENCE_PRINTING_SVCLASS
BT_SDP_IMAGING_SVCLASS
BT_SDP_IMAGING_RESPONDER_SVCLASS
BT_SDP_IMAGING_ARCHIVE_SVCLASS
BT_SDP_IMAGING_REFOBJ_SVCLASS
BT_SDP_HANDSFREE_SVCLASS
BT_SDP_HANDSFREE_AGW_SVCLASS
BT_SDP_DIRECT_PRT_REF_OBJ_SVCLASS
BT_SDP_PNP_INFO_SVCLASS

BT_SDP_GENERIC_NETWORKING_SVCLASS

BT_SDP_GENERIC_FILETRANS_SVCLASS

BT_SDP_GENERIC_AUDIO_SVCLASS

BT_SDP_GENERIC_TELEPHONY_SVCLASS

BT_SDP_UPNP_SVCLASS

BT_SDP_UPNP_IP_SVCLASS

BT_SDP_UPNP_PAN_SVCLASS

BT_SDP_UPNP_LAP_SVCLASS

BT_SDP_UPNP_L2CAP_SVCLASS

BT_SDP_VIDEO_SOURCE_SVCLASS

BT_SDP_VIDEO_SINK_SVCLASS

BT_SDP_VIDEO_DISTRIBUTION_SVCLASS

BT_SDP_HDP_SVCLASS

BT_SDP_HDP_SOURCE_SVCLASS

BT_SDP_HDP_SINK_SVCLASS

BT_SDP_GENERIC_ACCESS_SVCLASS

BT_SDP_GENERIC_ATTRIB_SVCLASS

BT_SDP_APPLE_AGENT_SVCLASS

BT_SDP_SERVER_RECORD_HANDLE

BT_SDP_ATTR_RECORD_HANDLE

BT_SDP_ATTR_SVCLASS_ID_LIST

BT_SDP_ATTR_RECORD_STATE
BT_SDP_ATTR_SERVICE_ID

BT_SDP_ATTR_PROTO_DESC_LIST

BT_SDP_ATTR_BROWSE_GRP_LIST

BT_SDP_ATTR_LANG_BASE_ATTR_ID_LIST

BT_SDP_ATTR_SVCINFO_TTL

BT_SDP_ATTR_SERVICE_AVAILABILITY

BT_SDP_ATTR_PROFILE_DESC_LIST

BT_SDP_ATTR_DOC_URL

BT_SDP_ATTR_CLNT_EXEC_URL

BT_SDP_ATTR_ICON_URL

BT_SDP_ATTR_ADD_PROTO_DESC_LIST

BT_SDP_ATTR_GROUP_ID

BT_SDP_ATTR_IP_SUBNET

BT_SDP_ATTR_VERSION_NUM_LIST

BT_SDP_ATTR_SUPPORTED_FEATURES_LIST

BT_SDP_ATTR_GOEP_L2CAP_PSM

BT_SDP_ATTR_SVCDB_STATE

BT_SDP_ATTR_MPSD_SCENARIOS

BT_SDP_ATTR_MPMD_SCENARIOS

BT_SDP_ATTR_MPS_DEPENDENCIES

BT_SDP_ATTR_SERVICE_VERSION

BT_SDP_ATTR_EXTERNAL_NETWORK

BT_SDP_ATTR_SUPPORTED_DATA_STORES_LIST
BT_SDP_ATTR_DATA_EXCHANGE_SPEC
BT_SDP_ATTR_NETWORK
BT_SDP_ATTR_FAX_CLASS1_SUPPORT
BT_SDP_ATTR_REMOTE_AUDIO_VOLUME_CONTROL
BT_SDP_ATTR_MCAP_SUPPORTED_PROCEDURES
BT_SDP_ATTR_FAX_CLASS20_SUPPORT
BT_SDP_ATTR_SUPPORTED_FORMATS_LIST
BT_SDP_ATTR_FAX_CLASS2_SUPPORT
BT_SDP_ATTR_AUDIO_FEEDBACK_SUPPORT
BT_SDP_ATTR_NETWORK_ADDRESS
BT_SDP_ATTR_WAP_GATEWAY
BT_SDP_ATTR_HOMEPAGE_URL
BT_SDP_ATTR_WAP_STACK_TYPE
BT_SDP_ATTR_SECURITY_DESC
BT_SDP_ATTR_NET_ACCESS_TYPE
BT_SDP_ATTR_MAX_NET_ACCESSRATE
BT_SDP_ATTR_IP4_SUBNET
BT_SDP_ATTR_IP6_SUBNET
BT_SDP_ATTR_SUPPORTED_CAPABILITIES
BT_SDP_ATTR_SUPPORTED_FEATURES
BT_SDP_ATTR_SUPPORTED_FUNCTIONS
BT_SDP_ATTR_TOTAL_IMAGING_DATA_CAPACITY
BT_SDP_ATTR_SUPPORTED_REPOSITORIES
BT_SDP_ATTR_MAS_INSTANCE_ID
BT_SDP_ATTR_SUPPORTED_MESSAGE_TYPES
BT_SDP_ATTR_PBAP_SUPPORTED_FEATURES
BT_SDP_ATTR_MAP_SUPPORTED_FEATURES
BT_SDP_ATTR_SPECIFICATION_ID
BT_SDP_ATTR_VENDOR_ID
BT_SDP_ATTR_PRODUCT_ID
BT_SDP_ATTR_VERSION
BT_SDP_ATTR_PRIMARY_RECORD
BT_SDP_ATTR_VENDOR_ID_SOURCE
BT_SDP_ATTR_HID_DEVICE_RELEASE_NUMBER
BT_SDP_ATTR_HID_PARSER_VERSION
BT_SDP_ATTR_HID_DEVICE_SUBCLASS
BT_SDP_ATTR_HID_COUNTRY_CODE
BT_SDP_ATTR_HID_VIRTUAL_CABLE
BT_SDP_ATTR_HID_RECONNECT_INITIATE
BT_SDP_ATTR_HID_DESCRIPTOR_LIST
BT_SDP_ATTR_HID_LANG_ID_BASE_LIST
BT_SDP_ATTR_HID_SDP_DISABLE
BT_SDP_ATTR_HID_BATTERY_POWER
BT_SDP_ATTR_HID_REMOTE_WAKEUP
BT_SDP_ATTR_HID_PROFILE_VERSION
BT_SDP_ATTR_HID_SUPERVISION_TIMEOUT
BT_SDP_ATTR_HID_NORMALLY_CONNECTABLE

BT_SDP_ATTR_HID_BOOT_DEVICE

BT_SDP_PRIMARY_LANG_BASE

BT_SDP_ATTR_SVCNAME_PRIMARY

BT_SDP_ATTR_SVCDESC_PRIMARY

BT_SDP_ATTR_PROVNAME_PRIMARY

BT_SDP_DATA_NIL

BT_SDP_UINT8

BT_SDP_UINT16

BT_SDP_UINT32

BT_SDP_UINT64

BT_SDP_UINT128

BT_SDP_INT8

BT_SDP_INT16

BT_SDP_INT32

BT_SDP_INT64

BT_SDP_INT128

BT_SDP_UUID_UNSPEC

BT_SDP_UUID16

BT_SDP_UUID32

BT_SDP_UUID128

BT_SDP_TEXT_STR_UNSPEC

BT_SDP_TEXT_STR8
Declare an array of 8-bit elements in an attribute.

**BT_SDP_ARRAY_8(...)**

Declare an array of 16-bit elements in an attribute.

**BT_SDP_ARRAY_16(...)**

Declare an array of 32-bit elements in an attribute.

**BT_SDP_ARRAY_32(...)**

Declare a fixed-size data element header.

**Parameters**

- `_type` – Data element header containing type and size descriptors.
BT_SDP_TYPE_SIZE_VAR(_type, _size)
Declare a variable-size data element header.

**Parameters**
- _type – Data element header containing type and size descriptors.
- _size – The actual size of the data.

BT_SDP_DATA_ELEM_LIST(...) 
Declare a list of data elements.

BT_SDP_NEW_SERVICE
SDP New Service Record Declaration Macro.
Helper macro to declare a new service record. Default attributes: Record Handle, Record State, Language Base, Root Browse Group

BT_SDP_LIST(_att_id, _type_size, _data_elem_seq)
Generic SDP List Attribute Declaration Macro.
Helper macro to declare a list attribute.

**Parameters**
- _att_id – List Attribute ID.
- _data_elem_seq – Data element sequence for the list.
- _type_size – SDP type and size descriptor.

BT_SDP_SERVICE_ID(_uuid)
SDP Service ID Attribute Declaration Macro.
Helper macro to declare a service ID attribute.

**Parameters**
- _uuid – Service ID 16bit UUID.

BT_SDP_SERVICE_NAME(_name)
SDP Name Attribute Declaration Macro.
Helper macro to declare a service name attribute.

**Parameters**
- _name – Service name as a string (up to 256 chars).

BT_SDP_SUPPORTED_FEATURES(_features)
SDP Supported Features Attribute Declaration Macro.
Helper macro to declare supported features of a profile/protocol.

**Parameters**
- _features – Feature mask as 16bit unsigned integer.

BT_SDP_RECORD(_attrs)
SDP Service Declaration Macro.
Helper macro to declare a service.

**Parameters**
- _attrs – List of attributes for the service record.
Typedefs

typedef uint8_t (*bt_sdp_discover_func_t)(struct bt_conn *conn, struct bt_sdp_client_result *result)

Callback type reporting to user that there is a resolved result on remote for given UUID and the result record buffer can be used by user for further inspection.

A function of this type is given by the user to the bt_sdp_discover_params object. It'll be called on each valid record discovery completion for given UUID. When UUID resolution gives back no records then NULL is passed to the user. Otherwise user can get valid record(s) and then the internal hint 'next record' is set to false saying the UUID resolution is complete or the hint can be set by caller to true meaning that next record is available for given UUID. The returned function value allows the user to control retrieving follow-up resolved records if any. If the user doesn't want to read more resolved records for given UUID since current record data fulfills its requirements then should return BT_SDP_DISCOVER_UUID_STOP. Otherwise returned value means more subcall iterations are allowable.

**Param conn**
Connection object identifying connection to queried remote.

**Param result**
Object pointing to logical unparsed SDP record collected on base of response driven by given UUID.

**Return**
BT_SDP_DISCOVER_UUID_STOP in case of no more need to read next record data and continue discovery for given UUID. By returning BT_SDP_DISCOVER_UUID_CONTINUE user allows this discovery continuation.

Enums

enum [anonymous]
Helper enum to be used as return value of bt_sdp_discover_func_t. The value informs the caller to perform further pending actions or stop them.

**Values:**

enumerator BT_SDP_DISCOVER_UUID_STOP = 0

enumerator BT_SDP_DISCOVER_UUID_CONTINUE

enum bt_sdp_proto
Protocols to be asked about specific parameters.

**Values:**

enumerator BT_SDP_PROTO_RFCOMM = 0x0003

enumerator BT_SDP_PROTO_L2CAP = 0x0100

Functions
int bt_sdp_register_service(struct bt_sdp_record *service)

Register a Service Record. Applications can make use of macros such as BT_SDP_DECLARE_SERVICE, BT_SDP_LIST, BT_SDP_SERVICE_ID, BT_SDP_SERVICE_NAME, etc. A service declaration must start with BT_SDP_NEW_SERVICE.

**Parameters**

- service – Service record declared using BT_SDP_DECLARE_SERVICE.

**Returns**

0 in case of success or negative value in case of error.

int bt_sdp_discover(struct bt_conn *conn, const struct bt_sdp_discover_params *params)

Allows user to start SDP discovery session.

The function performs SDP service discovery on remote server driven by user delivered discovery parameters. Discovery session is made as soon as no SDP transaction is ongoing between peers and if any then this one is queued to be processed at discovery completion of previous one. On the service discovery completion the callback function will be called to get feedback to user about findings.

**Parameters**

- conn – Object identifying connection to remote.
- params – SDP discovery parameters.

**Returns**

0 in case of success or negative value in case of error.

int bt_sdp_discover_cancel(struct bt_conn *conn, const struct bt_sdp_discover_params *params)

Release waiting SDP discovery request.

It can cancel valid waiting SDP client request identified by SDP discovery parameters object.

**Parameters**

- conn – Object identifying connection to remote.
- params – SDP discovery parameters.

**Returns**

0 in case of success or negative value in case of error.

int bt_sdp_get_proto_param(const struct net_buf *buf, enum bt_sdp_proto proto, uint16_t *param)

Give to user parameter value related to given stacked protocol UUID.

API extracts specific parameter associated with given protocol UUID available in Protocol Descriptor List attribute.

**Parameters**

- buf – Original buffered raw record data.
- proto – Known protocol to be checked like RFCOMM or L2CAP.
- param – On success populated by found parameter value.

**Returns**

0 on success when specific parameter associated with given protocol value is found, or negative if error occurred during processing.
Get additional parameter value related to given stacked protocol UUID.

API extracts specific parameter associated with given protocol UUID available in Additional Protocol Descriptor List attribute.

**Parameters**

- **buf** – Original buffered raw record data.
- **proto** – Known protocol to be checked like RFCOMM or L2CAP.
- **param_index** – There may be more than one parameter related to the given protocol UUID. This function returns the result that is indexed by this parameter. It’s value is from 0, 0 means the first matched result, 1 means the second matched result.
- **param** – [out] On success populated by found parameter value.

**Returns**

0 on success when a specific parameter associated with a given protocol value is found, or negative if error occurred during processing.

Get profile version.

Helper API extracting remote profile version number. To get it proper generic profile parameter needs to be selected usually listed in SDP Interoperability Requirements section for given profile specification.

**Parameters**

- **buf** – Original buffered raw record data.
- **profile** – Profile family identifier the profile belongs.
- **version** – On success populated by found version number.

**Returns**

0 on success, negative value if error occurred during processing.

Get SupportedFeatures attribute value.

Allows if exposed by remote retrieve SupportedFeature attribute.

**Parameters**

- **buf** – Buffer holding original raw record data from remote.
- **features** – On success object to be populated with SupportedFeature mask.

**Returns**

0 on success if feature found and valid, negative in case any error

SDP Generic Data Element Value.

SDP Attribute Value.

SDP Service Record Value.
struct bt_sdp_client_result
   #include <sdp.h> Generic SDP Client Query Result data holder.

struct bt_sdp_discover_params
   #include <sdp.h> Main user structure used in SDP discovery of remote.

   Public Members

   const struct bt_uuid *uuid
       UUID (service) to be discovered on remote SDP entity

   bt_sdp_discover_func_t func
       Discover callback to be called on resolved SDP record

   struct net_buf_pool *pool
       Memory buffer enabled by user for SDP query results

Bluetooth Audio Volume Control

API Reference

group bt_gatt_vcp
    Volume Control Profile (VCP)
    [Experimental] Users should note that the APIs can change as a part of ongoing development.

Defines

BT_VCP_VOL_REND_VOCS_CNT

BT_VCP_VOL_REND_AICS_CNT

BT_VCP_ERR_INVALID_COUNTER
    Volume Control Service Error codes

BT_VCP_ERR_OP_NOT_SUPPORTED

BT_VCP_STATE_UNMUTED
    Volume Control Service Mute Values

BT_VCP_STATE_MUTED

Functions

6.1. Bluetooth
```c
int bt_vcp_vol_rend_included_get(struct bt_vcp_included *included)
Get Volume Control Service included services.
Returns a pointer to a struct that contains information about the Volume Control Service included service instances, such as pointers to the Volume Offset Control Service (Volume Offset Control Service) or Audio Input Control Service (AICS) instances.

Parameters
    • included – [out] Pointer to store the result in.

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_register(struct bt_vcp_vol_rend_register_param *param)
Register the Volume Control Service.
This will register and enable the service and make it discoverable by clients.

Parameters
    • param – Volume Control Service register parameters.

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_set_step(uint8_t volume_step)
Set the Volume Control Service volume step size.
Set the value that the volume changes, when changed relatively with e.g. bt_vcp_vol_rend_vol_down or bt_vcp_vol_rend_vol_up.
This can only be done as the server.

Parameters
    • volume_step – The volume step size (1-255).

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_get_state(void)
Get the Volume Control Service volume state.

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_get_flags(void)
Get the Volume Control Service flags.

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_vol_down(void)
Turn the volume down by one step on the server.

Returns
    0 if success, errno on failure.
```

```c
int bt_vcp_vol_rend_vol_up(void)
Turn the volume up by one step on the server.

Returns
    0 if success, errno on failure.
```
int bt_vcp_vol_rend_unmute_vol_down(void)
Turn the volume down and unmute the server.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_rend_unmute_vol_up(void)
Turn the volume up and unmute the server.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_rend_set_vol(uint8_t volume)
Set the volume on the server.

**Parameters**
- volume – The absolute volume to set.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_rend_unmute(void)
Unmute the server.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_rend_mute(void)
Mute the server.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_ctlr_cb_register(struct bt_vcp_vol_ctlr_cb *cb)
Registers the callbacks used by the Volume Controller.

**Parameters**
- cb – The callback structure.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_ctlr_discover(struct bt_conn *conn, struct bt_vcp_vol_ctlr **vol_ctlr)
Discover Volume Control Service and included services.

This will start a GATT discovery and setup handles and subscriptions. This shall be called once before any other actions can be executed for the peer device, and the \texttt{bt\_vcp\_vol\_ctlr\_cb::discover} callback will notify when it is possible to start remote operations.

This shall only be done as the client,

**Parameters**
- conn – The connection to discover Volume Control Service for.

**Returns**
0 if success, errno on failure.

int bt_vcp_vol_ctlr_conn_get(const struct bt_vcp_vol_ctlr *vol_ctlr, struct bt_conn **conn)
Get the connection pointer of a client instance.

Get the Bluetooth connection pointer of a Volume Control Service client instance.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.
• `conn` – [out] Connection pointer.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_included_get(struct bt_vcp_vol_ctlr *vol_ctlr, struct bt_vcp_included *included)
```

Get Volume Control Service included services.

Returns a pointer to a struct that contains information about the Volume Control Service included service instances, such as pointers to the Volume Offset Control Service (Volume Offset Control Service) or Audio Input Control Service (AICS) instances.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.
• `included` – [out] Pointer to store the result in.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_read_state(struct bt_vcp_vol_ctlr *vol_ctlr)
```

Read the volume state of a remote Volume Renderer.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_read_flags(struct bt_vcp_vol_ctlr *vol_ctlr)
```

Read the volume flags of a remote Volume Renderer.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_vol_down(struct bt_vcp_vol_ctlr *vol_ctlr)
```

Turn the volume down one step on a remote Volume Renderer.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_vol_up(struct bt_vcp_vol_ctlr *vol_ctlr)
```

Turn the volume up one step on a remote Volume Renderer.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.

**Returns**
0 if success, errno on failure.

```c
int bt_vcp_vol_ctlr_unmute_vol_down(struct bt_vcp_vol_ctlr *vol_ctlr)
```

Turn the volume down one step and unmute on a remote Volume Renderer.

**Parameters**
• `vol_ctlr` – Volume Controller instance pointer.
Returns
0 if success, errno on failure.

int bt_vcp_vol_ctlr_unmute_vol_up(struct bt_vcp_vol_ctlr *vol_ctlr)
Turn the volume up one step and unmute on a remote Volume Renderer.

Parameters
• vol_ctlr – Volume Controller instance pointer.

Returns
0 if success, errno on failure.

int bt_vcp_vol_ctlr_set_vol(struct bt_vcp_vol_ctlr *vol_ctlr, uint8_t volume)
Set the absolute volume on a remote Volume Renderer.

Parameters
• vol_ctlr – Volume Controller instance pointer.
• volume – The absolute volume to set.

Returns
0 if success, errno on failure.

int bt_vcp_vol_ctlr_unmute(struct bt_vcp_vol_ctlr *vol_ctlr)
Unmute a remote Volume Renderer.

Parameters
• vol_ctlr – Volume Controller instance pointer.

Returns
0 if success, errno on failure.

int bt_vcp_vol_ctlr_mute(struct bt_vcp_vol_ctlr *vol_ctlr)
Mute a remote Volume Renderer.

Parameters
• vol_ctlr – Volume Controller instance pointer.

Returns
0 if success, errno on failure.

struct bt_vcp_vol_rend_register_param
#include <vcp.h> Register structure for Volume Control Service

Public Members

uint8_t step
Initial step size (1-255)

uint8_t mute
Initial mute state (0-1)

uint8_t volume
Initial volume level (0-255)

struct bt_vocs_register_param vocs_param[0]
Register parameters for Volume Offset Control Services
struct bt_aics_register_param aics_param[0]
    Register parameters for Audio Input Control Services

struct bt_vcp_vol_rend_cb *cb
    Volume Control Service callback structure.

struct bt_vcp_included
    #include <vcp.h> Volume Control Service included services.
    Used for to represent the Volume Control Service included service instances, for either a client or a server. The instance pointers either represent local server instances, or remote service instances.

**Public Members**

uint8_t vocs_cnt
    Number of Volume Offset Control Service instances

struct bt_vocs **vocs
    Array of pointers to Volume Offset Control Service instances

uint8_t aics_cnt
    Number of Audio Input Control Service instances

struct bt_aics **aics
    Array of pointers to Audio Input Control Service instances

struct bt_vcp_vol_rend_cb
    #include <vcp.h>

**Public Members**

void (*state)(int err, uint8_t volume, uint8_t mute)
    Callback function for Volume Control Service volume state.
    Called when the value is locally read with bt_vcp_vol_rend_get_state(), or if the state is changed by either the Volume Renderer or a remote Volume Controller.
    **Param err**
    Error value. 0 on success, GATT error on positive value or errno on negative value.
    **Param volume**
    The volume of the Volume Control Service server.
    **Param mute**
    The mute setting of the Volume Control Service server.

void (*flags)(int err, uint8_t flags)
    Callback function for Volume Control Service flags.
    Called when the value is locally read as the server. Called when the value is remotely read as the client. Called if the value is changed by either the server or client.
Param err
Error value. 0 on success, GATT error on positive value or errno on negative value.

Param flags
The flags of the Volume Control Service server.

```c
#include <vcp.h>
```

Public Members

```c
void (*state)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t volume, uint8_t mute)
```

Callback function for Volume Control Profile volume state. Called when the value is remotely read as the Volume Controller. Called if the value is changed by either the Volume Renderer or Volume Controller, and notified to the to Volume Controller.

- **Param vol_ctlr**: Volume Controller instance pointer.
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param volume**: The volume of the Volume Renderer.
- **Param mute**: The mute setting of the Volume Renderer.

```c
void (*flags)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t flags)
```

Callback function for Volume Control Profile volume flags. Called when the value is remotely read as the Volume Controller. Called if the value is changed by the Volume Renderer.

A non-zero value indicates the the volume has been changed on the Volume Renderer since it was booted.

- **Param vol_ctlr**: Volume Controller instance pointer.
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param flags**: The flags of the Volume Renderer.

```c
void (*discover)(struct bt_vcp_vol_ctlr *vol_ctlr, int err, uint8_t vocs_count, uint8_t aics_count)
```

Callback function for `bt_vcp_vol_ctlr_discover()`.

This callback is called once the discovery procedure is completed.

- **Param vol_ctlr**: Volume Controller instance pointer.
- **Param err**: Error value. 0 on success, GATT error on positive value or errno on negative value.
- **Param vocs_count**: Number of Volume Offset Control Service instances on the remote Volume Renderer.
**Param aics_count**

Number of Audio Input Control Service instances the remote Volume Renderer.

```c
void (*vol_down)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_vol_down()`. Called when the volume down procedure is completed.

- **Param vol_ctlr**
  Volume Controller instance pointer.

- **Param err**
  Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_up)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_vol_up()`. Called when the volume up procedure is completed.

- **Param vol_ctlr**
  Volume Controller instance pointer.

- **Param err**
  Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*mute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_mute()`. Called when the mute procedure is completed.

- **Param vol_ctlr**
  Volume Controller instance pointer.

- **Param err**
  Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_unmute()`. Called when the unmute procedure is completed.

- **Param vol_ctlr**
  Volume Controller instance pointer.

- **Param err**
  Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_down_unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_vol_down_unmute()`. Called when the volume down and unmute procedure is completed.

- **Param vol_ctlr**
  Volume Controller instance pointer.

- **Param err**
  Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_up_unmute)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```

Callback function for `bt_vcp_vol_ctlr_vol_up_unmute()`. Called when the volume up and unmute procedure is completed.
**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

```c
void (*vol_set)(struct bt_vcp_vol_ctlr *vol_ctlr, int err)
```
Callback function for `bt_vcp_vol_ctlr_vol_set()`.
Called when the set absolute volume procedure is completed.

**Param vol_ctlr**
Volume Controller instance pointer.

**Param err**
Error value. 0 on success, GATT error on positive value or errno on negative value.

---

**Universal Unique Identifiers (UUIDs)**

**API Reference**

**group bt_uuid**

UUIDs.

**Defines**

- **BT_UUID_SIZE_16**
  Size in octets of a 16-bit UUID

- **BT_UUID_SIZE_32**
  Size in octets of a 32-bit UUID

- **BT_UUID_SIZE_128**
  Size in octets of a 128-bit UUID

- **BT_UUID_INIT_16(value)**
  Initialize a 16-bit UUID.

  **Parameters**
  - value – 16-bit UUID value in host endianness.

- **BT_UUID_INIT_32(value)**
  Initialize a 32-bit UUID.

  **Parameters**
  - value – 32-bit UUID value in host endianness.

- **BT_UUID_INIT_128(value...)**
  Initialize a 128-bit UUID.

  **Parameters**
  - value – 128-bit UUID array values in little-endian format. Can be combined with **BT_UUID_128_ENCODE** to initialize a UUID from the readable form of UUIDs.
BT_UUID_DECLARE_16(value)
Help to declare a 16-bit UUID inline.

Parameters
• value – 16-bit UUID value in host endianness.

Returns
Pointer to a generic UUID.

BT_UUID_DECLARE_32(value)
Helper to declare a 32-bit UUID inline.

Parameters
• value – 32-bit UUID value in host endianness.

Returns
Pointer to a generic UUID.

BT_UUID_DECLARE_128(value...)
Helper to declare a 128-bit UUID inline.

Parameters
• value – 128-bit UUID array values in little-endian format. Can be combined with BT_UUID_128_ENCODE to declare a UUID from the readable form of UUIDs.

Returns
Pointer to a generic UUID.

BT_UUID_16(__u)
Helper macro to access the 16-bit UUID from a generic UUID.

BT_UUID_32(__u)
Helper macro to access the 32-bit UUID from a generic UUID.

BT_UUID_128(__u)
Helper macro to access the 128-bit UUID from a generic UUID.

BT_UUID_128_ENCODE(w32, w1, w2, w3, w48)
Encode 128 bit UUID into array values in little-endian format.

Helper macro to initialize a 128-bit UUID array value from the readable form of UUIDs, or encode 128-bit UUID values into advertising data Can be combined with BT_UUID_DECLARE_128 to declare a 128-bit UUID.

Example of how to declare the UUID 6E400001-B5A3-F393-E0A9-E50E24DCCA9E

```
BT_UUID_DECLARE_128(  
    BT_UUID_128_ENCODE(0x6E400001, 0xB5A3, 0xF393, 0xE0A9, 0xE50E24DCCA9E))
```

Example of how to encode the UUID 6E400001-B5A3-F393-E0A9-E50E24DCCA9E into advertising data.

```
BT_DATA_BYTES(BT_DATA_UUID128_ALL,  
    BT_UUID_128_ENCODE(0x6E400001, 0xB5A3, 0xF393, 0xE0A9, 0xE50E24DCCA9E))
```

Just replace the hyphen by the comma and add 0x prefixes.

Parameters
• w32 – First part of the UUID (32 bits)
• w1 – Second part of the UUID (16 bits)
• w2 – Third part of the UUID (16 bits)
• w3 – Fourth part of the UUID (16 bits)
• w48 – Fifth part of the UUID (48 bits)

**Returns**
The comma separated values for UUID 128 initializer that may be used directly as an argument for `BT_UUID_INIT_128` or `BT_UUID_DECLARE_128`.

```
BT_UUID_16_ENCODE(w16)
```
Encode 16-bit UUID into array values in little-endian format.
Helper macro to encode 16-bit UUID values into advertising data.
Example of how to encode the UUID 0x180a into advertising data.

```
BT_DATA_BYTES(BT_DATA_UUID16_ALL, BT_UUID_16_ENCODE(0x180a))
```

**Parameters**
• w16 – UUID value (16-bits)

**Returns**
The comma separated values for UUID 16 value that may be used directly as an argument for `BT_DATA_BYTES`.

```
BT_UUID_32_ENCODE(w32)
```
Encode 32-bit UUID into array values in little-endian format.
Helper macro to encode 32-bit UUID values into advertising data.
Example of how to encode the UUID 0x180a01af into advertising data.

```
BT_DATA_BYTES(BT_DATA_UUID32_ALL, BT_UUID_32_ENCODE(0x180a01af))
```

**Parameters**
• w32 – UUID value (32-bits)

**Returns**
The comma separated values for UUID 32 value that may be used directly as an argument for `BT_DATA_BYTES`.

```
BT_UUID_STR_LEN
```
Recommended length of user string buffer for Bluetooth UUID.
The recommended length guarantee the output of UUID conversion will not lose valuable information about the UUID being processed. If the length of the UUID is known the string can be shorter.

```
BT_UUID_GAP_VAL
```
Generic Access UUID value.

```
BT_UUID_GAP
```
Generic Access.

---

6.1. Bluetooth
BT_UUID_GATT_VAL
  Generic attribute UUID value.

BT_UUID_GATT
  Generic Attribute.

BT_UUID_IAS_VAL
  Immediate Alert Service UUID value.

BT_UUID_IAS
  Immediate Alert Service.

BT_UUID_LLS_VAL
  Link Loss Service UUID value.

BT_UUID_LLS
  Link Loss Service.

BT_UUID_TPS_VAL
  Tx Power Service UUID value.

BT_UUID_TPS
  Tx Power Service.

BT_UUID_CTS_VAL
  Current Time Service UUID value.

BT_UUID_CTS
  Current Time Service.

BT_UUID_HTS_VAL
  Health Thermometer Service UUID value.

BT_UUID_HTS
  Health Thermometer Service.

BT_UUID_DIS_VAL
  Device Information Service UUID value.

BT_UUID_DIS
  Device Information Service.

BT_UUID_HRS_VAL
  Heart Rate Service UUID value.

BT_UUID_HRS
  Heart Rate Service.
BT_UUID_BAS_VAL
Battery Service UUID value.

BT_UUID_BAS
Battery Service.

BT_UUID_HIDS_VAL
HID Service UUID value.

BT_UUID_HIDS
HID Service.

BT_UUID_RSCS_VAL
Running Speed and Cadence Service UUID value.

BT_UUID_RSCS
Running Speed and Cadence Service.

BT_UUID_CSC_VAL
Cycling Speed and Cadence Service UUID value.

BT_UUID_CSC
Cycling Speed and Cadence Service.

BT_UUID_ESS_VAL
Environmental Sensing Service UUID value.

BT_UUID_ESS
Environmental Sensing Service.

BT_UUID_BMS_VAL
Bond Management Service UUID value.

BT_UUID_BMS
Bond Management Service.

BT_UUID_CGMS_VAL
Continuous Glucose Monitoring Service UUID value.

BT_UUID_CGMS
Continuous Glucose Monitoring Service.

BT_UUID_IPSS_VAL
IP Support Service UUID value.

BT_UUID_IPSS
IP Support Service.
BT_UUID_HPS_VAL
    HTTP Proxy Service UUID value.

BT_UUID_HPS
    HTTP Proxy Service.

BT_UUID_OTS_VAL
    Object Transfer Service UUID value.

BT_UUID_OTS
    Object Transfer Service.

BT_UUID_MESH_PROV_VAL
    Mesh Provisioning Service UUID value.

BT_UUID_MESH_PROV
    Mesh Provisioning Service.

BT_UUID_MESH_PROXY_VAL
    Mesh Proxy Service UUID value.

BT_UUID_MESH_PROXY
    Mesh Proxy Service.

BT_UUID_AICS_VAL
    Audio Input Control Service value.

BT_UUID_AICS
    Audio Input Control Service.

BT_UUID_VCS_VAL
    Volume Control Service value.

BT_UUID_VCS
    Volume Control Service.

BT_UUID_VOCS_VAL
    Volume Offset Control Service value.

BT_UUID_VOCS
    Volume Offset Control Service.

BT_UUID_CSIS_VAL
    Coordinated Set Identification Service value.

BT_UUID_CSIS
    Coordinated Set Identification Service.
BT_UUID_MCS_VAL
  Media Control Service value.

BT_UUID_MCS
  Media Control Service.

BT_UUID_GMCS_VAL
  Generic Media Control Service value.

BT_UUID_GMCS
  Generic Media Control Service.

BT_UUID_TBS_VAL
  Telephone Bearer Service value.

BT_UUID_TBS
  Telephone Bearer Service.

BT_UUID_GTBS_VAL
  Generic Telephone Bearer Service value.

BT_UUID_GTBS
  Generic Telephone Bearer Service.

BT_UUID_MICS_VAL
  Microphone Input Control Service value.

BT_UUID_MICS
  Microphone Input Control Service.

BT_UUID_ASCS_VAL
  Audio Stream Control Service value.

BT_UUID_ASCS
  Audio Stream Control Service.

BT_UUID_BASS_VAL
  Broadcast Audio Scan Service value.

BT_UUID_BASS
  Broadcast Audio Scan Service.

BT_UUID_PACS_VAL
  Published Audio Capabilities Service value.

BT_UUID_PACS
  Published Audio Capabilities Service.
BT_UUID_BASIC_AUDIO_VAL
Basic Audio Announcement Service value.

BT_UUID_BASIC_AUDIO
Basic Audio Announcement Service.

BT_UUID_BROADCAST_AUDIO_VAL
Broadcast Audio Announcement Service value.

BT_UUID_BROADCAST_AUDIO
Broadcast Audio Announcement Service.

BT_UUID_CAS_VAL
Common Audio Service value.

BT_UUID_CAS
Common Audio Service.

BT_UUID_HAS_VAL
Hearing Access Service value.

BT_UUID_HAS
Hearing Access Service.

BT_UUID_GATT_PRIMARY_VAL
GATT Primary Service UUID value.

BT_UUID_GATT_PRIMARY
GATT Primary Service.

BT_UUID_GATT_SECONDARY_VAL
GATT Secondary Service UUID value.

BT_UUID_GATT_SECONDARY
GATT Secondary Service.

BT_UUID_GATT_INCLUDE_VAL
GATT Include Service UUID value.

BT_UUID_GATT_INCLUDE
GATT Include Service.

BT_UUID_GATT_CHRC_VAL
GATT Characteristic UUID value.

BT_UUID_GATT_CHRC
GATT Characteristic.
BT_UUID_GATT_CEP_VAL
GATT Characteristic Extended Properties UUID value.

BT_UUID_GATT_CEP
GATT Characteristic Extended Properties.

BT_UUID_GATT_CUD_VAL
GATT Characteristic User Description UUID value.

BT_UUID_GATT_CUD
GATT Characteristic User Description.

BT_UUID_GATT_CCC_VAL
GATT Client Characteristic Configuration UUID value.

BT_UUID_GATT_CCC
GATT Client Characteristic Configuration.

BT_UUID_GATT_SCC_VAL
GATT Server Characteristic Configuration UUID value.

BT_UUID_GATT_SCC
GATT Server Characteristic Configuration.

BT_UUID_GATTCPF_VAL
GATT Characteristic Presentation Format UUID value.

BT_UUID_GATTCPF
GATT Characteristic Presentation Format.

BT_UUID_GATT_CAF_VAL
GATT Characteristic Aggregated Format UUID value.

BT_UUID_GATT_CAF
GATT Characteristic Aggregated Format.

BT_UUID_VALID_RANGE_VAL
Valid Range Descriptor UUID value.

BT_UUID_VALID_RANGE
Valid Range Descriptor.

BT_UUID_HIDS_EXT_REPORT_VAL
HID External Report Descriptor UUID value.

BT_UUID_HIDS_EXT_REPORT
HID External Report Descriptor.
BG_UUID_HIDS_REPORT_REF_VAL
HID Report Reference Descriptor UUID value.

BG_UUID_HIDS_REPORT_REF
HID Report Reference Descriptor.

BG_UUID_ES_CONFIGURATION_VAL
Environmental Sensing Configuration Descriptor UUID value.

BG_UUID_ES_CONFIGURATION
Environmental Sensing Configuration Descriptor.

BG_UUID_ES_MEASUREMENT_VAL
Environmental Sensing Measurement Descriptor UUID value.

BG_UUID_ES_MEASUREMENT
Environmental Sensing Measurement Descriptor.

BG_UUID_ES_TRIGGER_SETTING_VAL
Environmental Sensing Trigger Setting Descriptor UUID value.

BG_UUID_ES_TRIGGER_SETTING
Environmental Sensing Trigger Setting Descriptor.

BG_UUID_GAP_DEVICE_NAME_VAL
GAP Characteristic Device Name UUID value.

BG_UUID_GAP_DEVICE_NAME
GAP Characteristic Device Name.

BG_UUID_GAP_APPEARANCE_VAL
GAP Characteristic Appearance UUID value.

BG_UUID_GAP_APPEARANCE
GAP Characteristic Appearance.

BG_UUID_GAP_PPCP_VAL
GAP Characteristic Peripheral Preferred Connection Parameters UUID value.

BG_UUID_GAP_PPCP
GAP Characteristic Peripheral Preferred Connection Parameters.

BG_UUID_GATT_SC_VAL
GATT Characteristic Service Changed UUID value.

BG_UUID_GATT_SC
GATT Characteristic Service Changed.
BT_UUID_ALERT_LEVEL_VAL
Alert Level UUID value.

BT_UUID_ALERT_LEVEL
Alert Level.

BT_UUID_TPS_TX_POWER_LEVEL_VAL
TPS Characteristic Tx Power Level UUID value.

BT_UUID_TPS_TX_POWER_LEVEL
TPS Characteristic Tx Power Level.

BT_UUID_BAS_BATTERY_LEVEL_VAL
BAS Characteristic Battery Level UUID value.

BT_UUID_BAS_BATTERY_LEVEL
BAS Characteristic Battery Level.

BT_UUID_HTS_MEASUREMENT_VAL
HTS Characteristic Measurement Value UUID value.

BT_UUID_HTS_MEASUREMENT
HTS Characteristic Measurement Value.

BT_UUID_HIDS_BOOT_KB_IN_REPORT_VAL
HID Characteristic Boot Keyboard Input Report UUID value.

BT_UUID_HIDS_BOOT_KB_IN_REPORT
HID Characteristic Boot Keyboard Input Report.

BT_UUID_DIS_SYSTEM_ID_VAL
DIS Characteristic System ID UUID value.

BT_UUID_DIS_SYSTEM_ID
DIS Characteristic System ID.

BT_UUID_DIS_MODEL_NUMBER_VAL
DIS Characteristic Model Number String UUID value.

BT_UUID_DIS_MODEL_NUMBER
DIS Characteristic Model Number String.

BT_UUID_DIS_SERIAL_NUMBER_VAL
DIS Characteristic Serial Number String UUID value.

BT_UUID_DIS_SERIAL_NUMBER
DIS Characteristic Serial Number String.
BT_UUID_DIS_FIRMWARE_REVISION_VAL
DIS Characteristic Firmware Revision String UUID value.

BT_UUID_DIS_FIRMWARE_REVISION
DIS Characteristic Firmware Revision String.

BT_UUID_DIS_HARDWARE_REVISION_VAL
DIS Characteristic Hardware Revision String UUID value.

BT_UUID_DIS_HARDWARE_REVISION
DIS Characteristic Hardware Revision String.

BT_UUID_DIS_SOFTWARE_REVISION_VAL
DIS Characteristic Software Revision String UUID value.

BT_UUID_DIS_SOFTWARE_REVISION
DIS Characteristic Software Revision String.

BT_UUID_DIS_MANUFACTURER_NAME_VAL
DIS Characteristic Manufacturer Name String UUID Value.

BT_UUID_DIS_MANUFACTURER_NAME
DIS Characteristic Manufacturer Name String.

BT_UUID_DIS_PNP_ID_VAL
DIS Characteristic PnP ID UUID value.

BT_UUID_DIS_PNP_ID
DIS Characteristic PnP ID.

BT_UUID_CTS_CURRENT_TIME_VAL
CTS Characteristic Current Time UUID value.

BT_UUID_CTS_CURRENT_TIME
CTS Characteristic Current Time.

BT_UUID_MAGN_DECLINATION_VAL
Magnetic Declination Characteristic UUID value.

BT_UUID_MAGN_DECLINATION
Magnetic Declination Characteristic.

BT_UUID_HIDS_BOOT_KB_OUT_REPORT_VAL
HID Boot Keyboard Output Report Characteristic UUID value.

BT_UUID_HIDS_BOOT_KB_OUT_REPORT
HID Boot Keyboard Output Report Characteristic.
BT_UUID_HIDS_BOOT_MOUSE_IN_REPORT_VAL
HID Boot Mouse Input Report Characteristic UUID value.

BT_UUID_HIDS_BOOT_MOUSE_IN_REPORT
HID Boot Mouse Input Report Characteristic.

BT_UUID_HRS_MEASUREMENT_VAL
HRS Characteristic Measurement Interval UUID value.

BT_UUID_HRS_MEASUREMENT
HRS Characteristic Measurement Interval.

BT_UUID_HRS_BODY_SENSOR_VAL
HRS Characteristic Body Sensor Location.

BT_UUID_HRS_BODY_SENSOR
HRS Characteristic Control Point.

BT_UUID_HRS_CONTROL_POINT_VAL
HRS Characteristic Control Point UUID value.

BT_UUID_HRS_CONTROL_POINT
HRS Characteristic Control Point.

BT_UUID_HIDS_INFO_VAL
HID Information Characteristic UUID value.

BT_UUID_HIDS_INFO
HID Information Characteristic.

BT_UUID_HIDS_REPORT_MAP_VAL
HID Report Map Characteristic UUID value.

BT_UUID_HIDS_REPORT_MAP
HID Report Map Characteristic.

BT_UUID_HIDS_CTRL_POINT_VAL
HID Control Point Characteristic UUID value.

BT_UUID_HIDS_CTRL_POINT
HID Control Point Characteristic.

BT_UUID_HIDS_REPORT_VAL
HID Report Characteristic UUID value.

BT_UUID_HIDS_REPORT
HID Report Characteristic.

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BT_UUID_HIDS_PROTOCOL_MODE_VAL
HID Protocol Mode Characteristic UUID value.

BT_UUID_HIDS_PROTOCOL_MODE
HID Protocol Mode Characteristic.

BT_UUID_RECORD_ACCESS_CONTROL_POINT_VAL
Record Access Control Point Characteristic value.

BT_UUID_RECORD_ACCESS_CONTROL_POINT
Record Access Control Point.

BT_UUID_RSC_MEASUREMENT_VAL
RSC Measurement Characteristic UUID value.

BT_UUID_RSC_MEASUREMENT
RSC Measurement Characteristic.

BT_UUID_RSC_FEATURE_VAL
RSC Feature Characteristic UUID value.

BT_UUID_RSC_FEATURE
RSC Feature Characteristic.

BT_UUID_CSC_MEASUREMENT_VAL
CSC Measurement Characteristic UUID value.

BT_UUID_CSC_MEASUREMENT
CSC Measurement Characteristic.

BT_UUID_CSC_FEATURE_VAL
CSC Feature Characteristic UUID value.

BT_UUID_CSC_FEATURE
CSC Feature Characteristic.

BT_UUID_SENSOR_LOCATION_VAL
Sensor Location Characteristic UUID value.

BT_UUID_SENSOR_LOCATION
Sensor Location Characteristic.

BT_UUID_SC_CONTROL_POINT_VAL
SC Control Point Characteristic UUID value.

BT_UUID_SC_CONTROL_POINT
SC Control Point Characteristic.
BT_UUID_ELEVATION_VAL
Elevation Characteristic UUID value.

BT_UUID_ELEVATION
Elevation Characteristic.

BT_UUID_PRESSURE_VAL
Pressure Characteristic UUID value.

BT_UUID_PRESSURE
Pressure Characteristic.

BT_UUID_TEMPERATURE_VAL
Temperature Characteristic UUID value.

BT_UUID_TEMPERATURE
Temperature Characteristic.

BT_UUID_HUMIDITY_VAL
Humidity Characteristic UUID value.

BT_UUID_HUMIDITY
Humidity Characteristic.

BT_UUID_TRUE_WIND_SPEED_VAL
True Wind Speed Characteristic UUID value.

BT_UUID_TRUE_WIND_SPEED
True Wind Speed Characteristic.

BT_UUID_TRUE_WIND_DIR_VAL
True Wind Direction Characteristic UUID value.

BT_UUID_TRUE_WIND_DIR
True Wind Direction Characteristic.

BT_UUID_APPARENT_WIND_SPEED_VAL
Apparent Wind Speed Characteristic UUID value.

BT_UUID_APPARENT_WIND_SPEED
Apparent Wind Speed Characteristic.

BT_UUID_APPARENT_WIND_DIR_VAL
Apparent Wind Direction Characteristic UUID value.

BT_UUID_APPARENT_WIND_DIR
Apparent Wind Direction Characteristic.
BT_UUID_GUST_FACTOR_VAL
Gust Factor Characteristic UUID value.

BT_UUID_GUST_FACTOR
Gust Factor Characteristic.

BT_UUID_POLLEN_CONCENTRATION_VAL
Pollen Concentration Characteristic UUID value.

BT_UUID_POLLEN_CONCENTRATION
Pollen Concentration Characteristic.

BT_UUID_UV_INDEX_VAL
UV Index Characteristic UUID value.

BT_UUID_UV_INDEX
UV Index Characteristic.

BT_UUID_IRRADIANCE_VAL
Irradiance Characteristic UUID value.

BT_UUID_IRRADIANCE
Irradiance Characteristic.

BT_UUID_RAINFALL_VAL
Rainfall Characteristic UUID value.

BT_UUID_RAINFALL
Rainfall Characteristic.

BT_UUID_WIND_CHILL_VAL
Wind Chill Characteristic UUID value.

BT_UUID_WIND_CHILL
Wind Chill Characteristic.

BT_UUID_HEAT_INDEX_VAL
Heat Index Characteristic UUID value.

BT_UUID_HEAT_INDEX
Heat Index Characteristic.

BT_UUID_DEW_POINT_VAL
Dew Point Characteristic UUID value.

BT_UUID_DEW_POINT
Dew Point Characteristic.
BT_UUID_DESC_VALUE_CHANGED_VAL
Descriptor Value Changed Characteristic UUID value.

BT_UUID_DESC_VALUE_CHANGED
Descriptor Value Changed Characteristic.

BT_UUID_MAGN_FLUX_DENSITY_2D_VAL
Magnetic Flux Density - 2D Characteristic UUID value.

BT_UUID_MAGN_FLUX_DENSITY_2D
Magnetic Flux Density - 2D Characteristic.

BT_UUID_MAGN_FLUX_DENSITY_3D_VAL
Magnetic Flux Density - 3D Characteristic UUID value.

BT_UUID_MAGN_FLUX_DENSITY_3D
Magnetic Flux Density - 3D Characteristic.

BT_UUID_BAR_PRESSURE_TREND_VAL
Barometric Pressure Trend Characteristic UUID value.

BT_UUID_BAR_PRESSURE_TREND
Barometric Pressure Trend Characteristic.

BT_UUID_BMS_CONTROL_POINT_VAL
Bond Management Control Point UUID value.

BT_UUID_BMS_CONTROL_POINT
Bond Management Control Point.

BT_UUID_BMS_FEATURE_VAL
Bond Management Feature UUID value.

BT_UUID_BMS_FEATURE
Bond Management Feature.

BT_UUID_CENTRAL_ADDR_RES_VAL
Central Address Resolution Characteristic UUID value.

BT_UUID_CENTRAL_ADDR_RES
Central Address Resolution Characteristic.

BT_UUID_CGM_MEASUREMENT_VAL
CGM Measurement Characteristic value.

BT_UUID_CGM_MEASUREMENT
CGM Measurement Characteristic.

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BT_UUID_CGM_FEATURE_VAL
CGM Feature Characteristic value.

BT_UUID_CGM_FEATURE
CGM Feature Characteristic.

BT_UUID_CGM_STATUS_VAL
CGM Status Characteristic value.

BT_UUID_CGM_STATUS
CGM Status Characteristic.

BT_UUID_CGM_SESSION_START_TIME_VAL
CGM Session Start Time Characteristic value.

BT_UUID_CGM_SESSION_START_TIME
CGM Session Start Time.

BT_UUID_CGM_SESSION_RUN_TIME_VAL
CGM Session Run Time Characteristic value.

BT_UUID_CGM_SESSION_RUN_TIME
CGM Session Run Time.

BT_UUID_CGM_SPECIFIC_OPS_CONTROL_POINT_VAL
CGM Specific Ops Control Point Characteristic value.

BT_UUID_CGM_SPECIFIC_OPS_CONTROL_POINT
CGM Specific Ops Control Point.

BT_UUID_URI_VAL
URI UUID value.

BT_UUID_URI
URI.

BT_UUID_HTTP_HEADERS_VAL
HTTP Headers UUID value.

BT_UUID_HTTP_HEADERS
HTTP Headers.

BT_UUID_HTTP_STATUS_CODE_VAL
HTTP Status Code UUID value.

BT_UUID_HTTP_STATUS_CODE
HTTP Status Code.
BT_UUID_HTTP_ENTITY_BODY_VAL
HTTP Entity Body UUID value.

BT_UUID_HTTP_ENTITY_BODY
HTTP Entity Body.

BT_UUID_HTTP_CONTROL_POINT_VAL
HTTP Control Point UUID value.

BT_UUID_HTTP_CONTROL_POINT
HTTP Control Point.

BT_UUID_HTTPS_SECURITY_VAL
HTTPS Security UUID value.

BT_UUID_HTTPS_SECURITY
HTTPS Security.

BT_UUID_OTS_FEATURE_VAL
OTS Feature Characteristic UUID value.

BT_UUID_OTS_FEATURE
OTS Feature Characteristic.

BT_UUID_OTS_NAME_VAL
OTS Object Name Characteristic UUID value.

BT_UUID_OTS_NAME
OTS Object Name Characteristic.

BT_UUID_OTS_TYPE_VAL
OTS Object Type Characteristic UUID value.

BT_UUID_OTS_TYPE
OTS Object Type Characteristic.

BT_UUID_OTS_SIZE_VAL
OTS Object Size Characteristic UUID value.

BT_UUID_OTS_SIZE
OTS Object Size Characteristic.

BT_UUID_OTS_FIRST_CREATED_VAL
OTS Object First-Created Characteristic UUID value.

BT_UUID_OTS_FIRST_CREATED
OTS Object First-Created Characteristic.

6.1. Bluetooth
**BT_UUID_OTS_LAST_MODIFIED_VAL**
OTS Object Last-Modified Characteristic UUID value.

**BT_UUID_OTS_LAST_MODIFIED**
OTS Object Last-Modified Characteristic.

**BT_UUID_OTS_ID_VAL**
OTS Object ID Characteristic UUID value.

**BT_UUID_OTS_ID**
OTS Object ID Characteristic.

**BT_UUID_OTS_PROPERTIES_VAL**
OTS Object Properties Characteristic UUID value.

**BT_UUID_OTS_PROPERTIES**
OTS Object Properties Characteristic.

**BT_UUID_OTS_ACTION_CP_VAL**
OTS Object Action Control Point Characteristic UUID value.

**BT_UUID_OTS_ACTION_CP**
OTS Object Action Control Point Characteristic.

**BT_UUID_OTS_LIST_CP_VAL**
OTS Object List Control Point Characteristic UUID value.

**BT_UUID_OTS_LIST_CP**
OTS Object List Control Point Characteristic.

**BT_UUID_OTS_LIST_FILTER_VAL**
OTS Object List Filter Characteristic UUID value.

**BT_UUID_OTS_LIST_FILTER**
OTS Object List Filter Characteristic.

**BT_UUID_OTS_CHANGED_VAL**
OTS Object Changed Characteristic UUID value.

**BT_UUID_OTS_CHANGED**
OTS Object Changed Characteristic.

**BT_UUID_OTS_TYPE_UNSPECIFIED_VAL**
OTS Unspecified Object Type UUID value.

**BT_UUID_OTS_TYPE_UNSPECIFIED**
OTS Unspecified Object Type.
BT_UUID_OTS_DIRECTORY_LISTING_VAL
OTS Directory Listing UUID value.

BT_UUID_OTS_DIRECTORY_LISTING
OTS Directory Listing.

BT_UUID_MESH_PROV_DATA_IN_VAL
Mesh Provisioning Data In UUID value.

BT_UUID_MESH_PROV_DATA_IN
Mesh Provisioning Data In.

BT_UUID_MESH_PROV_DATA_OUT_VAL
Mesh Provisioning Data Out UUID value.

BT_UUID_MESH_PROV_DATA_OUT
Mesh Provisioning Data Out.

BT_UUID_MESH_PROXY_DATA_IN_VAL
Mesh Proxy Data In UUID value.

BT_UUID_MESH_PROXY_DATA_IN
Mesh Proxy Data In.

BT_UUID_MESH_PROXY_DATA_OUT_VAL
Mesh Proxy Data Out UUID value.

BT_UUID_MESH_PROXY_DATA_OUT
Mesh Proxy Data Out.

BT_UUID_GATT_CLIENT_FEATURES_VAL
Client Supported Features UUID value.

BT_UUID_GATT_CLIENT_FEATURES
Client Supported Features.

BT_UUID_GATT_DB_HASH_VAL
Database Hash UUID value.

BT_UUID_GATT_DB_HASH
Database Hash.

BT_UUID_GATT_SERVER_FEATURES_VAL
Server Supported Features UUID value.

BT_UUID_GATT_SERVER_FEATURES
Server Supported Features.
BT_UUID_AICS_STATE_VAL
Audio Input Control Service State value.

BT_UUID_AICS_STATE
Audio Input Control Service State.

BT_UUID_AICS_GAIN_SETTINGS_VAL
Audio Input Control Service Gain Settings Properties value.

BT_UUID_AICS_GAIN_SETTINGS
Audio Input Control Service Gain Settings Properties.

BT_UUID_AICS_INPUT_TYPE_VAL
Audio Input Control Service Input Type value.

BT_UUID_AICS_INPUT_TYPE
Audio Input Control Service Input Type.

BT_UUID_AICS_INPUT_STATUS_VAL
Audio Input Control Service Input Status value.

BT_UUID_AICS_INPUT_STATUS
Audio Input Control Service Input Status.

BT_UUID_AICS_CONTROL_VAL
Audio Input Control Service Control Point value.

BT_UUID_AICS_CONTROL
Audio Input Control Service Control Point.

BT_UUID_AICS_DESCRIPTION_VAL
Audio Input Control Service Input Description value.

BT_UUID_AICS_DESCRIPTION
Audio Input Control Service Input Description.

BT_UUID_VCS_STATE_VAL
Volume Control Setting value.

BT_UUID_VCS_STATE
Volume Control Setting.

BT_UUID_VCS_CONTROL_VAL
Volume Control Control point value.

BT_UUID_VCS_CONTROL
Volume Control Control point.
6.1. Bluetooth

BT_UUID_VCS_FLAGS_VAL
  Volume Control Flags value.

BT_UUID_VCS_FLAGS
  Volume Control Flags.

BT_UUID_VOCS_STATE_VAL
  Volume Offset State value.

BT_UUID_VOCS_STATE
  Volume Offset State.

BT_UUID_VOCS_LOCATION_VAL
  Audio Location value.

BT_UUID_VOCS_LOCATION
  Audio Location.

BT_UUID_VOCS_CONTROL_VAL
  Volume Offset Control Point value.

BT_UUID_VOCS_CONTROL
  Volume Offset Control Point.

BT_UUID_VOCS_DESCRIPTION_VAL
  Volume Offset Audio Output Description value.

BT_UUID_VOCS_DESCRIPTION
  Volume Offset Audio Output Description.

BT_UUID_CSIS_SET_SIRK_VAL
  Set Identity Resolving Key value.

BT_UUID_CSIS_SET_SIRK
  Set Identity Resolving Key.

BT_UUID_CSIS_SET_SIZE_VAL
  Set size value.

BT_UUID_CSIS_SET_SIZE
  Set size.

BT_UUID_CSIS_SET_LOCK_VAL
  Set lock value.

BT_UUID_CSIS_SET_LOCK
  Set lock.
BT_UUID_CSIS_RANK_VAL
   Rank value.

BT_UUID_CSIS_RANK
   Rank.

BT_UUID_MCS_PLAYER_NAME_VAL
   Media player name value.

BT_UUID_MCS_PLAYER_NAME
   Media player name.

BT_UUID_MCS_ICON_OBJ_ID_VAL
   Media Icon Object ID value.

BT_UUID_MCS_ICON_OBJ_ID
   Media Icon Object ID.

BT_UUID_MCS_ICON_URL_VAL
   Media Icon URL value.

BT_UUID_MCS_ICON_URL
   Media Icon URL.

BT_UUID_MCS_TRACK_CHANGED_VAL
   Track Changed value.

BT_UUID_MCS_TRACK_CHANGED
   Track Changed.

BT_UUID_MCS_TRACK_TITLE_VAL
   Track Title value.

BT_UUID_MCS_TRACK_TITLE
   Track Title.

BT_UUID_MCS_TRACK_DURATION_VAL
   Track Duration value.

BT_UUID_MCS_TRACK_DURATION
   Track Duration.

BT_UUID_MCS_TRACK_POSITION_VAL
   Track Position value.

BT_UUID_MCS_TRACK_POSITION
   Track Position.
BT_UUID_MCS_PLAYBACK_SPEED_VAL
Playback Speed value.

BT_UUID_MCS_PLAYBACK_SPEED
Playback Speed.

BT_UUID_MCS_SEEKING_SPEED_VAL
Seeking Speed value.

BT_UUID_MCS_SEEKING_SPEED
Seeking Speed.

BT_UUID_MCS_TRACK_SEGMENTS_OBJ_ID_VAL
Track Segments Object ID value.

BT_UUID_MCS_TRACK_SEGMENTS_OBJ_ID
Track Segments Object ID.

BT_UUID_MCS_CURRENT_TRACK_OBJ_ID_VAL
Current Track Object ID value.

BT_UUID_MCS_CURRENT_TRACK_OBJ_ID
Current Track Object ID.

BT_UUID_MCS_NEXT_TRACK_OBJ_ID_VAL
Next Track Object ID value.

BT_UUID_MCS_NEXT_TRACK_OBJ_ID
Next Track Object ID.

BT_UUID_MCS_PARENT_GROUP_OBJ_ID_VAL
Parent Group Object ID value.

BT_UUID_MCS_PARENT_GROUP_OBJ_ID
Parent Group Object ID.

BT_UUID_MCS_CURRENT_GROUP_OBJ_ID_VAL
Group Object ID value.

BT_UUID_MCS_CURRENT_GROUP_OBJ_ID
Group Object ID.

BT_UUID_MCS_PLAYING_ORDER_VAL
Playing Order value.

BT_UUID_MCS_PLAYING_ORDER
Playing Order.
BT_UUID_MCS_PLAYING_ORDERS_VAL
Playing Orders supported value.

BT_UUID_MCS_PLAYING_ORDERS
Playing Orders supported.

BT_UUID_MCS_MEDIA_STATE_VAL
Media State value.

BT_UUID_MCS_MEDIA_STATE
Media State.

BT_UUID_MCS_MEDIA_CONTROL_POINT_VAL
Media Control Point value.

BT_UUID_MCS_MEDIA_CONTROL_POINT
Media Control Point.

BT_UUID_MCS_MEDIA_CONTROL_OPCODES_VAL
Media control opcodes supported value.

BT_UUID_MCS_MEDIA_CONTROL_OPCODES
Media control opcodes supported.

BT_UUID_MCS_SEARCH_RESULTS_OBJ_ID_VAL
Search result object ID value.

BT_UUID_MCS_SEARCH_RESULTS_OBJ_ID
Search result object ID.

BT_UUID_MCS_SEARCH_CONTROL_POINT_VAL
Search control point value.

BT_UUID_MCS_SEARCH_CONTROL_POINT
Search control point.

BT_UUID_OTS_TYPE_MPL_ICON_VAL
Media Player Icon Object Type value.

BT_UUID_OTS_TYPE_MPL_ICON
Media Player Icon Object Type.

BT_UUID_OTS_TYPE_TRACK_SEGMENT_VAL
Track Segments Object Type value.

BT_UUID_OTS_TYPE_TRACK_SEGMENT
Track Segments Object Type.
BT_UUID_OTS_TYPE_TRACK_VAL
Track Object Type value.

BT_UUID_OTS_TYPE_TRACK
Track Object Type.

BT_UUID_OTS_TYPE_GROUP_VAL
Group Object Type value.

BT_UUID_OTS_TYPE_GROUP
Group Object Type.

BT_UUID_TBS_PROVIDER_NAME_VAL
Bearer Provider Name value.

BT_UUID_TBS_PROVIDER_NAME
Bearer Provider Name.

BT_UUID_TBS_UCI_VAL
Bearer UCI value.

BT_UUID_TBS_UCI
Bearer UCI.

BT_UUID_TBS_TECHNOLOGY_VAL
Bearer Technology value.

BT_UUID_TBS_TECHNOLOGY
Bearer Technology.

BT_UUID_TBS_URI_LIST_VAL
Bearer URI Prefixes Supported List value.

BT_UUID_TBS_URI_LIST
Bearer URI Prefixes Supported List.

BT_UUID_TBS_SIGNAL_STRENGTH_VAL
Bearer Signal Strength value.

BT_UUID_TBS_SIGNAL_STRENGTH
Bearer Signal Strength.

BT_UUID_TBS_SIGNAL_INTERVAL_VAL
Bearer Signal Strength Reporting Interval value.

BT_UUID_TBS_SIGNAL_INTERVAL
Bearer Signal Strength Reporting Interval.

6.1. Bluetooth
BT_UUID_TBS_LIST_CURRENT_CALLS_VAL
Bearer List Current Calls value.

BT_UUID_TBS_LIST_CURRENT_CALLS
Bearer List Current Calls.

BT_UUID_CCID_VAL
Content Control ID value.

BT_UUID_CCID
Content Control ID.

BT_UUID_TBS_STATUS_FLAGS_VAL
Status flags value.

BT_UUID_TBS_STATUS_FLAGS
Status flags.

BT_UUID_TBS_INCOMING_URI_VAL
Incoming Call Target Caller ID value.

BT_UUID_TBS_INCOMING_URI
Incoming Call Target Caller ID.

BT_UUID_TBS_CALL_STATE_VAL
Call State value.

BT_UUID_TBS_CALL_STATE
Call State.

BT_UUID_TBS_CALL_CONTROL_POINT_VAL
Call Control Point value.

BT_UUID_TBS_CALL_CONTROL_POINT
Call Control Point.

BT_UUID_TBS_OPTIONAL_OPCODES_VAL
Optional Opcodes value.

BT_UUID_TBS_OPTIONAL_OPCODES
Optional Opcodes.

BT_UUID_TBS_TERMINATE_REASON_VAL
Terminate reason value.

BT_UUID_TBS_TERMINATE_REASON
Terminate reason.
BT_UUID_TBS_INCOMING_CALL_VAL
Incoming Call value.

BT_UUID_TBS_INCOMING_CALL
Incoming Call.

BT_UUID_TBS_FRIENDLY_NAME_VAL
Incoming Call Friendly name value.

BT_UUID_TBS_FRIENDLY_NAME
Incoming Call Friendly name.

BT_UUID_MICS_MUTE_VAL
Microphone Input Control Service Mute value.

BT_UUID_MICS_MUTE
Microphone Input Control Service Mute.

BT_UUID_ASCS_ASE_SNK_VAL
Audio Stream Endpoint Sink Characteristic value.

BT_UUID_ASCS_ASE_SNK
Audio Stream Endpoint Sink Characteristic.

BT_UUID_ASCS_ASE_SRC_VAL
Audio Stream Endpoint Source Characteristic value.

BT_UUID_ASCS_ASE_SRC
Audio Stream Endpoint Source Characteristic.

BT_UUID_ASCS_ASE_CP_VAL
Audio Stream Endpoint Control Point Characteristic value.

BT_UUID_ASCS_ASE_CP
Audio Stream Endpoint Control Point Characteristic.

BT_UUID_BASS_CONTROL_POINT_VAL
Broadcast Audio Scan Service Scan State value.

BT_UUID_BASS_CONTROL_POINT
Broadcast Audio Scan Service Scan State.

BT_UUID_BASS_RECV_STATE_VAL
Broadcast Audio Scan Service Receive State value.

BT_UUID_BASS_RECV_STATE
Broadcast Audio Scan Service Receive State.
BT_UUID_PACS_SNK_VAL
  Sink PAC Characteristic value.

BT_UUID_PACS_SNK
  Sink PAC Characteristic.

BT_UUID_PACS_SNK_LOC_VAL
  Sink PAC Locations Characteristic value.

BT_UUID_PACS_SNK_LOC
  Sink PAC Locations Characteristic.

BT_UUID_PACS_SRC_VAL
  Source PAC Characteristic value.

BT_UUID_PACS_SRC
  Source PAC Characteristic.

BT_UUID_PACS_SRC_LOC_VAL
  Source PAC Locations Characteristic value.

BT_UUID_PACS_SRC_LOC
  Source PAC Locations Characteristic.

BT_UUID_PACS_AVAILABLE_CONTEXT_VAL
  Available Audio Contexts Characteristic value.

BT_UUID_PACS_AVAILABLE_CONTEXT
  Available Audio Contexts Characteristic.

BT_UUID_PACS_SUPPORTED_CONTEXT_VAL
  Supported Audio Context Characteristic value.

BT_UUID_PACS_SUPPORTED_CONTEXT
  Supported Audio Context Characteristic.

BT_UUID_HAS_HEARING_AID_FEATURES_VAL
  Hearing Aid Features Characteristic value.

BT_UUID_HAS_HEARING_AID_FEATURES
  Hearing Aid Features Characteristic.

BT_UUID_HAS_PRESET_CONTROL_POINT_VAL
  Hearing Aid Preset Control Point Characteristic value.

BT_UUID_HAS_PRESET_CONTROL_POINT
  Hearing Aid Preset Control Point Characteristic.
BT_UUID_HAS_ACTIVE_PRESET_INDEX_VAL
   Active Preset Index Characteristic value.

BT_UUID_HAS_ACTIVE_PRESET_INDEX
   Active Preset Index Characteristic.

BT_UUID_SDP_VAL

BT_UUID_SDP

BT_UUID_UDP_VAL

BT_UUID_UDP

BT_UUID_RFCOMM_VAL

BT_UUID_RFCOMM

BT_UUID_TCP_VAL

BT_UUID_TCP

BT_UUID_TCS_BIN_VAL

BT_UUID_TCS_BIN

BT_UUID_TCS_AT_VAL

BT_UUID_TCS_AT

BT_UUID_ATT_VAL

BT_UUID_ATT

BT_UUID_OBEX_VAL

BT_UUID_OBEX

BT_UUID_IP_VAL

BT_UUID_IP

BT_UUID_FTP_VAL

BT_UUID_FTP
BT_UUID_HTTP_VAL

BT_UUID_HTTP

BT_UUID_BNEP_VAL

BT_UUID_BNEP

BT_UUID_UPNP_VAL

BT_UUID_UPNP

BT_UUID_HIDP_VAL

BT_UUID_HIDP

BT_UUID_HCRP_CTRL_VAL

BT_UUID_HCRP_CTRL

BT_UUID_HCRP_DATA_VAL

BT_UUID_HCRP_DATA

BT_UUID_HCRP_NOTE_VAL

BT_UUID_HCRP_NOTE

BT_UUID_AVCTP_VAL

BT_UUID_AVCTP

BT_UUID_AVDTP_VAL

BT_UUID_AVDTP

BT_UUID_CMTP_VAL

BT_UUID_CMTP

BT_UUID_UDI_VAL

BT_UUID_UDI

BT_UUID_MCAP_CTRL_VAL
Enums

enum [anonymous]
    Bluetooth UUID types.
    Values:

    enumerator BT_UUID_TYPE_16
        UUID type 16-bit.

    enumerator BT_UUID_TYPE_32
        UUID type 32-bit.

    enumerator BT_UUID_TYPE_128
        UUID type 128-bit.

Functions

int bt_uuid_cmp(const struct bt_uuid *u1, const struct bt_uuid *u2)
    Compare Bluetooth UUIDs.
    Compares 2 Bluetooth UUIDs, if the types are different both UUIDs are first converted to 128
    bits format before comparing.

    Parameters
     • u1 – First Bluetooth UUID to compare
     • u2 – Second Bluetooth UUID to compare

    Returns
        negative value if u1 < u2, 0 if u1 == u2, else positive

bool bt_uuid_create(struct bt_uuid *uuid, const uint8_t *data, uint8_t data_len)
    Create a bt_uuid from a little-endian data buffer.
    Create a bt_uuid from a little-endian data buffer. The data_len parameter is used to determine
    whether the UUID is in 16, 32 or 128 bit format (length 2, 4 or 16). Note: 32 bit format is
    not allowed over the air.

    Parameters
     • uuid – Pointer to the bt_uuid variable
     • data – pointer to UUID stored in little-endian data buffer
• data_len – length of the UUID in the data buffer

Returns
true if the data was valid and the UUID was successfully created.

void bt_uuid_to_str(const struct bt_uuid *uuid, char *str, size_t len)
Convert Bluetooth UUID to string.
Converts Bluetooth UUID to string. UUID can be in any format, 16-bit, 32-bit or 128-bit.

Parameters
• uuid – Bluetooth UUID
• str – pointer where to put converted string
• len – length of str

struct bt_uuid
#include <uuid.h> This is a ‘tentative’ type and should be used as a pointer only.

struct bt_uuid_16
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint16_t val
UUID value, 16-bit in host endianness.

struct bt_uuid_32
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint32_t val
UUID value, 32-bit in host endianness.

struct bt_uuid_128
#include <uuid.h>

Public Members

struct bt_uuid uuid
UUID generic type.

uint8_t val[16]
UUID value, 128-bit in little-endian format.
Bluetooth: Basic Audio Profile

This document describes how to run basic audio profile functionality which includes:

- Capabilities and Endpoint discovery
- Audio Stream Endpoint procedures

Commands

```
audio --help
```

Subcommands:

- `init`
- `select_broadcast <stream>`
- `create_broadcast [codec] [preset]`
- `start_stream`
- `stop_stream`
- `delete_broadcast`
- `broadcast_scan <on, off>`
- `accept_broadcast 0x<broadcast_id>`
- `sync_broadcast 0x<bis_bitfield>`
- `stop_broadcast_sink` : Stops broadcast sink
- `term_broadcast_sink`
- `discover [type: sink, source]`
- `preset [preset]`
- `config <direction: sink, source> <index> [codec] [preset]`
- `qos [preset] [interval] [framing] [latency] [pd] [sdru] [phy] [rtn]`
- `enable`
- `metadata [context]`
- `start`
- `disable`
- `stop`
- `release`
- `list`
- `connect <direction: sink, source> <index> [codec] [preset]`
- `select_unicast <stream>`
- `send` : Send to Audio Stream [data]

<table>
<thead>
<tr>
<th>Command</th>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>init</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>discover</td>
<td>init</td>
<td>any</td>
<td>any</td>
</tr>
<tr>
<td>config</td>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
<tr>
<td>qos</td>
<td>config</td>
<td>codec-configured/qos-configured</td>
<td>qos-configured</td>
</tr>
<tr>
<td>enable</td>
<td>qos</td>
<td>qos-configured</td>
<td>enabling</td>
</tr>
<tr>
<td>start</td>
<td>enable</td>
<td>enabling</td>
<td>streaming</td>
</tr>
<tr>
<td>disable</td>
<td>enable</td>
<td>enabling/streaming</td>
<td>disabling</td>
</tr>
<tr>
<td>stop</td>
<td>disable</td>
<td>disabling</td>
<td>qos-config/codec-configured/idle</td>
</tr>
<tr>
<td>release</td>
<td>config</td>
<td>any</td>
<td>releasing/codec-config/iolde</td>
</tr>
<tr>
<td>list</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>select_unicast</td>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
<tr>
<td>connect</td>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
<tr>
<td>send</td>
<td>enable</td>
<td>streaming</td>
<td>codec-configured</td>
</tr>
</tbody>
</table>

**Example Central**  
Connect and establish a stream:
uart:~$ bt init
uart:~$ audio init
uart:~$ bt connect <address>
uart:~$ gatt exchange-mtu
uart:~$ audio discover sink
uart:~$ audio config sink 0
uart:~$ audio qos
uart:~$ audio enable

Or using connect command:

uart:~$ bt init
uart:~$ audio init
uart:~$ bt connect <address>
uart:~$ gatt exchange-mtu
uart:~$ audio discover sink
uart:~$ audio connect sink 0

Disconnect and release:

uart:~$ audio disable
uart:~$ audio release

Example Peripheral  Listen:

uart:~$ bt init
uart:~$ audio init
uart:~$ bt advertise on

Server initiated disable and release:

uart:~$ audio disable
uart:~$ audio release

Example Broadcast Source  Create and establish a broadcast source stream:

uart:~$ audio init
uart:~$ audio create_broadcast
uart:~$ audio start_broadcast

Stop and release a broadcast source stream:

uart:~$ audio stop_broadcast
uart:~$ audio delete_broadcast

Example Broadcast Sink  Scan for and establish a broadcast sink stream:

uart:~$ audio init
uart:~$ audio broadcast_scan on
Found broadcaster with ID 0xB91CD4
uart:~$ audio accept_broadcast 0xB91CD4
PA syncing to broadcaster
Broadcast scan was terminated: 0
PA synced to broadcaster with ID 0xB91CD4 as sink 0x2000d09c
Sink 0x2000d09c is set as default

(continues on next page)
Sink 0x2000d09c is ready to sync without encryption
Received BASE from sink 0x2000d09c:
Subgroup[0]:
codec 0x06 cid 0x0000 vid 0x0000 count 4
data #0: type 0x01 len 1
data #1: type 0x02 len 1
data #2: type 0x03 len 4
00000000: 00 00 00 [... ]
data #3: type 0x04 len 2
00000000: 28 [( ]
meta #0: type 0x02 len 2
BIS[0] index 0x01
[0]: 0x01
Possible indexes: 0x01
audio sync_broadcast 0x01

Stop and release a broadcast sink stream:

uart:~$ audio stop_broadcast_sink
uart:~$ audio term_broadcast_sink

**Init**  The `init` command register local PAC records which are necessary to be able to configure stream and properly manage capabilities in use.

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

uart:~$ audio init

**Discover PAC(s) and ASE(s)**  Once connected the `discover` command discover PAC records and ASE characteristics representing remote endpoints.

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>init</td>
<td>any</td>
<td>any</td>
</tr>
</tbody>
</table>

**Note:** Use command `gatt exchange-mtu` to make sure the MTU is configured properly.

uart:~$ gatt exchange-mtu
Exchange pending
Exchange successful
uart:~$ audio discover [type: sink, source]
uart:~$ audio discover sink
cap 0x8175940 type 0x01
codec 0x06 cid 0x0000 vid 0x0000 count 4
data #0: type 0x01 len 1
00000000: 3f [? ]
data #1: type 0x02 len 1
00000000: 03 [.] (continues on next page)
Select preset  The preset command can be used to either print the default preset configuration or set a different one, it is worth noting that it doesn't change any stream previously configured.

```bash
uart:~$ audio preset [preset]
uart:~$ audio preset
16_2_1
```

codec 0x06 cid 0x0000 vid 0x0000 count 3
data #0: type 0x01 len 1 00000000: 02 | . | . |
data #1: type 0x02 len 1 00000000: 01 | . | . |
data #2: type 0x04 len 2 00000000: 00 00 | . | . |
meta #0: type 0x01 len 2 00000000: 06 00 | . | . |
meta #1: type 0x02 len 2 00000000: ff 03 | . | . |
ep 0x81754e0
ep 0x81755d4
Discover complete: err 0

QoS: dir 0x02 interval 10000 framing 0x00 phy 0x02 sdu 40 rtn 2 latency 10 pd 40000

Configure Codec  The config command attempts to configure a stream for the given direction using a preset codec configuration which can either be passed directly or in case it is omitted the default preset is used.

```bash
uart:~$ audio config <direction: sink, source> <index> [codec] [preset]
uart:~$ audio config sink 0
ASE Codec Config: conn 0x8173800 ep 0x81754e0 cap 0x816a360
codec 0x06 cid 0x0000 vid 0x0000 count 3
data #0: type 0x01 len 1 00000000: 02 | . | . |
data #1: type 0x02 len 1 00000000: 01 | . | . |
data #2: type 0x04 len 2 00000000: 00 00 | . | . |
meta #0: type 0x01 len 2 00000000: 06 00 | . | . |
meta #1: type 0x02 len 2 00000000: ff 03 | . | . |
ASE Codec Config stream 0x8179e60
Default ase: 1
ASE config: preset 16_2_1
```

Table 6.9: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>codec-configured</td>
</tr>
</tbody>
</table>

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Configure QoS  The `qos` command attempts to configure the stream QoS using the preset configuration, each individual QoS parameter can be set with use optional parameters.

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>config</td>
<td>qos-configured/codec-configured</td>
<td>qos-configured</td>
</tr>
</tbody>
</table>

```
uart:~$ audio qos [preset] [interval] [framing] [latency] [pd] [sdu] [phy] [rtn]
uart:~$ audio qos
ASE config: preset 16_2_1
```

Enable  The `enable` command attempts to enable the stream previously configured, if the remote peer accepts then the ISO connection procedure is also initiated.

```
uart:~$ audio enable
```

Start [sink only]  The `start` command is only necessary when acting as a sink as it indicates to the source the stack is ready to start receiving data.

```
uart:~$ audio start
```

Disable  The `disable` command attempts to disable the stream previously enabled, if the remote peer accepts then the ISO disconnection procedure is also initiated.

```
uart:~$ audio disable
```

Stop [sink only]  The `stop` command is only necessary when acting as a sink as it indicates to the source the stack is ready to stop receiving data.

```
uart:~$ audio stop
```
**Release**  The release command releases the current stream and its configuration.

Table 6.15: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>config</td>
<td>any</td>
<td>releasing/codec-configure/idle</td>
</tr>
</tbody>
</table>

```
uart:~$ audio release
```

**List**  The list command list the available streams.

Table 6.16: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

```
uart:~$ audio list
*0: ase 0x01 dir 0x01 state 0x01
```

**Select Unicast**  The select_unicast command set a unicast stream as default.

Table 6.17: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>none</td>
<td>any</td>
<td>none</td>
</tr>
</tbody>
</table>

```
uart:~$ audio select <ase>
uart:~$ audio select 0x01
Default stream: 1
```

To select a broadcast stream:

```
uart:~$ audio select 0x01 broadcast
Default stream: 1 (broadcast)
```

**Connect**  The connect command combines config, qos and enable commands in one so it can be used to quickly configure and enable a stream.

Table 6.18: State Machine Transitions

<table>
<thead>
<tr>
<th>Depends</th>
<th>Allowed States</th>
<th>Next States</th>
</tr>
</thead>
<tbody>
<tr>
<td>discover</td>
<td>idle/codec-configured/qos-configured</td>
<td>streaming</td>
</tr>
</tbody>
</table>

```
uart:~$ audio connect <direction: sink, source> <index> [codec] [preset]
uart:~$ audio connect sink 0
ASE Codec Config: conn 0x17ca40 ep 0x17f860 cap 0x19f6a0
codec 0x06 cid 0x0000 vid 0x0000 count 3
data #0: type 0x01 len 1
000000000: 02 |. | |
data #1: type 0x02 len 1
000000000: 01 |. | |
data #2: type 0x04 len 2
000000000: 28 00 |(. | |
meta #0: type 0x02 len 2
(continues on next page)
Sending The send command sends data over Audio Stream.

```
uart:~$ audio send [count]
uart:~$ audio send
Audio sending...
```

Bluetooth: Broadcast Audio Profile Broadcast Assistant

This document describes how to run the BAP Broadcast Assistant functionality. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

The Broadcast Assistant is responsible for offloading scan for a resource restricted device, such that scanning does not drain the battery. The Broadcast Assistant shall support scanning for periodic advertisements and may optionally support the periodic advertisements synchronization transfer (PAST) protocol.

The Broadcast Assistant will typically be phones or laptops. The Broadcast Assistant scans for periodic advertisements and transfers information to the server.

It is necessary to have BT_DEBUG_BAP_BROADCAST_ASSISTANT enabled for using the Broadcast Assistant interactively.

When the Bluetooth stack has been initialized (bt init), and a device has been connected, the Broadcast Assistant can discover BASS on the connected device calling bap_broadcast_assistant discover, which will start a discovery for the BASS UUIDs and store the handles, and subscribe to all notifications.
**Example usage**

### Setup

```bash
uart:~$ bt init
```

### When connected

Start scanning for periodic advertisements for a server:

**Note:** The Broadcast Assistant will not actually start scanning for periodic advertisements, as that feature is still, at the time of writing, not implemented.

```bash
uart:~$ bap_broadcast_assistant discover
<dbg> bt_bap_broadcast_assistant.char_discover_func: Found 1 BASS receive states
<dbg> bt_bap_broadcast_assistant.read_recv_state_cb: src_id 0, PA 0, BIS 0, encrypt 0,
    ... addr 00:00:00:00:00:00 (public), sid 0, metadata_len 0
uart:~$ bap_broadcast_assistant scan_start
<dbg> bt_bap_broadcast_assistant.write_func: err: 0x00, handle 0x001e
```

Adding a source to the receive state:

```bash
uart:~$ bap_broadcast_assistant add_src 11:22:33:44:55:66 public 5 1 1
BASS recv state: src_id 0, addr 11:22:33:44:55:66 (public), sid 5, sync_state 1,
    ... encrypt_state 00000000000000000000000000000000
    [0]: BIS sync 0, metadata_len 0
```
init : Initialize the service and register callbacks
synced : Set server scan state <src_id> <pa_synced> <bis_syncs> <enc_state>

Example Usage

Setup

uart:~$ bt init
uart:~$ bt advertise on
Advertising started

When connected Set sync state for a source:

uart:~$ bap_scan_delegator synced 0 1 3 0

Bluetooth: Call Control Profile

This document describes how to run the call control functionality, both as a client and as a (telephone bearer service (TBS)) server. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

Telephone Bearer Service Client The telephone bearer service client will typically exist on a resource restricted device, such as headphones, but may also exist on e.g. phones or laptops. The call control client will also thus typically be the advertiser. The client can control the states of calls on a server using the call control point.

It is necessary to have BT_DEBUG_TBS_CLIENT enabled for using the client interactively.

Using the telephone bearer service client When the Bluetooth stack has been initialized (bt init), and a device has been connected, the telephone bearer service client can discover TBS on the connected device calling tbs_client discover, which will start a discovery for the TBS UUIDs and store the handles, and optionally subscribe to all notifications (default is to subscribe to all).

Since a server may have multiple TBS instances, most of the tbs_client commands will take an index (starting from 0) as input. Joining calls require at least 2 call IDs, and all call indexes shall be on the same TBS instance.

A server may also have a GTBS instance, which is an abstraction layer for all the telephone bearers on the server. If the server has both GTBS and TBS, the client may subscribe and use either when sending requests if BT_TBS_CLIENT_GTBS is enabled.

tbs_client --help
tbs_client - Bluetooth TBS_CLIENT shell commands
Subcommands:
discover : Discover TBS [subscribe]
set_signal_reporting_interval : Set the signal reporting interval
(originating_instance_index, gtbs) interval
originate : Originate a call (originating_instance_index, gtbs) uri
terminate : Terminate a call (terminating_instance_index, gtbs) id
accept : Accept a call (accepting_instance_index, gtbs) id
In the following examples, notifications from GTBS is ignored, unless otherwise specified.

**Example usage**

**Setup**

```sh
tart:~$ bt init
tart:~$ bt advertise on
Advertising started
```

**When connected**  Placing a call:

```sh
tart:~$ tbs_client discover
<dbg> bt_tbs_client.primary_discover_func: Discover complete, found 1 instances (GTBS → found)
<dbg> bt_tbs_client.discover_func: Setup complete for 1 / 1 TBS
<dbg> bt_tbs_client.discover_func: Setup complete GTBS
tart:~$ tbs_client originate 0 tel:123
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the dialing state with URI tel:123
<dbg> bt_tbs_client.call_cp_notify_handler: Status: success for the originate opcode for call 0x00
<dbg> bt_tbs_client.notify_handler: Index 0
```

(continues on next page)
Placing a call on GTBS:

```
uart:~$ tbs_client originate 0 tel:123
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the dialing state→ with URI tel:123
<dbg> bt_tbs_client.call_cp_notify_handler: Status: success for the originate opcode→ for call 0x00
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the alerting state→ with URI tel:123
<call answered by peer device, and status notified by TBS server>
<dbg> bt_tbs_client.notify_handler: Index 0
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x01 is in the active state→ with URI tel:123
```

It is necessary to set an outgoing caller ID before placing a call.

Accepting incoming call from peer device:

```
<dbg> bt_tbs_client.incoming_uri_notify_handler: tel:123
<dbg> bt_tbs_client.in_call_notify_handler: tel:456
<dbg> bt_tbs_client.friendly_name_notify_handler: Peter
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x05 is in the incoming state→ with URI tel:456
uart:~$ tbs_client accept 0 5
<dbg> bt_tbs_client.call_cp_callback_handler: Status: success for the accept opcode→ for call 0x05
<dbg> bt_tbs_client.current_calls_notify_handler: Call 0x05 is in the active state→ with URI tel
```

Terminate call:

```
uart:~$ tbs_client terminate 0 5
<dbg> bt_tbs_client.termination_reason_notify_handler: ID 0x05, reason 0x06
<dbg> bt_tbs_client.call_cp_notify_handler: Status: success for the terminate opcode→ for call 0x05
<dbg> bt_tbs_client.current_calls_notify_handler:
```

**Telephone Bearer Service (TBS)** The telephone bearer service is a service that typically resides on devices that can make calls, including calls from apps such as Skype, e.g. (smart)phones and PCs.

It is necessary to have `BT_DEBUG_TBS` enabled for using the TBS server interactively.

**Using the telephone bearer service** TBS can be controlled locally, or by a remote device (when in a call). For example a remote device may initiate a call to the device with the TBS server, or the TBS server may initiate a call to remote device, without a `TBS_CLIENT` client. The TBS implementation is capable of fully controlling any call.

6.1. Bluetooth
tbs --help

**tbs** - Bluetooth TBS shell commands

**Subcommands:**
- **init**: Initialize TBS
- **authorize**: Authorize the current connection
- **accept**: Accept call `<call_index>`
- **terminate**: Terminate call `<call_index>`
- **hold**: Hold call `<call_index>`
- **retrieve**: Retrieve call `<call_index>`
- **originate**: Originate call `[<instance_index>, gtbs>] `<uri>`
- **join**: Join calls `<id> [<id>] [<id>] [...]`
- **incoming**: Simulate incoming remote call `[<instance_index, gtbs>] `<local_uri>` `<remote_uri>`
  `<remote_friendly_name>`
- **remote_answer**: Simulate remote answer outgoing call `<call_index>`
- **remote_retrieve**: Simulate remote retrieve `<call_index>`
- **remote_terminate**: Simulate remote terminate `<call_index>`
- **remote_hold**: Simulate remote hold `<call_index>`
- **set_bearer_provider_name**: Set the bearer provider name `[<instance_index, gtbs>]` `<name>`
- **set_bearer_technology**: Set the bearer technology `[<instance_index, gtbs>]` `<technology>`
- **set_bearer_signal_strength**: Set the bearer signal strength `[<instance_index, gtbs>]` `<strength>`
- **set_status_flags**: Set the bearer feature and status value `[<instance_index, gtbs>]` `<feature_and_status>`
- **set_uri_scheme**: Set the URI prefix list `<bearer_idx>` `<uri1 [uri2 [uri3 [...]]]>`
- **print_calls**: Output all calls in the debug log

**Example Usage**

**Setup**

```
uart:~$ bt init
```

**When connected**  Answering a call for a peer device originated by a client:

```
<dbg> bt_tbs.write_call_cp: Index 0: Processing the originate opcode
<dbg> bt_tbs.originate_call: New call with call index 1
<dbg> bt_tbs.write_call_cp: Index 0: Processed the originate opcode with status → success for call index 1
uart:~$ tbs remote_answer 1
TBS succeeded for call_id: 1
```

Incoming call from a peer device, accepted by client:

```
uart:~$ tbs incoming 0 tel:123 tel:456 Peter
TBS succeeded for call_id: 4
<dbg> bt_tbs.bt_tbs_remote_incoming: New call with call index 4
<dbg> bt_tbs.write_call_cp: Index 0: Processed the accept opcode with status success → for call index 4
```
Bluetooth: Coordinated Set Identification Profile

This document describes how to run the coordinated set identification functionality, both as a client and as a server. Note that in the examples below, some lines of debug have been removed to make this shorter and provide a better overview.

Set Coordinator (Client) The client will typically be a resource-rich device, such as a smartphone or a laptop. The client is able to lock and release members of a coordinated set. While the coordinated set is locked, no other clients may lock the set.

To lock a set, the client must connect to each of the set members it wants to lock. This implementation will always try to connect to all the members of the set, and at the same time. Thus if the set size is 3, then BT_MAX_CONN shall be at least 3.

If the locks on set members shall persists through disconnects, it is necessary to bond with the set members. If you need to bond with multiple set members, make sure that BT_MAX_PAIRED is correctly configured.

Using the Set Coordinator When the Bluetooth stack has been initialized (bt init), and a set member device has been connected, the call control client can be initialized by calling csip_set_coordinator init, which will start a discovery for the TBS uuids and store the handles, and optionally subscribe to all notifications (default is to subscribe to all).

Once the client has connected and discovered the handles, then it can read the set information, which is needed to identify other set members. The client can then scan for and connect to the remaining set members, and once all the members has been connected to, it can lock and release the set.

It is necessary to enable BT_DEBUG_CSIP_SET_COORDINATOR to properly use the set coordinator.

<table>
<thead>
<tr>
<th>Subcommands:</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>init</td>
<td>Initialize CSIP_SET_COORDINATOR</td>
</tr>
<tr>
<td>discover</td>
<td>Run discover for CSIS on peer device [member_index]</td>
</tr>
<tr>
<td>discover_members</td>
<td>Scan for set members [set_pointer]</td>
</tr>
<tr>
<td>lock_set</td>
<td>Lock set</td>
</tr>
<tr>
<td>release_set</td>
<td>Release set</td>
</tr>
<tr>
<td>lock</td>
<td>Lock specific member [member_index]</td>
</tr>
<tr>
<td>release</td>
<td>Release specific member [member_index]</td>
</tr>
<tr>
<td>lock_get</td>
<td>Get the lock value of the specific member and instance [member_index [inst_idx]]</td>
</tr>
</tbody>
</table>

Example usage

Setup

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>uart:$ init</td>
<td>Initialize CSIP_SET_COORDINATOR</td>
</tr>
<tr>
<td>uart:$ bt connect xx:xx:xx:xx:xx:xx public</td>
<td>Connect to a set member</td>
</tr>
</tbody>
</table>

When connected Discovering sets on a device:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>uart:$ csip_set_coordinator init</td>
<td>Start discovery for CSIS on device</td>
</tr>
<tr>
<td>(dbg) bt_csip_set_coordinator.primary_discover_func: [ATTRIBUTE] handle 0x0048</td>
<td>Discover complete, found 1 instances</td>
</tr>
</tbody>
</table>
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(continued from previous page)

<dbg> bt_csip_set_coordinator.discover_func: Setup complete for 1 / 1
Found 1 sets on device
uart:~$ csip_set_coordinator discover_sets
<dbg> bt_csip_set_coordinator.Set SIRK
36 04 9a dc 66 3a a1 a1 |6...f:..
1d 9a 2f 41 01 73 3e 01 l./A.s>.
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_size_cb: 2
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_lock_cb: 1
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_rank_cb: 1
Set size 2 (pointer: 0x566fdfe8)

Discover set members, based on the set pointer above:

uart:~$ csip_set_coordinator discover_members 0x566fdfe8
<dbg> bt_csip_set_coordinator.csip_found: Found CSIS advertiser with address→
˓→34:02:86:03:86:c0 (public)
<dbg> bt_csip_set_coordinator.is_set_member: hash: 0x33ccb1, prand 0x5bfe6a
<dbg> bt_csip_set_coordinator.is_discovered: 34:02:86:03:86:c0 (public)
<dbg> bt_csip_set_coordinator.is_discovered: 34:13:e8:b3:7f:9e (public)
<dbg> bt_csip_set_coordinator.csip_found: Found member (2 / 2)
Discovered 2/2 set members

Lock set members:

uart:~$ csip_set_coordinator lock_set
<dbg> bt_csip_set_coordinator.bt_csip_set_coordinator_lock_set: Connecting to→
˓→34:02:86:03:86:c0 (public)
<dbg> bt_csip_set_coordinator.csip_set_coordinator_connected: Connected to→
˓→34:02:86:03:86:c0 (public)
<dbg> bt_csip_set_coordinator.discover_func: Setup complete for 1 / 1
<dbg> bt_csip_set_coordinator.csip_set_coordinator_lock_set_init_cb:
<dbg> bt_csip_set_coordinator.Set SIRK
36 04 9a dc 66 3a a1 a1 |6...f:..
1d 9a 2f 41 01 73 3e 01 l./A.s>.
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_size_cb: 2
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_set_lock_cb: 1
<dbg> bt_csip_set_coordinator.csip_set_coordinator_discover_sets_read_rank_cb: 2
<dbg> bt_csip_set_coordinator.csip_set_coordinator_write_lowest_rank: Locking member→
˓→with rank 1
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was locked
<dbg> bt_csip_set_coordinator.csip_set_coordinator_write_lowest_rank: Locking member→
˓→with rank 2
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was locked
Set locked

Release set members:

uart:~$ csip_set_coordinator release_set
<dbg> bt_csip_set_coordinator.csip_set_coordinator_release_highest_rank: Releasing→
˓→member with rank 2
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was released
<dbg> bt_csip_set_coordinator.csip_set_coordinator_release_highest_rank: Releasing→
˓→member with rank 1
<dbg> bt_csip_set_coordinator.notify_func: Instance 0 lock was released
Set released
Coordinated Set Member (Server)  The server on devices that are part of a set, consisting of at least two devices, e.g. a pair of earbuds.

Using the Set Member

```
csip_set_member --help
csip_set_member - Bluetooth CSIP set member shell commands
Subcommands:
  register : Initialize the service and register callbacks [size <int>]
             [rank <int>] [not-lockable] [sirk <data>]
  update_psri : Update the advertised PSRI
  lock : Lock the set
  release : Release the set [force]
  print_sirk : Print the currently used SIRK
  set_sirk_rsp : Set the response used in SIRK requests <accept, accept_enc, reject, oob>
```

Example Usage

Setup

```
uart:~$ bt init
uart:~$ csip_set_member register
```

Bluetooth: Isochronous Channels

Commands

```
iso --help
iso - Bluetooth ISO shell commands
Subcommands:
  cig_create : [dir=tx,rx,txrx] [interval] [packing] [framing] [latency] [sdu]
               [phy] [rtn]
  cig_term : Terminate the CIG
  connect : Connect ISO Channel
  listen : <dir=tx,rx,txrx> [security level]
  send : Send to ISO Channel [count]
  disconnect : Disconnect ISO Channel
  create-big : Create a BIG as a broadcaster [enc <broadcast code>]
  broadcast : Broadcast on ISO channels
  sync-big : Synchronize to a BIG as a receiver <BIS bitfield> [mse] [timeout]
             [enc <broadcast code>]
  term-big : Terminate a BIG
```

1. [Central] Create CIG:

   Requires to be connected:

   ```
   uart:~$ iso cig_create
   CIG created
   ```

2. [Peripheral] Listen to ISO connections

   ```
   uart:~$ iso listen txrx
   ```

3. [Central] Connect ISO channel:
Media control for Generic Audio Content Control

This document describes how to run the media control functionality, using the shell, both as a client and as a server.

The media control server consists of two parts. There is a media player (mpl) that contains the logic to handle media, and there is a media control service (mcs) that serves as a GATT-based interface to the player. The media control client consists of one part, the GATT-based client (mcc).

The media control server may include an object transfer service (ots) and the media control client may include an object transfer client (otc). When these are included, a richer set of functionality is available.

The media control server and client both implement the Generic Media Control Service (only), and do not use any underlying Media Control Services.

Note that in the examples below, in many cases the debug output has been removed and long outputs may have been shortened to make the examples shorter and clearer.

Also note that this documentation does not list all shell commands, it just shows examples of some of them. The set of commands is explorable from the mcc shell and the mpl shell, by typing `mcc` or `mpl` and pressing TAB. A help text for each command can be found by doing `mcc <command> help` or `mpl <command> help`.

**Overview**  
A media player has a *name* and an *icon* that allows identification of the player for the user.

The content of the media player is structured into tracks and groups. A media player has a number of groups. A group contains tracks and other groups. (In this implementation, a group only contains tracks, not other groups.) Tracks can be divided into segments.

An active player will have a *current track*. This is the track that is playing now (if the player is playing). The current track has a *title*, a *duration* (given in hundredths of a second) and a *position* - the current position of the player within the track.

There is also a *current group* (the group of the current track), a *parent group* (the parent group of the current group) and a *next track*.

The media player is in a *state*, which will be one of playing, paused, seeking or inactive. When playing, playback happens at a given *playback speed*, and the tracks are played according to the *playing order*, which is one of the *playing orders supported*. Track changes are signalled as notifications of the *track changed* characteristic. When seeking (fast forward or fast rewind), the track position is moved according to the *seeking speed*.

The *opcodes supported* tells which operations are supported by the player by writing to the *media control point*. There is also a *search control point* that allows to search for groups and tracks according to various criteria, with the result returned in the *search results*.
Finally, the content control ID is used to associate the media player with an audio stream.

**Media Control Client (MCP)** The media control client is used to control, and to get information from, a media control server. Control is done by writing to one of the two control points, or by writing to other writable characteristics. Getting information is done by reading characteristics, or by configuring the server to send notifications.

**Using the media control client** Before use, the media control client must be initialized by the command `mcc init`.

To achieve a connection to the peer, the `bt` commands must be used - `bt init` followed by `bt advertise on` (or `bt connect` if the server is advertising).

When the media control client is connected to a media control server, the client can discover the server’s Generic Media Control Service, by giving the command `mcc discover_mcs`. This will store the handles of the service, and (optionally, but default) subscribe to all notifications.

After discovery, the media control client can read and write characteristics, including the media control point and the search control point.

**Example usage**

**Setup**

```
uart:~$ bt init
Bluetooth initialized

uart:~$ mcc init
MCC init complete

uart:~$ bt advertise on
Advertising started
```

**When connected** Service discovery (GMCS and included OTS):

```
uart:~$ mcc discover_mcs
<dbg> bt_mcc.bt_mcc_discover_mcs: start discovery of MCS primary service
<dbg> bt_mcc.discover_primary_func: [ATTRIBUTE] handle 0x00ae
<dbg> bt_mcc.discover_primary_func: Primary discovery complete
<dbg> bt_mcc.discover_primary_func: UUID: 2800
<dbg> bt_mcc.discover_primary_func: UUID: 8fd7
<dbg> bt_mcc.discover_primary_func: Start discovery of MCS characteristics
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b0
<dbg> bt_mcc.discover_mcs_char_func: Player name, UUID: 8fa0
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b2
<dbg> bt_mcc.discover_mcs_char_func: Icon Object, UUID: 8fa1
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b4
<dbg> bt_mcc.discover_mcs_char_func: Icon URI, UUID: 8fa2
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00b6
<dbg> bt_mcc.discover_mcs_char_func: Track Changed, UUID: 8fa3
<dbg> bt_mcc.discover_mcs_char_func: Subscribing - handle: 0x00b6
[...]
<dbg> bt_mcc.discover_mcs_char_func: [ATTRIBUTE] handle 0x00ea
<dbg> bt_mcc.discover_mcs_char_func: Content Control ID, UUID: 8fb5
```

(continues on next page)
Reading characteristics - the player name and the track duration as examples:

```
uart:~$ mcc read_player_name
Player name: My media player
```
```
uart:~$ mcc read_track_duration
Track duration: 6300
```

Note that the value of some characteristics may be truncated due to being too long to fit in the ATT packet. Increasing the ATT MTU may help:

```
uart:~$ gatt exchange-mtu
Exchange pending
Exchange successful
```
```
uart:~$ mcc read_track_title
Track title: Interlude #1 (Song for Alison)
```

Writing characteristics - track position as an example:

The track position is where the player “is” in the current track. Read the track position, change it by writing to it, confirm by reading it again.

```
uart:~$ mcc read_track_position
Track Position: 0
```
```
uart:~$ mcc set_track_position 500
Track Position: 500
```
```
uart:~$ mcc read_track_position
Track Position: 500
```

Controlling the player via the control point:

Writing to the control point allows the client to request the server to do operations like play, pause, fast forward, change track, change group and so on. Some operations (e.g. goto track) take an argument. Currently, raw opcode values are used as input to the control point shell command. These opcode values can be found in the mpl.h header file.
Send the play command (opcode “1”), the command to go to track (opcode “52”) number three, and the pause command (opcode “2”):

```bash
uart:~$ mcc set_cp 1
Media State: 1
Operation: 1, result: 1
Operation: 1, param: 0

uart:~$ mcc set_cp 52 3
Track changed
Track title: Interlude #3 (Levanto Seventy)
Track duration: 7800
Track Position: 0
Current Track Object ID: 0x00000000104
Next Track Object ID: 0x00000000105
Operation: 52, result: 1
Operation: 52, param: 3

uart:~$ mcc set_cp 2
Media State: 2
Operation: 2, result: 1
Operation: 2, param: 0
```

Using the included object transfer client When object transfer is supported by both the client and the server, a larger set of characteristics is available. These include object IDs for the various track and group objects. These IDs can be used to select and download the corresponding objects from the server's object transfer service.

Read the object ID of the current group object:

```bash
uart:~$ mcc read_current_group_obj_id
Current Group Object ID: 0x00000000107
```

Select the object with that ID:

```bash
uart:~$ mcc ots_select 0x107
Selecting object succeeded
```

Read the object's metadata:

```bash
uart:~$ mcc ots_read_metadata
Reading object metadata succeeded
<inf> bt_mcc: Object's meta data:
<inf> bt_mcc:  Current size :35
<inf> bt_otc:  --- Displaying 1 metadata records ---
<inf> bt_otc:  Object ID: 0x00000000107
<inf> bt_otc:  Object name: Joe Pass - Guitar Inte
<inf> bt_otc:  Object Current Size: 35
<inf> bt_otc:  Object Allocate Size: 35
<inf> bt_otc:  Type: Group Obj Type
<inf> bt_otc:  Properties:0x4
<inf> bt_otc:  - read permitted
```

Read the object itself:

The object received is a group object. It consists of a series of records consisting of a type (track or group) and an object ID.

6.1. Bluetooth
Zephyr Project Documentation, Release 3.2.99

UART:
```shell
$ mcc ots_read_current_group_object
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x0000000000102
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x0000000000103
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x0000000000104
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x0000000000105
<dbg> bt_mcc.on_group_content: Object type: 0, object ID: 0x0000000000106
```

**Search**  The search control point takes as its input a sequence of search control items, each consisting of length, type (e.g. track name or artist name) and parameter (the track name or artist name to search for). If the result is successful, the search results are stored in an object in the object transfer service. The ID of the search results ID object can be read from the search results object ID characteristic. The search result object can then be downloaded as for the current group object above. (Note that the search results object ID is empty until a search has been done.)

This implementation has a working implementation of the search functionality interface and the server-side search control point parameter parsing. But the **actual searching is faked**, the same results are returned no matter what is searched for.

There are two commands for search, one (**mcc set_scp_raw**) allows to input the search control point parameter (the sequence of search control items) as a string. The other (**mcc set_scp_iopertest**) does preset IOP test searches and takes the round number of the IOP search control point test as a parameter.

Before the search, the search results object ID is empty

UART:
```shell
$ mcc read_search_results_obj_id
Search Results Object ID: 0x000000000000
<dbg> bt_mcc.mcc_read_search_results_obj_id_cb: Zero-length Search Results Object ID
```

Run the search corresponding to the fourth round of the IOP test:

The search control point parameter generated by this command and parameter has one search control item. The length field (first octet) is 16 (0x10). (The length of the length field itself is not included.) The type field (second octet) is 0x04 (search for a group name). The parameter (the group name to search for) is “TSPX_Group_Name”.

UART:
```shell
$ mcc set_scp_iopertest 4
Search string:
00000000: 10 04 54 53 50 4f 75 70 5f 4e 61 6d 65 |..TSPX_G roup_Nam|
00000010: 65 |e |
Search control point notification result code: 1
Search Results Object ID: 0x0000000000107
Search Control Point set
```

After the successful search, the search results object ID has a value:

UART:
```shell
$ mcc read_search_results_obj_id
Search Results Object ID: 0x0000000000107
```

**Media Control Service (MCS)**  The media control service (mcs) and the associated media player (mpl) typically reside on devices that can provide access to, and serve, media content, like PCs and smartphones.

As mentioned above, the media player (mpl) has the player logic, while the media control service (mcs) has the GATT-based interface. This separation is done so that the media player can also be used without the GATT-based interface.

1716 Chapter 6. Connectivity
Using the media control service and the media player  The media control service and the media player are in general controlled remotely, from the media control client.

Before use, the media control client must be initialized by the command mpl init.

As for the client, the bt commands are used for connecting - bt init followed by bt connect <address> <address type> (or bt advertise on if the server is advertising).

Example Usage

Setup

```
uart:~$ bt init
Bluetooth initialized

uart:~$ mpl init
[Large amounts of debug output]

uart:~$ bt connect F9:33:3B:67:D2:A7 (random)
Connection pending
Connected: F9:33:3B:67:D2:A7 (random)
```

When connected  Control is done from the client.

The server will give debug output related to the various operations performed by the client.

Example: Debug output by the server when the client gives the “next track” command:

```
[00:13:29.932,373] <dbg> bt_mcs.control_point_write: Opcode: 49
[00:13:29.932,403] <dbg> bt_mpl.paused_state_operation_handler: Operation opcode: 49
[00:13:29.932,495] <dbg> bt_mpl.do_next_track: Track ID before: 0x000000000104
[00:13:29.932,586] <dbg> bt_mpl.do_next_track: Track ID after: 0x000000000105
[00:13:29.932,617] <dbg> bt_mcs.mpl_track_changed_cb: Notifying track change
[00:13:29.932,800] <dbg> bt_mcs.mpl_track_duration_cb: Notifying track duration: 13500
[00:13:29.932,861] <dbg> bt_mcs.mpl_track_position_cb: Notifying track position: 0
[00:13:29.933,044] <dbg> bt_mcs.mpl_current_track_id_cb: Notifying current track ID: 0x000000000105
[00:13:29.933,258] <dbg> bt_mcs.mpl_next_track_id_cb: Notifying next track ID: 0x000000000106
[00:13:29.933,380] <dbg> bt_mcs.mpl_operation_cb: Notifying control point - opcode: → 49, result: 1
```

Some server commands are available. These commands force notifications of the various characteristics, for testing that the client receives notifications. The values sent in the notifications caused by these testing commands are independent of the media player, so they do not correspond the actual values of the characteristics nor to the actual state of the media player.

Example: Force (fake value) notification of the track duration:

```
uart:~$ mpl duration_changed_cb
[00:15:17.491,058] <dbg> bt_mcs.mpl_track_duration_cb: Notifying track duration: 12000
```
6.2 Networking

The networking section contains information regarding the network stack of the Zephyr kernel. Use the information to understand the principles behind the operation of the stacks and how they were implemented.

6.2.1 Overview

- Supported Features
- Source Tree Layout

Supported Features

The networking IP stack is modular and highly configurable via build-time configuration options. You can minimize system memory consumption by enabling only those network features required by your application. Almost all features can be disabled if not needed.

- IPv6
  - The support for IPv6 is enabled by default. Various IPv6 sub-options can be enabled or disabled depending on networking needs.
    - Developer can set the number of unicast and multicast IPv6 addresses that are active at the same time.
    - The IPv6 address for the device can be set either statically or dynamically using SLAAC (Stateless Address Auto Configuration) (RFC 4862).
    - The system also supports multiple IPv6 prefixes and the maximum IPv6 prefix count can be configured at build time.
    - The IPv6 neighbor cache can be disabled if not needed, and its size can be configured at build time.
    - The IPv6 neighbor discovery support (RFC 4861) is enabled by default.
    - Multicast Listener Discovery v2 support (RFC 3810) is enabled by default.
    - IPv6 header compression (6lo) is available for IPv6 connectivity for Bluetooth IPSP (RFC 7668) and IEEE 802.15.4 networks (RFC 4944).

- IPv4
  - The legacy IPv4 is supported by the networking stack. It cannot be used by IEEE 802.15.4 or Bluetooth IPSP as those network technologies support only IPv6. IPv4 can be used in Ethernet based networks. By default IPv4 support is disabled.
    - DHCP (Dynamic Host Configuration Protocol) client is supported (RFC 2131).
    - The IPv4 address can also be configured manually. Static IPv4 addresses are supported by default.

- Dual stack support
  - The networking stack allows a developer to configure the system to use both IPv6 and IPv4 at the same time.

- UDP
  - User Datagram Protocol (RFC 768) is supported. The developer can send UDP datagrams (client side support) or create a listener to receive UDP packets destined to certain port (server side support).

- TCP
  - Transmission Control Protocol (RFC 793) is supported. Both server and client roles can be used the application. The amount of TCP sockets that are available to applications can be configured at build time.

- BSD Sockets API
  - Support for a subset of a BSD sockets compatible API is implemented. Both blocking and non-blocking datagram (UDP) and stream (TCP) sockets are supported.
• **Secure Sockets API** Experimental support for TLS/DTLS secure protocols and configuration options for sockets API. Secure functions for the implementation are provided by mbedTLS library.

• **MQTT** Message Queue Telemetry Transport (ISO/IEC PRF 20922) is supported. A sample mqtt-publisher-sample client application for MQTT v3.1.1 is implemented.

• **CoAP** Constrained Application Protocol (RFC 7252) is supported. Both coap-client-sample and coap-server-sample sample applications are implemented.

• **LwM2M** OMA Lightweight Machine-to-Machine Protocol (LwM2M specification 1.0.2) is supported via the “Bootstrap”, “Client Registration”, “Device Management & Service Enablement” and “Information Reporting” interfaces. The required core LwM2M objects are implemented as well as several IPSO Smart Objects. (LwM2M specification 1.1.1) is supported in similar manner when enabled with a Kconfig option. lwm2m-client-sample implements the library as an example.

• **DNS** Domain Name Service (RFC 1035) client functionality is supported. Applications can use the DNS API to query domain name information or IP addresses from the DNS server. Both IPv4 (A) and IPv6 (AAAA) records can be queried. Both multicast DNS (mDNS) (RFC 6762) and link-local multicast name resolution (LLMNR) (RFC 4795) are supported.

• **Network Management API**. Applications can use network management API to listen management events generated by core stack when for example IP address is added to the device, or network interface is coming up etc.

• **Multiple Network Technologies**. The Zephyr OS can be configured to support multiple network technologies at the same time simply by enabling them in Kconfig: for example, Ethernet and 802.15.4 support. Note that no automatic IP routing functionality is provided between these technologies. Applications can send data according to their needs to desired network interface.

• **Minimal Copy Network Buffer Management**. It is possible to have minimal copy network data path. This means that the system tries to avoid copying application data when it is sent to the network.

• **Virtual LAN support**. Virtual LANs (VLANs) allow partitioning of physical ethernet networks into logical networks. See [VLAN support](#) for more details.

• **Network traffic classification**. The sent and received network packets can be prioritized depending on application needs. See [traffic classification](#) for more details.

• **Time Sensitive Networking**. The gPTP (generalized Precision Time Protocol) is supported. See [gPTP support](#) for more details.

• **Network shell**. The network shell provides helpers for figuring out network status, enabling/disabling features, and issuing commands like ping or DNS resolving. The net-shell is useful when developing network software. See [network shell](#) for more details.

Additionally these network technologies (link layers) are supported in Zephyr OS v1.7 and later:

- IEEE 802.15.4
- Bluetooth
- Ethernet
- SLIP (IP over serial line). Used for testing with QEMU. It provides ethernet interface to host system (like Linux) and test applications can be run in Linux host and send network data to Zephyr OS device.

### Source Tree Layout

The networking stack source code tree is organized as follows:

```
subsyst/et/np/
```

This is where the IP stack code is located.
subsys/net/l2/
   This is where the IP stack layer 2 code is located. This includes generic support for Bluetooth IPSP adaptation, Ethernet, IEEE 802.15.4 and Wi-Fi.

subsys/net/lib/
   Application-level protocols (DNS, MQTT, etc.) and additional stack components (BSD Sockets, etc.).

include/net/
   Public API header files. These are the header files applications need to include to use IP networking functionality.

samples/net/
   Sample networking code. This is a good reference to get started with network application development.

tests/net/
   Test applications. These applications are used to verify the functionality of the IP stack, but are not the best source for sample code (see samples/net instead).

6.2.2 Network Stack Architecture

Network Packet Processing Statistics

This page describes how to get information about network packet processing statistics inside network stack.

Network stack contains infrastructure to figure out how long the network packet processing takes either in sending or receiving path. There are two Kconfig options that control this. For transmit (TX) path the option is called CONFIG_NET_PKT_TXTIME_STATS and for receive (RX) path the options is called CONFIG_NET_PKT_RXTIME_STATS. Note that for TX, all kind of network packet statistics is collected. For RX, only UDP, TCP or raw packet type network packet statistics is collected.

After enabling these options, the net stats network shell command will show this information:

<table>
<thead>
<tr>
<th></th>
<th>Value 1</th>
<th>Value 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Avg TX net_pkt</td>
<td>11484</td>
<td>67 us</td>
</tr>
<tr>
<td>Avg RX net_pkt</td>
<td>11474</td>
<td>43 us</td>
</tr>
</tbody>
</table>

Note: The values above and below are from emulated qemu_x86 board and UDP traffic

The TX time tells how long it took for network packet from its creation to when it was sent to the network. The RX time tells the time from its creation to when it was passed to the application. The values are in microseconds. The statistics will be collected per traffic class if there are more than one transmit or receive queues defined in the system. These are controlled by CONFIG_NET_TC_TX_COUNT and CONFIG_NET_TC_RX_COUNT options.

If you enable CONFIG_NET_PKT_TXTIME_STATS_DETAIL or CONFIG_NET_PKT_RXTIME_STATS_DETAIL options, then additional information for TX or RX network packets are collected when the network packet traverses the IP stack.

After enabling these options, the net stats will show this information:

<table>
<thead>
<tr>
<th></th>
<th>Value 1</th>
<th>Value 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Avg TX net_pkt</td>
<td>18902</td>
<td>63 us</td>
</tr>
<tr>
<td>Avg RX net_pkt</td>
<td>18892</td>
<td>42 us</td>
</tr>
</tbody>
</table>

The numbers inside the brackets contain information how many microseconds it took for a network packet to go from previous state to next.

In the TX example above, the values are averages over 18902 packets and contain this information:

- Packet was created by application so the time is 0.
* Packet is about to be placed to transmit queue. The time it took from network packet creation to this state, is 22 microseconds in this example.

* The correct TX thread is invoked, and the packet is read from the transmit queue. It took 15 microseconds from previous state.

* The network packet was just sent and the network stack is about to free the network packet. It took 23 microseconds from previous state.

* In total it took on average 60 microseconds to get the network packet sent. The value 63 tells also the same information, but is calculated differently so there is slight difference because of rounding errors.

In the RX example above, the values are averages over 18892 packets and contain this information:

* Packet was created network device driver so the time is 0.

* Packet is about to be placed to receive queue. The time it took from network packet creation to this state, is 9 microseconds in this example.

* The correct RX thread is invoked, and the packet is read from the receive queue. It took 6 microseconds from previous state.

* The network packet is then processed and placed to correct socket queue. It took 11 microseconds from previous state.

* The last value tells how long it took from there to the application. Here the value is 13 microseconds.

* In total it took on average 39 microseconds to get the network packet sent. The value 42 tells also the same information, but is calculated differently so there is slight difference because of rounding errors.

The Zephyr network stack is a native network stack specifically designed for Zephyr OS. It consists of layers, each meant to provide certain services to other layers. Network stack functionality is highly configurable via Kconfig options.

---

**High level overview of the network stack**

**Network data flow**

- Data receiving (RX)
- Data sending (TX)

**Network packet processing statistics**

---

**High level overview of the network stack**

The network stack is layered and consists of the following parts:

- **Network Application.** The network application can either use the provided application-level protocol libraries or access the BSD socket API directly to create a network connection, send or receive data, and close a connection. The application can also use the network management API to configure the network and set related parameters such as network link options, starting a scan (when applicable), listen network configuration events, etc. The network interface API can be used to set IP address to a network interface, taking the network interface down, etc.

- **Network Protocols.** This provides implementations for various protocols such as
  
  - Application-level network protocols like CoAP, LWM2M, and MQTT. See application protocols chapter for information about them.
  
  - Core network protocols like IPv6, IPv4, UDP, TCP, ICMPv4, and ICMPv6. You access these protocols by using the BSD socket API.
Fig. 6.7: Network stack overview
• **Network Interface Abstraction.** This provides functionality that is common in all the network interfaces, such as setting network interface down, etc. There can be multiple network interfaces in the system. See network interface overview for more details.

• **L2 Network Technologies.** This provides a common API for sending and receiving data to and from an actual network device. See L2 overview for more details. These network technologies include Ethernet, IEEE 802.15.4, Bluetooth, CANBUS, etc. Some of these technologies support IPv6 header compression (6Lo), see RFC 6282 for details. For example ARP for IPv4 is done by the Ethernet component.

• **Network Device Drivers.** The actual low-level device drivers handle the physical sending or receiving of network packets.

**Network data flow**

An application typically consists of one or more threads that execute the application logic. When using the BSD socket API, the following things will happen.

**Data receiving (RX)**

1. A network data packet is received by a device driver.
2. The device driver allocates enough network buffers to store the received data. The network packet is placed in the proper RX queue (implemented by k_fifo). By default there is only one receive queue in the system, but it is possible to have up to 8 receive queues. These queues will process incoming packets with different priority. See Traffic Classification for more details. The receive queues also act as a way to separate the data processing pipeline (bottom-half) as the device driver is running in an interrupt context and it must do its processing as fast as possible.
3. The network packet is then passed to the correct L2 driver. The L2 driver can check if the packet is proper and modify it if needed, e.g. strip L2 header and frame check sequence, etc.
4. The packet is processed by a network interface. The network statistics are collected if enabled by CONFIG_NET_STATISTICS.
5. The packet is then passed to L3 processing. If the packet is IP based, then the L3 layer checks if the packet is a proper IPv6 or IPv4 packet.
6. A socket handler then finds an active socket to which the network packet belongs and puts it in a queue for that socket, in order to separate the networking code from the application. Typically the application is run in userspace context and the network stack is run in kernel context.
7. The application will then receive the data and can process it as needed. The application should have used the BSD socket API to create a socket that will receive the data.

**Data sending (TX)**

1. The application should use the BSD socket API when sending the data.
2. The application data is prepared for sending to kernel space and then copied to internal net_buf structures.
3. Depending on the socket type, a protocol header is added in front of the data. For example, if the socket is a UDP socket, then a UDP header is constructed and placed in front of the data.
4. An IP header is added to the network packet for a UDP or TCP packet.
5. The network stack will check that the network interface is properly set for the network packet, and also will make sure that the network interface is enabled before the data is queued to be sent.
6. The network packet is then classified and placed to the proper transmit queue (implemented by k_fifo). By default there is only one transmit queue in the system, but it is possible to have up to 8 transmit queues. These queues will process the sent packets with different priority. See Traffic...
Fig. 6.8: Network RX data flow
Fig. 6.9: Network TX data flow
Classification for more details. After the transmit packet classification, the packet is checked by
the correct L2 layer module. The L2 module will do additional checks for the data and it will also
create any L2 headers for the network packet. If everything is ok, the data is given to the network
device driver to be sent out.

7. The device driver will send the packet to the network.

Note that in both the TX and RX data paths, the queues (kfifo's) form separation points where data is
passed from one thread to another. These threads might run in different contexts (kernel vs. userspace)
and with different priorities.

Network packet processing statistics

See information about network processing statistics here.

6.2.3 Network Connectivity API

Applications should use the BSD socket API defined in include/zephyr/net/socket.h to create a connec-
tion, send or receive data, and close a connection. The same API can be used when working with UDP
or TCP data. See BSD socket API for more details.

See sockets-echo-server-sample and sockets-echo-client-sample applications how to create a simple
server or client BSD socket based application.

The legacy connectivity API in include/zephyr/net/net_context.h should not be used by applications.

6.2.4 Networking with the host system

Networking with native_posix board

- Prerequisites
- Basic Setup
  - Step 1 - Create Ethernet interface
  - Step 2 - Start app in native_posix board
  - Step 3 - Connect to console (optional)

This page describes how to set up a virtual network between a (Linux) host and a Zephyr application
running in a native_posix board.

In this example, the sockets-echo-server-sample sample application from the Zephyr source distribution
is run in native_posix board. The Zephyr native_posix board instance is connected to a Linux host using
a tuntap device which is modeled in Linux as an Ethernet network interface.

Prerequisites On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate
Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```

Basic Setup For the steps below, you will need three terminal windows:

- Terminal #1 is terminal window with net-tools being the current directory (cd net-tools)
- Terminal #2 is your usual Zephyr development terminal, with the Zephyr environment initialized.
• Terminal #3 is the console to the running Zephyr native_posix instance (optional).

**Step 1 - Create Ethernet interface**  
Before starting native_posix with network emulation, a network interface should be created.

In terminal #1, type:

```
./net-setup.sh
```

You can tweak the behavior of the net-setup.sh script. See various options by running `net-setup.sh` like this:

```
./net-setup.sh --help
```

**Step 2 - Start app in native_posix board**  
Build and start the `echo_server` sample application.

In terminal #2, type:

```
west build -b native_posix samples/net/sockets/echo_server
west build -t run
```

**Step 3 - Connect to console (optional)**  
The console window should be launched automatically when the Zephyr instance is started but if it does not show up, you can manually connect to the console. The native_posix board will print a string like this when it starts:

```
UART connected to pseudotty: /dev/pts/5
```

You can manually connect to it like this:

```
screen /dev/pts/5
```

---

**Networking with QEMU Ethernet**

- **Prerequisites**
- **Basic Setup**
  - **Step 1 - Create Ethernet interface**
  - **Step 2 - Start app in QEMU board**

This page describes how to set up a virtual network between a (Linux) host and a Zephyr application running in QEMU.

In this example, the sockets-echo-server-sample sample application from the Zephyr source distribution is run in QEMU. The Zephyr instance is connected to a Linux host using a tuntap device which is modeled in Linux as an Ethernet network interface.

**Prerequisites**  
On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```
Basic Setup  For the steps below, you will need two terminal windows:

- Terminal #1 is terminal window with net-tools being the current directory (cd net-tools)
- Terminal #2 is your usual Zephyr development terminal, with the Zephyr environment initialized.

When configuring the Zephyr instance, you must select the correct Ethernet driver for QEMU connectivity:

- For qemu_x86, select Intel(R) PRO/1000 Gigabit Ethernet driver Ethernet driver. Driver is called e1000 in Zephyr source tree.
- For qemu_cortex_m3, select TI Stellaris MCU family ethernet driver Ethernet driver. Driver is called stellaris in Zephyr source tree.
- For mps2_an385, select SMSC911x/9220 Ethernet driver Ethernet driver. Driver is called smsc911x in Zephyr source tree.

Step 1 - Create Ethernet interface  Before starting QEMU with network connectivity, a network interface should be created in the host system.

In terminal #1, type:

```
./net-setup.sh
```

You can tweak the behavior of the net-setup.sh script. See various options by running net-setup.sh like this:

```
./net-setup.sh --help
```

Step 2 - Start app in QEMU board  Build and start the sockets-echo-server-sample sample application. In this example, the qemu_x86 board is used.

In terminal #2, type:

```
west build -b qemu_x86 samples/net/sockets/echo_server -- -DOVERLAY_CONFIG=overlay-e1000.conf
west build -t run
```

Exit QEMU by pressing CTRL+A x.
This page describes how to set up a virtual network between a (Linux) host and a Zephyr application running in a QEMU virtual machine (built for Zephyr targets such as qemu_x86 and qemu_cortex_m3).

In this example, the sockets-echo-server-sample sample application from the Zephyr source distribution is run in QEMU. The QEMU instance is connected to a Linux host using a serial port, and SLIP is used to transfer data between the Zephyr application and Linux (over a chain of virtual connections).

**Prerequisites**  On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```bash
git clone https://github.com/zephyrproject-rtos/net-tools
cd net-tools
make
```

*Note:* If you get an error about AX_CHECK_COMPILE_FLAG, install package `autoconf-archive` package on Debian/Ubuntu.

**Basic Setup**  For the steps below, you will need at least 4 terminal windows:

- Terminal #1 is your usual Zephyr development terminal, with the Zephyr environment initialized.
- Terminals #2, #3, and #4 are terminal windows with net-tools being the current directory (cd net-tools)

**Step 1 - Create helper socket**  Before starting QEMU with network emulation, a Unix socket for the emulation should be created.

In terminal #2, type:

```
./loop-socat.sh
```

**Step 2 - Start TAP device routing daemon**  In terminal #3, type:

```
sudo ./loop-slip-tap.sh
```

For applications requiring DNS, you may need to restart the host's DNS server at this point, as described in *Setting up Zephyr and NAT/masquerading on host to access Internet*.

**Step 3 - Start app in QEMU**  Build and start the echo_server sample application.

In terminal #1, type:

```
west build -b qemu_x86 samples/net/sockets/echo_server
west build -t run
```

If you see an error from QEMU about `unix:/tmp/slip.sock`, it means you missed Step 1 above.
Step 4 - Run apps on host  Now in terminal #4, you can run various tools to communicate with the application running in QEMU.

You can start with pings:

```
ping 192.0.2.1
ping6 2001:db8::1
```

You can use the netcat ("nc") utility, connecting using UDP:

```
echo foobar | nc -6 -u 2001:db8::1 4242
foobar
```

```
echo foobar | nc -u 192.0.2.1 4242
foobar
```

If echo_server is compiled with TCP support (now enabled by default for the echo_server sample, CONFIG_NET_TCP=y):

```
echo foobar | nc -6 -q2 2001:db8::1 4242
foobar
```

Note: Use Ctrl+C to exit.

You can also use the telnet command to achieve the above.

Step 5 - Stop supporting daemons  When you are finished with network testing using QEMU, you should stop any daemons or helpers started in the initial steps, to avoid possible networking or routing problems such as address conflicts in local network interfaces. For example, stop them if you switch from testing networking with QEMU to using real hardware, or to return your host laptop to normal Wi-Fi use.

To stop the daemons, press Ctrl+C in the corresponding terminal windows (you need to stop both loop-slip-tap.sh and loop-socat.sh).

Exit QEMU by pressing CTRL+A x.

Setting up Zephyr and NAT/masquerading on host to access Internet  To access the internet from a Zephyr application, some additional setup on the host may be required. This setup is common for both application running in QEMU and on real hardware, assuming that a development board is connected to the development host. If a board is connected to a dedicated router, it should not be needed.

To access the internet from a Zephyr application using IPv4, a gateway should be set via DHCP or configured manually. For applications using the "Settings" facility (with the config option CONFIG_NET_CONFIG_SETTINGS enabled), set the CONFIG_NET_CONFIG_MY_IPV4_GW option to the IP address of the gateway. For apps not using the "Settings" facility, set up the gateway by calling the net_if_ipv4_set_gw() at runtime.

To access the internet from a custom application running in QEMU, NAT (masquerading) should be set up for QEMU’s source address. Assuming 192.0.2.1 is used, the following command should be run as root:

```
iptables -t nat -A POSTROUTING -j MASQUERADE -s 192.0.2.1
```

Additionally, IPv4 forwarding should be enabled on the host, and you may need to check that other firewall (iptables) rules don’t interfere with masquerading. To enable IPv4 forwarding the following command should be run as root:
Some applications may also require a DNS server. A number of Zephyr-provided samples assume by default that the DNS server is available on the host (IP 192.0.2.2), which, in modern Linux distributions, usually runs at least a DNS proxy. When running with QEMU, it may be required to restart the host’s DNS, so it can serve requests on the newly created TAP interface. For example, on Debian-based systems:

```
service dnsmasq restart
```

An alternative to relying on the host’s DNS server is to use one in the network. For example, 8.8.8.8 is a publicly available DNS server. You can configure it using `CONFIG_DNS_SERVER1` option.

**Network connection between two QEMU VMs** Unlike the VM-to-Host setup described above, VM-to-VM setup is automatic. For sample applications that support this mode (such as the echo_server and echo_client samples), you will need two terminal windows, set up for Zephyr development.

**Terminal #1:**

```
west build -b qemu_x86 samples/net/sockets/echo_server
```

This will start QEMU, waiting for a connection from a client QEMU.

**Terminal #2:**

```
west build -b qemu_x86 samples/net/sockets/echo_client
```

This will start a second QEMU instance, where you should see logging of data sent and received in both.

**Running multiple QEMU VMs of the same sample** If you find yourself wanting to run multiple instances of the same Zephyr sample application, which do not need to talk to each other, use the `QEMU_INSTANCE` argument.

Start `socat` and `tunslip6` manually (instead of using the `loop-xxx.sh` scripts) for as many instances as you want. Use the following as a guide, replacing `MAIN` or `OTHER`.

**Terminal #1:**

```
$ socat PTY,link=/tmp/slip.devMAIN UNIX-LISTEN:/tmp/slip.sockMAIN $ZEPHYR_BASE/../net-tools/tunslip6 -t tapMAIN -T -s /tmp/slip.devMAIN 2001:db8::1/64
# Now run Zephyr
make -Cbuild run QEMU_INSTANCE=MAIN
```

**Terminal #2:**

```
$ socat PTY,link=/tmp/slip.devOTHER UNIX-LISTEN:/tmp/slip.sockOTHER $ZEPHYR_BASE/../net-tools/tunslip6 -t tapOTHER -T -s /tmp/slip.devOTHER 2001:db8::1/64
make -Cbuild run QEMU_INSTANCE=OTHER
```

**USB Device Networking**
This page describes how to set up networking between a Linux host and a Zephyr application running on USB supported devices.

The board is connected to Linux host using USB cable and provides an Ethernet interface to the host. The sockets-echo-server-sample application from the Zephyr source distribution is run on supported board. The board is connected to a Linux host using a USB cable providing an Ethernet interface to the host.

**Basic Setup**

To communicate with the Zephyr application over a newly created Ethernet interface, we need to assign IP addresses and set up a routing table for the Linux host. After plugging a USB cable from the board to the Linux host, the `cdc_ether` driver registers a new Ethernet device with a provided MAC address.

You can check that network device is created and MAC address assigned by running `dmesg` from the Linux host.

```
cdc_ether 1-2.7:1.0 eth0: register 'cdc_ether' at usb-0000:00:01.2-2.7, CDC Ethernet
Device, 00:00:5e:00:53:01
```

We need to set it up and assign IP addresses as explained in the following section.

**Choosing IP addresses**

To establish network connection to the board we need to choose IP address for the interface on the Linux host.

It make sense to choose addresses in the same subnet we have in Zephyr application. IP addresses usually set in the project configuration files and may be checked also from the shell with following commands. Connect a serial console program (such as putTTY) to the board, and enter this command to the Zephyr shell:

```
shell> net iface
```

This command shows that one IPv4 address and two IPv6 addresses have been assigned to the board. We can use either IPv4 or IPv6 for network connection depending on the board network configuration.

Next step is to assign IP addresses to the new Linux host interface, in the following steps `enx00005e005301` is the name of the interface on my Linux system.

**Setting IPv4 address and routing**
# ip address add dev enx00005e005301 192.0.2.2
# ip link set enx00005e005301 up
# ip route add 192.0.2.0/24 dev enx00005e005301

### Setting IPv6 address and routing

# ip address add dev enx00005e005301 2001:db8::2
# ip link set enx00005e005301 up
# ip -6 route add 2001:db8::/64 dev enx00005e005301

### Testing connection

From the host we can test the connection by pinging Zephyr IP address of the board with:

$ ping 192.0.2.1
PING 192.0.2.1 (192.0.2.1) 56(84) bytes of data.
64 bytes from 192.0.2.1: icmp_seq=1 ttl=64 time=2.30 ms
64 bytes from 192.0.2.1: icmp_seq=2 ttl=64 time=1.43 ms
64 bytes from 192.0.2.1: icmp_seq=3 ttl=64 time=2.45 ms
...

### Networking with QEMU User

- **Introduction**
- **Using SLIRP with Zephyr**
- **Limitations**

This page is intended to serve as a starting point for anyone interested in using QEMU SLIRP with Zephyr.

**Introduction**  SLIRP is a network backend which provides the complete TCP/IP stack within QEMU and uses that stack to implement a virtual NAT'd network. As there are no dependencies on the host, SLIRP is simple to setup.

By default, QEMU uses the 10.0.2.X/24 network and runs a gateway at 10.0.2.2. All traffic intended for the host network has to travel through this gateway, which will filter out packets based on the QEMU command line parameters. This gateway also functions as a DHCP server for all GOS, allowing them to be automatically assigned with an IP address starting from 10.0.2.15.


**Using SLIRP with Zephyr**  In order to use SLIRP with Zephyr, the user has to set the Kconfig option to enable User Networking.

CONFIG_NET_QEMU_USER=y

Once this configuration option is enabled, all QEMU launches will use SLIRP. In the default configuration, Zephyr only enables User Networking, and does not pass any arguments to it. This means that the Guest will only be able to communicate to the QEMU gateway, and any data intended for the host machine will be dropped by QEMU.

In general, QEMU User Networking can take in a lot of arguments including,
• Information about host/guest port forwarding. This must be provided to create a communication channel between the guest and host.

• Information about network to use. This may be valuable if the user does not want to use the default 10.0.2.0/24 network.

• Tell QEMU to start DHCP server at user-defined IP address.

• ID and other information.

As this information varies with every use case, it is difficult to come up with good defaults that work for all. Therefore, Zephyr Implementation offloads this to the user, and expects that they will provide arguments based on requirements. For this, there is a Kconfig string which can be populated by the user.

```
CONFIG_NET_QEMU_USER_EXTRA_ARGS="net=192.168.0.0/24,hostfwd=tcp::8080-:8080"
```

This option is appended as-is to the QEMU command line. Therefore, any problems with this command line will be reported by QEMU only. Here’s what this particular example will do,

• Make QEMU use the 192.168.0.0/24 network instead of the default.

• Enable forwarding of any TCP data received from port 8080 of host to port 8080 of guest, and vice versa.

**Limitations** If the user does not have any specific networking requirements other than the ability to access a web page from the guest, user networking (slirp) is a good choice. However, it has several limitations

• There is a lot of overhead so the performance is poor.

• The guest is not directly accessible from the host or the external network.

• In general, ICMP traffic does not work (so you cannot use ping within a guest).

• As port mappings need to be defined before launching qemu, clients which use dynamically generated ports cannot communicate with external network.

• There is a bug in the SLIRP implementation which filters out all IPv6 packets from the guest. See [https://bugs.launchpad.net/qemu/+bug/1724590](https://bugs.launchpad.net/qemu/+bug/1724590) for details. Therefore, IPv6 will not work with User Networking.

**Networking with multiple Zephyr instances**

- **Prerequisites**
- **Basic Setup**
  - Step 1 - Create configuration files
  - Step 2 - Create Ethernet interfaces
  - Step 3 - Setup network bridging
  - Step 4 - Start Zephyr instances

This page describes how to set up a virtual network between multiple Zephyr instances. The Zephyr instances could be running inside QEMU or could be native_posix board processes. The Linux host can be used to route network traffic between these systems.

**Prerequisites** On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:
Basic Setup
For the steps below, you will need five terminal windows:

- Terminal #1 and #2 are terminal windows with net-tools being the current directory (cd net-tools)
- Terminal #3, where you setup bridging in Linux host
- Terminal #4 and #5 are your usual Zephyr development terminal, with the Zephyr environment initialized.

As there are multiple ways to setup the Zephyr network, the example below uses qemu_x86 board with e1000 Ethernet controller and native_posix board to simplify the setup instructions. You can use other QEMU boards and drivers if needed, see Networking with QEMU Ethernet for details. You can also use two or more native_posix board Zephyr instances and connect them together.

Step 1 - Create configuration files
Before starting QEMU with network connectivity, a network interfaces for each Zephyr instance should be created in the host system. The default setup for creating network interface cannot be used here as that is for connecting one Zephyr instance to Linux host.

For Zephyr instance #1, create file called zephyr1.conf to net-tools project, or to some other suitable directory.

```bash
# Configuration file for setting IP addresses for a network interface.
INTERFACE="$1"
HWADDR="00:00:5e:00:53:11"
IPV6_ADDR_1="2001:db8:100::2"
IPV6_ROUTE_1="2001:db8:100::/64"
IPV4_ADDR_1="198.51.100.2/24"
IPV4_ROUTE_1="198.51.100.0/24"
ip link set dev $INTERFACE up
ip link set dev $INTERFACE address $HWADDR
ip -6 address add $IPV6_ADDR_1 dev $INTERFACE nodad
ip -6 route add $IPV6_ROUTE_1 dev $INTERFACE
ip address add $IPV4_ADDR_1 dev $INTERFACE
ip route add $IPV4_ROUTE_1 dev $INTERFACE > /dev/null 2>&1
```

For Zephyr instance #2, create file called zephyr2.conf to net-tools project, or to some other suitable directory.

```bash
# Configuration file for setting IP addresses for a network interface.
INTERFACE="$1"
HWADDR="00:00:5e:00:53:22"
IPV6_ADDR_1="2001:db8:200::2"
IPV6_ROUTE_1="2001:db8:200::/64"
IPV4_ADDR_1="203.0.113.2/24"
IPV4_ROUTE_1="203.0.113.0/24"
ip link set dev $INTERFACE up
ip link set dev $INTERFACE address $HWADDR
ip -6 address add $IPV6_ADDR_1 dev $INTERFACE nodad
ip -6 route add $IPV6_ROUTE_1 dev $INTERFACE
ip address add $IPV4_ADDR_1 dev $INTERFACE
ip route add $IPV4_ROUTE_1 dev $INTERFACE > /dev/null 2>&1
```

Step 2 - Create Ethernet interfaces
The following net-setup.sh commands should be typed in net-tools directory (cd net-tools).
In terminal #1, type:

```
./net-setup.sh -c zephyr1.conf -i zeth.1
```

In terminal #2, type:

```
./net-setup.sh -c zephyr2.conf -i zeth.2
```

**Step 3 - Setup network bridging**  In terminal #3, type:

```
sudo brctl addbr zeth-br
sudo brctl addif zeth-br zeth.1
sudo brctl addif zeth-br zeth.2
sudo ifconfig zeth-br up
```

**Step 4 - Start Zephyr instances**  In this example we start sockets-echo-server-sample and sockets-echo-client-sample applications. You can use other applications too as needed.

In terminal #4, if you are using QEMU, type this:

```
w west build -d build/server -b qemu_x86 -t run \
    samples/net/sockets/echo_server -- \
    -DOVERLAY_CONFIG=overlay-e1000.conf \
    -DCONFIG_NET_CONFIG_MY_IPV4_ADDR="198.51.100.1" \
    -DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="203.0.113.1" \
    -DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:100::1" \
    -DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:200::1" \
    -DCONFIG_NET_CONFIG_MY_IPV4_GW="203.0.113.1" \
    -DCONFIG_ETH_QEMU_IFACE_NAME="zeth.1" \
    -DCONFIG_ETH_QEMU_EXTRA_ARGS="mac=00:00:5e:00:53:01"
```

or if you want to use native_posix board, type this:

```
w west build -d build/server -b native_posix -t run \
    samples/net/sockets/echo_server -- \
    -DCONFIG_NET_CONFIG_MY_IPV4_ADDR="198.51.100.1" \
    -DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="203.0.113.1" \
    -DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:100::1" \
    -DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:200::1" \
    -DCONFIG_NET_CONFIG_MY_IPV4_GW="203.0.113.1" \
    -DCONFIG_ETH_NATIVE_POSIX_DRV_NAME="zeth.1" \
    -DCONFIG_ETH_NATIVE_POSIX_MAC_ADDR="00:00:5e:00:53:01" \
    -DCONFIG_ETH_NATIVE_POSIX_RANDOM_MAC=n
```

In terminal #5, if you are using QEMU, type this:

```
w west build -d build/client -b qemu_x86 -t run \
    samples/net/sockets/echo_client -- \
    -DOVERLAY_CONFIG=overlay-e1000.conf \
    -DCONFIG_NET_CONFIG_MY_IPV4_ADDR="203.0.113.1" \
    -DCONFIG_NET_CONFIG_PEER_IPV4_ADDR="198.51.100.1" \
    -DCONFIG_NET_CONFIG_MY_IPV6_ADDR="2001:db8:200::1" \
    -DCONFIG_NET_CONFIG_PEER_IPV6_ADDR="2001:db8:100::1" \
    -DCONFIG_NET_CONFIG_MY_IPV4_GW="198.51.100.1" \
    -DCONFIG_ETH_QEMU_IFACE_NAME="zeth.2" \
    -DCONFIG_ETH_QEMU_EXTRA_ARGS="mac=00:00:5e:00:53:02"
```

or if you want to use native_posix board, type this:
Also if you have firewall enabled in your host, you need to allow traffic between zeth.1, zeth.2 and zeth-br interfaces.

Networking with QEMU and IEEE 802.15.4

This page describes how to set up a virtual network between two QEMUs that are connected together via UART and are running IEEE 802.15.4 link layer between them. Note that this only works in Linux host.

Basic Setup

For the steps below, you will need two terminal windows:

- Terminal #1 is terminal window with echo-server Zephyr sample application.
- Terminal #2 is terminal window with echo-client Zephyr sample application.

If you want to capture the transferred network data, you must compile the monitor_15_4 program in net-tools directory.

Open a terminal window and type:

cd $ZEPHYR_BASE/../net-tools
make monitor_15_4

Step 1 - Compile and start echo-server

In terminal #1, type:

west build -b qemu_x86 -d build/server samples/net/sockets/echo_server -- -DOVERLAY_CLASS=overlay-qemu_802154.conf
west build -t server -d build/server

If you want to capture the network traffic between the two QEMUs, type:

west build -b qemu_x86 -d build/server samples/net/sockets/echo_server -- -G 'UnixMakefiles' -DOVERLAY_CONFIG=overlay-qemu_802154.conf -DPCAP=.capture.pcap
west build -t server -d build/server

Note that the make must be used for server target if packet capture option is set in command line. The build/server/capture.pcap file will contain the transferred data.
Step 2 - Compile and start echo-client  
In terminal #2, type:

```
w west build -b qemu_x86 -d build/client samples/net/sockets/echo_client -- -DOVERLAY_→CONFIG=overlay-qemu_802154.conf
west build -t client -d build/client
```

You should see data passed between the two QEMUs. Exit QEMU by pressing CTRL+A x.

While developing networking software, it is usually necessary to connect and exchange data with the host system like a Linux desktop computer. Depending on what board is used for development, the following options are possible:

- **QEMU using SLIP (Serial Line Internet Protocol).**
  - Here IP packets are exchanged between Zephyr and the host system via serial port. This is the legacy way of transferring data. It is also quite slow so use it only when necessary. See Networking with QEMU for details.

- **QEMU using built-in Ethernet driver.**
  - Here IP packets are exchanged between Zephyr and the host system via QEMU's built-in Ethernet driver. Not all QEMU boards support built-in Ethernet so in some cases, you might need to use the SLIP method for host connectivity. See Networking with QEMU Ethernet for details.

- **QEMU using SLIRP (Qemu User Networking).**
  - QEMU User Networking is implemented using “slirp”, which provides a full TCP/IP stack within QEMU and uses that stack to implement a virtual NAT’d network. As this support is built into QEMU, it can be used with any model and requires no admin privileges on the host machine, unlike TAP. However, it has several limitations including performance which makes it less valuable for practical purposes. See Networking with QEMU User for details.

- **native_posix board.**
  - The Zephyr instance can be executed as a user space process in the host system. This is the most convenient way to debug the Zephyr system as one can attach host debugger directly to the running Zephyr instance. This requires that there is an adaptation driver in Zephyr for interfacing with the host system. An Ethernet driver exists in Zephyr for this purpose. See Networking with native_posix board for details.

- **USB device networking.**
  - Here, the Zephyr instance is run on a real board and the connectivity to the host system is done via USB. See USB Device Networking for details.

- **Connecting multiple Zephyr instances together.**
  - If you have multiple Zephyr instances, either QEMU or native_posix ones, and want to create a connection between them, see Networking with multiple Zephyr instances for details.

- **Simulating IEEE 802.15.4 network between two QEMUs.**
  - Here, two Zephyr instances are running and there is IEEE 802.15.4 link layer run over an UART between them. See Networking with QEMU and IEEE 802.15.4 for details.

### 6.2.5 Monitor Network Traffic

- **Host Configuration**
- **Zephyr Configuration**
- **Wireshark Configuration**
It is useful to be able to monitor the network traffic especially when debugging a connectivity issues or when developing new protocol support in Zephyr. This page describes how to set up a way to capture network traffic so that user is able to use Wireshark or similar tool in remote host to see the network packets sent or received by a Zephyr device.

See also the net-capture-sample sample application from the Zephyr source distribution for configuration options that need to be enabled.

Host Configuration

The instructions here describe how to setup a Linux host to capture Zephyr network RX and TX traffic. Similar instructions should work also in other operating systems. On the Linux Host, fetch the Zephyr net-tools project, which is located in a separate Git repository:

```
git clone https://github.com/zephyrproject-rtos/net-tools
```

The net-tools project provides a configure file to setup IP-to-IP tunnel interface so that we can transfer monitoring data from Zephyr to host.

In terminal #1, type:

```
./net-setup.sh -c zeth-tunnel.conf
```

This script will create following IPIP tunnel interfaces:

<table>
<thead>
<tr>
<th>Interface name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>zeth-ip6ip</td>
<td>IPv6-over-I Pv4 tunnel</td>
</tr>
<tr>
<td>zeth-ipip</td>
<td>IPv4-over-I Pv4 tunnel</td>
</tr>
<tr>
<td>zeth-ipip6</td>
<td>IPv4-over-I Pv6 tunnel</td>
</tr>
<tr>
<td>zeth-ip6ip6</td>
<td>IPv6-over-I Pv6 tunnel</td>
</tr>
</tbody>
</table>

Zephyr will send captured network packets to one of these interfaces. The actual interface will depend on how the capturing is configured. You can then use Wireshark to monitor the proper network interface.

After the tunneling interfaces have been created, you can use for example net-capture.py script from net-tools project to print or save the captured network packets. The net-capture.py provides an UDP listener, it can print the captured data to screen and optionally can also save the data to a pcap file.

```
$ ./net-capture.py -i zeth-ip6ip -w capture.pcap
```

The net-capture.py has following command line options:

```
Listen captured network data from Zephyr and save it optionally to pcap file.
./net-capture.py
   -i | --interface <network interface>
```

(continues on next page)
Listen this interface for the data

```
[-p | --port <UDP port>]
  UDP port (default is 4242) where the capture data is received
[-q | --quiet]
  Do not print packet information
[-t | --type <L2 type of the data>]
  Scapy L2 type name of the UDP payload, default is Ether
[-w | --write <pcap file name>]
  Write the received data to file in PCAP format
```

Instead of the net-capture.py script, you can for example use netcat to provide an UDP listener so that the host will not send port unreachable message to Zephyr:

```
nc -l -u 2001:db8:200::2 4242 > /dev/null
```

The IP address above is the inner tunnel endpoint, and can be changed and it depends on how the Zephyr is configured. Zephyr will send UDP packets containing the captured network packets to the configured IP tunnel, so we need to terminate the network connection like this.

**Zephyr Configuration**

In this example, we use native_posix board. You can also use any other board that supports networking.

In terminal #3, type:

```
west build -b native_posix samples/net/capture -- -DCONFIG_NATIVE_UART_AUTOATTACH_DEFAULT_CMD="gnome-terminal -- screen %s"
```

To see the Zephyr console and shell, start Zephyr instance like this:

```
build/zephyr/zephyr.exe -attach_uart
```

Any other application can be used too, just make sure that suitable configuration options are enabled (see samples/net/capture/prj.conf file for examples).

The network capture can be configured automatically if needed, but currently the capture sample application does not do that. User has to use net-shell to setup and enable the monitoring.

The network packet monitoring needs to be setup first. The net-shell has net capture setup command for doing that. The command syntax is

```
net capture setup <remote-ip-addr> <local-ip-addr> <peer-ip-addr>
  <remote> is the (outer) endpoint IP address
  <local> is the (inner) local IP address
  <peer> is the (inner) peer IP address
Local and Peer IP addresses can have UDP port number in them (optional)
like 198.0.51.2:9000 or [2001:db8:100::2]:4242
```

In Zephyr console, type:

```
net capture setup 192.0.2.2 2001:db8:200::1 2001:db8:200::2
```

This command will create the tunneling interface. The 192.0.2.2 is the remote host where the tunnel is terminated. The address is used to select the local network interface where the tunneling interface is attached to. The 2001:db8:200::1 tells the local IP address for the tunnel, the 2001:db8:200::2 is the peer IP address where the captured network packets are sent. The port numbers for UDP packet can be given in the setup command like this for IPv6-over-IPv4 tunnel.
net capture setup 192.0.2.2 [2001:db8:200::1]:9999 [2001:db8:200::2]:9998

and like this for IPv4-over-IPv4 tunnel

net capture setup 192.0.2.2 198.51.100.1:9999 198.51.100.2:9998

If the port number is omitted, then 4242 UDP port is used as a default.

The current monitoring configuration can be checked like this:

```
uart:~$ net capture
Network packet capture disabled
Capture Tunnel
Device iface iface Local Peer
NET_CAPTURE0 - 1 [2001:db8:200::1]:4242 [2001:db8:200::2]:4242
```

which will print the current configuration. As we have not yet enabled monitoring, the Capture iface
is not set.

Then we need to enable the network packet monitoring like this:

```
net capture enable 2
```

The 2 tells the network interface which traffic we want to capture. In this example, the 2 is the
native_posix board Ethernet interface. Note that we send the network traffic to the same interface
that we are monitoring in this example. The monitoring system avoids to capture already captured net-
work traffic as that would lead to recursion. You can use net iface command to see what network
interfaces are available. Note that you cannot capture traffic from the tunnel interface as that would
cause recursion loop. The captured network traffic can be sent to some other network interface if con-
figured so. Just set the <remote-ip-addr> option properly in net capture setup so that the IP tunnel
is attached to desired network interface. The capture status can be checked again like this:

```
uart:~$ net capture
Network packet capture enabled
Capture Tunnel
Device iface iface Local Peer
NET_CAPTURE0 2 1 [2001:db8:200::1]:4242 [2001:db8:200::2]:4242
```

After enabling the monitoring, the system will send captured (either received or sent) network packets
to the tunnel interface for further processing.

The monitoring can be disabled like this:

```
net capture disable
```

which will turn currently running monitoring off. The monitoring setup can be cleared like this:

```
net capture cleanup
```

It is not necessary to use net-shell for configuring the monitoring. The network capture API functions
can be called by the application if needed.

**Wireshark Configuration**

The Wireshark tool can be used to monitor the captured network traffic in a useful way.

You can monitor either the tunnel interfaces or the zeth interface. In order to see the actual captured
data inside an UDP packet, see Wireshark decapsulate UDP document for instructions.
6.2.6 Networking APIs

Network APIs

BSD Sockets

- **Overview**
- **Secure Sockets**
  - TLS credentials subsystem
  - Secure Socket Creation
  - Secure Sockets options
- **Socket offloading**
  - Offloaded socket creation
  - Dealing with multiple offloaded interfaces
- **API Reference**
  - BSD Sockets
  - TLS Credentials

**Overview** Zephyr offers an implementation of a subset of the BSD Sockets API (a part of the POSIX standard). This API allows to reuse existing programming experience and port existing simple networking applications to Zephyr.

Here are the key requirements and concepts which governed BSD Sockets compatible API implementation for Zephyr:

- Has minimal overhead, similar to the requirement for other Zephyr subsystems.
- Is namespaced by default, to avoid name conflicts with well-known names like `close()`, which may be part of libc or other POSIX compatibility libraries. If enabled by `CONFIG_NET_SOCKETS_POSIX_NAMES`, it will also expose native POSIX names.

BSD Sockets compatible API is enabled using `CONFIG_NET_SOCKETS` config option and implements the following operations: `socket()`, `close()`, `recv()`, `recvfrom()`, `send()`, `sendto()`, `connect()`, `bind()`, `listen()`, `accept()`, `fcntl()` (to set non-blocking mode), `getsockopt()`, `setsockopt()`, `poll()`, `select()`, `getaddrinfo()`, `getnameinfo()`.

Based on the namespacing requirements above, these operations are by default exposed as functions with `zsock_` prefix, e.g. `zsock_socket()` and `zsock_close()`. If the config option `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined, all the functions will be also exposed as aliases without the prefix. This includes the functions like `close()` and `fcntl()` (which may conflict with functions in libc or other libraries, for example, with the filesystem libraries).

Another entailment of the design requirements above is that the Zephyr API aggressively employs the short-read/short-write property of the POSIX API whenever possible (to minimize complexity and overheads). POSIX allows for calls like `recv()` and `send()` to actually process (receive or send) less data than requested by the user (on `SOCK_STREAM` type sockets). For example, a call `recv(sock, 1000, 0)` may return 100, meaning that only 100 bytes were read (short read), and the application needs to retry call(s) to receive the remaining 900 bytes.

Another entailment of the design requirements above is that the Zephyr API aggressively employs the short-read/short-write property of the POSIX API whenever possible (to minimize complexity and overheads). POSIX allows for calls like `recv()` and `send()` to actually process (receive or send) less data than requested by the user (on `SOCK_STREAM` type sockets). For example, a call `recv(sock, 1000, 0)` may return 100, meaning that only 100 bytes were read (short read), and the application needs to retry call(s) to receive the remaining 900 bytes.

The BSD Sockets API uses file descriptors to represent sockets. File descriptors are small integers, consecutively assigned from zero, shared among sockets, files, special devices (like stdin/stdout), etc. Internally, there is a table mapping file descriptors to internal object pointers. The file descriptor table is used by the BSD Sockets API even if the rest of the POSIX subsystem (filesystem, stdin/stdout) is not enabled.
Secure Sockets  Zephyr provides an extension of standard POSIX socket API, allowing to create and configure sockets with TLS protocol types, facilitating secure communication. Secure functions for the implementation are provided by mbedTLS library. Secure sockets implementation allows use of both TLS and DTLS protocols with standard socket calls. See net_ip_protocol_secure type for supported secure protocol versions.

To enable secure sockets, set the CONFIG_NET_SOCKETS_SOCKOPT_TLS option. To enable DTLS support, use CONFIG_NET_SOCKETS_ENABLE_DTLS option.

**TLS credentials subsystem**  TLS credentials must be registered in the system before they can be used with secure sockets. See tls_credential_add() for more information.

When a specific TLS credential is registered in the system, it is assigned with numeric value of type sec_tag_t, called a tag. This value can be used later on to reference the credential during secure socket configuration with socket options.

The following TLS credential types can be registered in the system:

- TLS_CREDENTIAL_CA_CERTIFICATE
- TLS_CREDENTIAL_SERVER_CERTIFICATE
- TLS_CREDENTIAL_PRIVATE_KEY
- TLS_CREDENTIAL_PSK
- TLS_CREDENTIAL_PSK_ID

An example registration of CA certificate (provided in ca_certificate array) looks like this:

```c
ret = tls_credential_add(CA_CERTIFICATE_TAG, TLS_CREDENTIAL_CA_CERTIFICATE,
                        ca_certificate, sizeof(ca_certificate));
```

By default certificates in DER format are supported. PEM support can be enabled in mbedTLS settings.

**Secure Socket Creation**  A secure socket can be created by specifying secure protocol type, for instance:

```c
sock = socket(AF_INET, SOCK_STREAM, IPPROTO_TLS_1_2);
```

Once created, it can be configured with socket options. For instance, the CA certificate and hostname can be set:

```c
sec_tag_t sec_tag_opt[] = {
    CA_CERTIFICATE_TAG,
};
ret = setsockopt(sock, SOL_TLS, TLS_SEC_TAG_LIST,
                 sec_tag_opt, sizeof(sec_tag_opt));

char host[] = "google.com";
ret = setsockopt(sock, SOL_TLS, TLS_HOSTNAME, host, sizeof(host) - 1);
```

Once configured, socket can be used just like a regular TCP socket.

Several samples in Zephyr use secure sockets for communication. For a sample use see e.g. echo-server sample application or HTTP GET sample application.

**Secure Sockets options**  Secure sockets offer the following options for socket management:
Defines

**TLS_SEC_TAG_LIST**
Socket option to select TLS credentials to use. It accepts and returns an array of sec_tag_t that indicate which TLS credentials should be used with specific socket.

**TLS_HOSTNAME**
Write-only socket option to set hostname. It accepts a string containing the hostname (may be NULL to disable hostname verification). By default, hostname check is enforced for TLS clients.

**TLS_CIPHERSUITE_LIST**
Socket option to select ciphersuites to use. It accepts and returns an array of integers with IANA assigned ciphersuite identifiers. If not set, socket will allow all ciphersuites available in the system (mbedTLS default behavior).

**TLS_CIPHERSUITE_USED**
Read-only socket option to read a ciphersuite chosen during TLS handshake. It returns an integer containing an IANA assigned ciphersuite identifier of chosen ciphersuite.

**TLS_PEER_VERIFY**
Write-only socket option to set peer verification level for TLS connection. This option accepts an integer with a peer verification level, compatible with mbedTLS values:

- 0 - none
- 1 - optional
- 2 - required

If not set, socket will use mbedTLS defaults (none for servers, required for clients).

**TLS_DTLS_ROLE**
Write-only socket option to set role for DTLS connection. This option is irrelevant for TLS connections, as for them role is selected based on connect()/listen() usage. By default, DTLS will assume client role. This option accepts an integer with a TLS role, compatible with mbedTLS values:

- 0 - client
- 1 - server

**TLS_ALPN_LIST**
Socket option for setting the supported Application Layer Protocols. It accepts and returns a const char array of NULL terminated strings representing the supported application layer protocols listed during the TLS handshake.

**TLS_DTLS_HANDSHAKE_TIMEOUT_MIN**
Socket option to set DTLS handshake timeout. The timeout starts at min, and upon retransmission the timeout is doubled util max is reached. Min and max arguments are separate options. The time unit is ms.

**TLS_DTLS_HANDSHAKE_TIMEOUT_MAX**
TLS_CERT_NOCOPY
Socket option for preventing certificates from being copied to the mbedTLS heap if possible. The option is only effective for DER certificates and is ignored for PEM certificates.

TLS_NATIVE
TLS socket option to use with offloading. The option instructs the network stack only to offload underlying TCP/UDP communication. The TLS/DTLS operation is handled by a native TLS/DTLS socket implementation from Zephyr.

Note, that this option is only applicable if socket dispatcher is used (CONFIG_NET_SOCKETS_OFFLOAD_DISPATCHER is enabled). In such case, it should be the first socket option set on a newly created socket. After that, the application may use SO_BINDTODEVICE to choose the dedicated network interface for the underlying TCP/UDP socket.

TLS_SESSION_CACHE
Socket option to control TLS session caching on a socket. Accepted values:

- 0 - Disabled.
- 1 - Enabled.

TLS_SESSION_CACHE_PURGE
Write-only socket option to purge session cache immediately. This option accepts any value.

Socket offloading
Zephyr allows to register custom socket implementations (called offloaded sockets). This allows for seamless integration for devices which provide an external IP stack and expose socket-like API.

Socket offloading can be enabled with CONFIG_NET_SOCKETS_OFFLOAD option. A network driver that wants to register a new socket implementation should use NET_SOCKET_OFFLOAD_REGISTER macro. The macro accepts the following parameters:

- socket_name - an arbitrary name for the socket implementation.
- prio - socket implementation priority, the higher priority is, the earlier particular implementation is processed when creating a new socket. Lower numeric value indicate higher priority.
- _family - socket family implemented by the offloaded socket. AF_UNSPEC indicate any family.
- _is_supported - a filtering function, used to verify whether particular socket family, type and protocol are supported by the offloaded socket implementation.
- _handler - a function compatible with socket() API, used to create an offloaded socket.

Every offloaded socket implementation should also implement a set of socket APIs, specified in socket_op_vtable struct.

The function registered for socket creation should allocate a new file descriptor using z_reserve_fd() function. Any additional actions, specific to the creation of a particular offloaded socket implementation should take place after the file descriptor is allocated. As a final step, if the offloaded socket was created successfully, the file descriptor should be finalized with z_finalize_fd() function. The finalize function allows to register a socket_op_vtable structure implementing socket APIs for an offloaded socket along with an optional socket context data pointer.

Finally, when an offloaded network interface is initialized, it should indicate that the interface is offloaded with net_if_socket_offload_set() function. The function registers the function used to
create an offloaded socket (the same as the one provided in NET_SOCKET_OFFLOAD_REGISTER) at the network interface.

**Offloaded socket creation** When application creates a new socket with `socket()` function, the network stack iterates over all registered socket implementations (native and offloaded). Higher priority socket implementations are processed first. For each registered socket implementation, an address family is verified, and if it matches (or the socket was registered as `AF_UNSPEC`), the corresponding `_is_supported` function is called to verify the remaining socket parameters. The first implementation that fulfills the socket requirements (i.e. `_is_supported` returns true) will create a new socket with its `_handler` function.

The above indicates the importance of the socket priority. If multiple socket implementations support the same set of socket family/type/protocol, the first implementation processed by the system will create a socket. Therefore it’s important to give the highest priority to the implementation that should be the system default.

The socket priority for native socket implementation is configured with Kconfig. Use `CONFIG_NET_SOCKETS_TLS_PRIORITY` to set the priority for the native TLS sockets. Use `CONFIG_NET_SOCKETS_PRIORITY_DEFAULT` to set the priority for the remaining native sockets.

**Dealing with multiple offloaded interfaces** As the `socket()` function does not allow to specify which network interface should be used by a socket, it’s not possible to choose a specific implementation in case multiple offloaded socket implementations, supporting the same type of sockets, are available. The same problem arises when both native and offloaded sockets are available in the system.

To address this problem, a special socket implementation (called socket dispatcher) was introduced. The sole reason for this module is to postpone the socket creation for until the first operation on a socket is performed. This leaves an opening to use `SO_BINDTODEVICE` socket option, to bind a socket to a particular network interface (and thus offloaded socket implementation). The socket dispatcher can be enabled with `CONFIG_NET_SOCKETS_OFFLOAD_DISPATCHER` Kconfig option.

When enabled, the application can specify the network interface to use with `setsockopt()` function:

```c
/* A "dispatcher" socket is created */
struct ifreq ifreq = {
    .ifr_name = "SimpleLink"
};

/* The socket is "dispatched" to a particular network interface */
/* (offloaded or not). */
setsockopt(sock, SOL_SOCKET, SO_BINDTODEVICE, &ifreq, sizeof(ifreq));
```

Similarly, if TLS is supported by both native and offloaded sockets, `TLS_NATIVE` socket option can be used to indicate that a native TLS socket should be created. The underlying socket can then be bound to a particular network interface:

```c
/* A "dispatcher" socket is created */
int tls_native = 1;

/* The socket is "dispatched" to a native TLS socket implementation. */
/* The underlying socket is a "dispatcher" socket now. */
setsockopt(sock, SOL_TLS, TLS_NATIVE, &tls_native, sizeof(tls_native));
```

(continues on next page)
struct ifreq ifreq = {
    .ifr_name = "SimpleLink"
};

/* The underlying socket is "dispatched" to a particular network interface
 * (offloaded or not).
 */
setsockopt(sock, SOL_SOCKET, SO_BINDTODEVICE, &ifreq, sizeof(ifreq));

In case no SO_BINDTODEVICE socket option is used on a socket, the socket will be dispatched according to the default priority and filtering rules on a first socket API call.

API Reference

BSD Sockets

group bsd_sockets

BSD Sockets compatible API.

Defines

ZSOCK_POLLIN
    zsock_poll: Poll for readability

ZSOCK_POLLPRI
    zsock_poll: Compatibility value, ignored

ZSOCK_POLLOUT
    zsock_poll: Poll for writability

ZSOCK_POLLERR
    zsock_poll: Poll results in error condition (output value only)

ZSOCK_POLLHUP
    zsock_poll: Poll detected closed connection (output value only)

ZSOCK_POLLNVAL
    zsock_poll: Invalid socket (output value only)

ZSOCK_MSG_PEEK
    zsock_recv: Read data without removing it from socket input queue

ZSOCK_MSG_TRUNC
    zsock_recv: return the real length of the datagram, even when it was longer than the passed buffer

ZSOCK_MSG_DONTWAIT
    zsock_recv/zsock_send: Override operation to non-blocking
ZSOCK_MSG_WAITALL

zsock_recv: block until the full amount of data can be returned

ZSOCK_SHUT_RD

zsock_shutdown: Shut down for reading

ZSOCK_SHUT_WR

zsock_shutdown: Shut down for writing

ZSOCK_SHUT_RDWR

zsock_shutdown: Shut down for both reading and writing

SOL_TLS

Protocol level for TLS. Here, the same socket protocol level for TLS as in Linux was used.

TLS_PEER_VERIFY_NONE

Peer verification disabled.

TLS_PEER_VERIFY_OPTIONAL

Peer verification optional.

TLS_PEER_VERIFY_REQUIRED

Peer verification required.

TLS_DTLS_ROLE_CLIENT

Client role in a DTLS session.

TLS_DTLS_ROLE_SERVER

Server role in a DTLS session.

TLS_CERT_NOCOPY_NONE

Cert duplicated in heap

TLS_CERT_NOCOPY_OPTIONAL

Cert not copied in heap if DER

TLS_SESSION_CACHE_DISABLED

Disable TLS session caching.

TLS_SESSION_CACHE_ENABLED

Enable TLS session caching.

AI_PASSIVE

Address for bind() (vs for connect())

AI_CANONNAME

Fill in ai_canonname
AI_NUMERICHOST
Assume host address is in numeric notation, don’t DNS lookup

AI_V4MAPPED
May return IPv4 mapped address for IPv6

AI_ALL
May return both native IPv6 and mapped IPv4 address for IPv6

AI_ADDRCONFIG
IPv4/IPv6 support depends on local system config

AI_NUMERICSERV
Assume service (port) is numeric

NI_NUMERICHOST
zsock_getnameinfo(): Resolve to numeric address.

NI_NUMERICSERV
zsock_getnameinfo(): Resolve to numeric port number.

NI_NOFQDN
zsock_getnameinfo(): Return only hostname instead of FQDN

NI_NAMEREQD
zsock_getnameinfo(): Dummy option for compatibility

NI_DGRAM
zsock_getnameinfo(): Dummy option for compatibility

NI_MAXHOST
zsock_getnameinfo(): Max supported hostname length

c_pollfd

c_fcntl

addrlen

POLLIN
POSIX wrapper for ZSOCK_POLLIN

POLLOUT
POSIX wrapper for ZSOCK_POLLOUT

POLLERR
POSIX wrapper for ZSOCK_POLLERR
POLLHUP
    POSIX wrapper for ZSOCK_POLLHUP

POLLNVAL
    POSIX wrapper for ZSOCK_POLLNVAL

MSG_PEEK
    POSIX wrapper for ZSOCK_MSG_PEEK

MSG_TRUNC
    POSIX wrapper for ZSOCK_MSG_TRUNC

MSG_DONTWAIT
    POSIX wrapper for ZSOCK_MSG_DONTWAIT

MSG_WAITALL
    POSIX wrapper for ZSOCK_MSG_WAITALL

SHUT_RD
    POSIX wrapper for ZSOCK_SHUT_RD

SHUT_WR
    POSIX wrapper for ZSOCK_SHUT_WR

SHUT_RDWR
    POSIX wrapper for ZSOCK_SHUT_RDWR

EAI_BADFLAGS
    POSIX wrapper for DNS_EAI_BADFLAGS

EAI_NONAME
    POSIX wrapper for DNS_EAI_NONAME

EAI_AGAIN
    POSIX wrapper for DNS_EAI_AGAIN

EAI_FAIL
    POSIX wrapper for DNS_EAI_FAIL

EAI_NODATA
    POSIX wrapper for DNS_EAI_NODATA

EAI_MEMORY
    POSIX wrapper for DNS_EAI_MEMORY

EAI_SYSTEM
    POSIX wrapper for DNS_EAI_SYSTEM
EAI_SERVICE
   POSIX wrapper for DNS_EAI_SERVICE

EAI_SOCKTYPE
   POSIX wrapper for DNS_EAI_SOCKTYPE

EAI_FAMILY
   POSIX wrapper for DNS_EAI_FAMILY

IFNAMSIZ

SOCKET
   sockopt: Socket-level option

SO_DEBUG
   sockopt: Recording debugging information (ignored, for compatibility)

SO_REUSEADDR
   sockopt: address reuse (ignored, for compatibility)

SO_TYPE
   sockopt: Type of the socket

SO_ERROR
   sockopt: Async error (ignored, for compatibility)

SO_DONTROUTE
   sockopt: Bypass normal routing and send directly to host (ignored, for compatibility)

SO_BROADCAST
   sockopt: Transmission of broadcast messages is supported (ignored, for compatibility)

SO_SNDBUF
   sockopt: Size of socket socket send buffer (ignored, for compatibility)

SO_RCVBUF
   sockopt: Size of socket recv buffer

SO_KEEPALIVE
   sockopt: Enable sending keep-alive messages on connections (ignored, for compatibility)

SO_OOBINLINE
   sockopt: Place out-of-band data into receive stream (ignored, for compatibility)

SO_REUSEPORT
   sockopt: Allow multiple sockets to reuse a single port (ignored, for compatibility)

SO_RCVTIMEO
   sockopt: Receive timeout Applies to receive functions like recv(), but not to connect()
SO_SNDTIMEO
sockopt: Send timeout

SO_BINDTODEVICE
sockopt: Bind a socket to an interface

SO_ACCEPTCONN
sockopt: Socket accepts incoming connections (ignored, for compatibility)

SO_TIMESTAMPING
sockopt: Timestamp TX packets

SO_PROTOCOL
sockopt: Protocol used with the socket

SO_DOMAIN
sockopt: Domain used with SOCKET (ignored, for compatibility)

TCP_NODELAY
End Socket options for SOL_SOCKET level sockopt: Disable TCP buffering (ignored, for compatibility)

IP_TOS
sockopt: Set or receive the Type-Of-Service value for an outgoing packet.

IPV6_V6ONLY
sockopt: Don't support IPv4 access (ignored, for compatibility)

IPV6_TCLASS
sockopt: Set or receive the traffic class value for an outgoing packet.

SO_PRIORITY
sockopt: Socket priority

SO_TXTIME
sockopt: Socket TX time (when the data should be sent)

SCM_TXTIME

SO_SOCKS5
sockopt: Enable SOCKS5 for Socket

ZSOCK_FD_SETSIZE
Number of file descriptors which can be added to zsock_fd_set

fd_set

FD_SETSIZE
zsock_timeval

## Typedefs

typedef struct zsock_fd_set zsock_fd_set

## Functions

void *zsock_get_context_object(int sock)

Obtain a file descriptor's associated net context.

With CONFIG_USERSPACE enabled, the kernel's object permission system must apply to
socket file descriptors. When a socket is opened, by default only the caller has permission,
access by other threads will fail unless they have been specifically granted permission.

This is achieved by tagging data structure definitions that implement the underlying object
associated with a network socket file descriptor with '__net_socket'. All pointers to instances
of these will be known to the kernel as kernel objects with type K_OBJ_NET_SOCKET.

This API is intended for threads that need to grant access to the object associated with a
particular file descriptor to another thread. The returned pointer represents the underlying
K_OBJ_NET_SOCKET and may be passed to APIs like k_object_access_grant().

In a system like Linux which has the notion of threads running in processes in a shared vir-
tual address space, this sort of management is unnecessary as the scope of file descriptors is
implemented at the process level.

However in Zephyr the file descriptor scope is global, and MPU-based systems are not able to
implement a process-like model due to the lack of memory virtualization hardware. They use
discrete object permissions and memory domains instead to define thread access scope.

User threads will have no direct access to the returned object and will fault if they try to access
its memory; the pointer can only be used to make permission assignment calls, which follow
exactly the rules for other kernel objects like device drivers and IPC.

**Parameters**

- sock – file descriptor

**Returns**

pointer to associated network socket object, or NULL if the file descriptor wasn't
valid or the caller had no access permission

int zsock_socket(int family, int type, int proto)

Create a network socket.

See POSIX.1-2017 article for normative description. This function is also exposed as socket() if
CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

If CONFIG_USERSPACE is enabled, the caller will be granted access to the context object
associated with the returned file descriptor.

**See also:**

zsock_get_context_object()

int zsock_socketpair(int family, int type, int proto, int *sv)

Create an unnamed pair of connected sockets.
See POSIX.1-2017 article for normative description. This function is also exposed as `socketpair()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
int zsock_close(int sock)
```

Close a network socket.

Close a network socket. This function is also exposed as `close()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined (in which case it may conflict with generic POSIX `close()` function).

```c
int zsock_shutdown(int sock, int how)
```

Shutdown socket send/receive operations.

See POSIX.1-2017 article for normative description, but currently this function has no effect in Zephyr and provided solely for compatibility with existing code. This function is also exposed as `shutdown()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
int zsock_bind(int sock, const struct sockaddr *addr, socklen_t addrlen)
```

Bind a socket to a local network address.

See POSIX.1-2017 article for normative description. This function is also exposed as `bind()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
int zsock_connect(int sock, const struct sockaddr *addr, socklen_t addrlen)
```

Connect a socket to a peer network address.

See POSIX.1-2017 article for normative description. This function is also exposed as `connect()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
int zsock_listen(int sock, int backlog)
```

Set up a STREAM socket to accept peer connections.

See POSIX.1-2017 article for normative description. This function is also exposed as `listen()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
int zsock_accept(int sock, struct sockaddr *addr, socklen_t *addrlen)
```

Accept a connection on listening socket.

See POSIX.1-2017 article for normative description. This function is also exposed as `accept()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
ssize_t zsock_sendto(int sock, const void *buf, size_t len, int flags, const struct sockaddr *dest_addr, socklen_t addrlen)
```

Send data to an arbitrary network address.

See POSIX.1-2017 article for normative description. This function is also exposed as `sendto()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.

```c
static inline ssize_t zsock_send(int sock, const void *buf, size_t len, int flags)
```

Send data to a connected peer.

See POSIX.1-2017 article for normative description. This function is also exposed as `send()` if `CONFIG_NET_SOCKETS_POSIX_NAMES` is defined.
ssize_t zsock_sendmsg(int sock, const struct msghdr *msg, int flags)
    Send data to an arbitrary network address.

See POSIX.1-2017 article for normative description. This function is also exposed as sendmsg() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

ssize_t zsock_recvfrom(int sock, void *buf, size_t max_len, int flags, struct sockaddr *src_addr, socklen_t *addrlen)
    Receive data from an arbitrary network address.

See POSIX.1-2017 article for normative description. This function is also exposed as recvfrom() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline ssize_t zsock_recv(int sock, void *buf, size_t max_len, int flags)
    Receive data from a connected peer.

See POSIX.1-2017 article for normative description. This function is also exposed as recv() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_fcntl(int sock, int cmd, int flags)
    Control blocking/non-blocking mode of a socket.

This functions allow to (only) configure a socket for blocking or non-blocking operation (O_NONBLOCK). This function is also exposed as fcntl() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX fcntl() function).

int zsock_poll(struct zsock_pollfd *fds, int nfds, int timeout)
    Efficiently poll multiple sockets for events.

See POSIX.1-2017 article for normative description. (In Zephyr this function works only with sockets, not arbitrary file descriptors.) This function is also exposed as poll() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX poll() function).

int zsock_getsockopt(int sock, int level, int optname, void *optval, socklen_t *optlen)
    Get various socket options.

See POSIX.1-2017 article for normative description. In Zephyr this function supports a subset of socket options described by POSIX, but also some additional options available in Linux (some options are dummy and provided to ease porting of existing code). This function is also exposed as getsockopt() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_setsockopt(int sock, int level, int optname, const void *optval, socklen_t optlen)
    Set various socket options.

See POSIX.1-2017 article for normative description. In Zephyr this function supports a subset of socket options described by POSIX, but also some additional options available in Linux (some options are dummy and provided to ease porting of existing code). This function is also exposed as setsockopt() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.
int zsock_getpeername(int sock, struct sockaddr *addr, socklen_t *addrlen)
    Get peer name.

See POSIX.1-2017 article for normative description. This function is also exposed as
getpeername() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_getsockname(int sock, struct sockaddr *addr, socklen_t *addrlen)
    Get socket name.

See POSIX.1-2017 article for normative description. This function is also exposed as
getsockname() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_gethostname(char *buf, size_t len)
    Get local host name.

See POSIX.1-2017 article for normative description. This function is also exposed as
gethostname() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline char *zsock_inet_ntop(sa_family_t family, const void *src, char *dst, size_t size)
    Convert network address from internal to numeric ASCII form.

See POSIX.1-2017 article for normative description. This function is also exposed as
inet_ntop() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_inet_pton(sa_family_t family, const char *src, void *dst)
    Convert network address from numeric ASCII form to internal representation.

See POSIX.1-2017 article for normative description. This function is also exposed as
inet_pton() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int zsock_getaddrinfo(const char *host, const char *service, const struct zsock_addrinfo *hints,
                      struct zsock_addrinfo **res)
    Resolve a domain name to one or more network addresses.

See POSIX.1-2017 article for normative description. This function is also exposed as
getaddrinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

void zsock_freeaddrinfo(struct zsock_addrinfo *ai)
    Free results returned by zsock_getaddrinfo()

See POSIX.1-2017 article for normative description. This function is also exposed as
freeaddrinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

const char *zsock_gai_strerror(int errcode)
    Convert zsock_getaddrinfo() error code to textual message.

See POSIX.1-2017 article for normative description. This function is also exposed as
gai_strerror() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.
int zsock_getnameinfo(const struct sockaddr *addr, socklen_t addrlen, char *host, socklen_t hostlen, char *serv, socklen_t servlen, int flags)

Resolve a network address to a domain name or ASCII address.

See POSIX.1-2017 article for normative description. This function is also exposed as getnameinfo() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline int socket(int family, int type, int proto)
 POSIX wrapper for zsock_socket

static inline int socketpair(int family, int type, int proto, int sv[2])
 POSIX wrapper for zsock_socketpair

static inline int close(int sock)
 POSIX wrapper for zsock_close

static inline int shutdown(int sock, int how)
 POSIX wrapper for zsock_shutdown

static inline int bind(int sock, const struct sockaddr *addr, socklen_t addrlen)
 POSIX wrapper for zsock_bind

static inline int connect(int sock, const struct sockaddr *addr, socklen_t addrlen)
 POSIX wrapper for zsock_connect

static inline int listen(int sock, int backlog)
 POSIX wrapper for zsock_listen

static inline int accept(int sock, struct sockaddr *addr, socklen_t *addrlen)
 POSIX wrapper for zsock_accept

static inline ssize_t send(int sock, const void *buf, size_t len, int flags)
 POSIX wrapper for zsock_send

static inline ssize_t recv(int sock, void *buf, size_t max_len, int flags)
 POSIX wrapper for zsock_recv

static inline int zsock_fcntl_wrapper(int sock, int cmd, ...)

static inline ssize_t sendto(int sock, const void *buf, size_t len, int flags, const struct sockaddr *dest_addr, socklen_t addrlen)
 POSIX wrapper for zsock_sendto

static inline ssize_t sendmsg(int sock, const struct msghdr *message, int flags)
 POSIX wrapper for zsock_sendmsg

static inline ssize_t recvfrom(int sock, void *buf, size_t max_len, int flags, struct sockaddr *src_addr, socklen_t *addrlen)
 POSIX wrapper for zsock_recvfrom

static inline int poll(struct zsock_pollfd *fds, int nfds, int timeout)
 POSIX wrapper for zsock_poll

static inline int getsockopt(int sock, int level, int optname, void *optval, socklen_t *optlen)
 POSIX wrapper for zsock_getsockopt

static inline int setsockopt(int sock, int level, int optname, const void *optval, socklen_t optlen)
 POSIX wrapper for zsock_setsockopt

static inline int getpeername(int sock, struct sockaddr *addr, socklen_t *addrlen)
 POSIX wrapper for zsock_getpeername
static inline int getsockname(int sock, struct sockaddr *addr, socklen_t *addrlen)
    POSIX wrapper for zsock_getsockname

static inline int getaddrinfo(const char *host, const char *service, const struct zsock_addrinfo *hints, struct zsock_addrinfo **res)
    POSIX wrapper for zsock_getaddrinfo

static inline void freeaddrinfo(struct zsock_addrinfo *ai)
    POSIX wrapper for zsock_freeaddrinfo

static inline const char *gai_strerror(int errcode)
    POSIX wrapper for zsock_gai_strerror

static inline int getnameinfo(const struct sockaddr *addr, socklen_t addrlen, char *host, socklen_t hostlen, char *serv, socklen_t servlen, int flags)
    POSIX wrapper for zsock_getnameinfo

static inline const char *gethostname(char *buf, size_t len)
    POSIX wrapper for zsock_gethostname

static inline int inet_pton(sa_family_t family, const char *src, void *dst)
    POSIX wrapper for zsock_inet_pton

static inline char *inet_ntop(sa_family_t family, const void *src, char *dst, size_t size)
    POSIX wrapper for zsock_inet_ntop

int zsock_select(int nfds, zsock_fd_set *readfds, zsock_fd_set *writefds, zsock_fd_set *exceptfds, struct zsock_timeval *timeout)
    Legacy function to poll multiple sockets for events.

See POSIX.1-2017 article for normative description. This function is provided to ease porting of existing code and not recommended for usage due to its inefficiency, use zsock_poll() instead. In Zephyr this function works only with sockets, not arbitrary file descriptors. This function is also exposed as select() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined (in which case it may conflict with generic POSIX select() function).

void ZSOCK_FD_ZERO(zsock_fd_set *set)
    Initialize (clear) fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_ZERO() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

int ZSOCK_FD_ISSET(int fd, zsock_fd_set *set)
    Check whether socket is a member of fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_ISSET() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

void ZSOCK_FD_CLR(int fd, zsock_fd_set *set)
    Remove socket from fd_set.

See POSIX.1-2017 article for normative description. This function is also exposed as FD_CLR() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.
void ZSOCK_FD_SET(int fd, zsock_fd_set *set)
       Add socket to fd_set.

       See POSIX.1-2017 article for normative description. This function is also exposed as FD_SET() if CONFIG_NET_SOCKETS_POSIX_NAMES is defined.

static inline int select(int nfds, zsock_fd_set *readfds, zsock_fd_set *writefds, zsock_fd_set *exceptfds, struct timeval *timeout)

static inline void FD_ZERO(zsock_fd_set *set)

static inline int FD_ISSET(int fd, zsock_fd_set *set)

static inline void FD_CLR(int fd, zsock_fd_set *set)

static inline void FD_SET(int fd, zsock_fd_set *set)

struct zsock_pollfd
       #include <socket.h>

struct zsock_addrinfo
       #include <socket.h>

struct ifreq
       #include <socket.h> Interface description structure

struct zsock_fd_set
       #include <socket_select.h>

TLS Credentials

group tls_credentials
       TLS credentials management.

Typedefs

typedef int sec_tag_t
       Secure tag, a reference to TLS credential
       Secure tag can be used to reference credential after it was registered in the system.

Note: Some TLS credentials come in pairs:

• TLS_CREDENTIAL_SERVER_CERTIFICATE with TLS_CREDENTIAL_PRIVATE_KEY,
• TLS_CREDENTIAL_PSK with TLS_CREDENTIAL_PSK_ID. Such pairs of credentials must be assigned the same secure tag to be correctly handled in the system.
enum tls_credential_type
    TLS credential types

Values:

enumerator TLS_CREDENTIAL_NONE
    Unspecified credential.

enumerator TLS_CREDENTIAL_CA_CERTIFICATE
    A trusted CA certificate. Use this to authenticate remote servers. Used with certificate-based ciphersuites.

enumerator TLS_CREDENTIAL_SERVER_CERTIFICATE
    A public server certificate. Use this to register your own server certificate. Should be registered together with a corresponding private key. Used with certificate-based ciphersuites.

enumerator TLS_CREDENTIAL_PRIVATE_KEY
    Private key. Should be registered together with a corresponding public certificate. Used with certificate-based ciphersuites.

enumerator TLS_CREDENTIAL_PSK
    Pre-shared key. Should be registered together with a corresponding PSK identity. Used with PSK-based ciphersuites.

enumerator TLS_CREDENTIAL_PSK_ID
    Pre-shared key identity. Should be registered together with a corresponding PSK. Used with PSK-based ciphersuites.

Functions

int tls_credential_add(sec_tag_t tag, enum tls_credential_type type, const void *cred, size_t credlen)

Add a TLS credential.
This function adds a TLS credential, that can be used by TLS/DTLS for authentication.

Parameters

• tag – A security tag that credential will be referenced with.
• type – A TLS/DTLS credential type.
• cred – A TLS/DTLS credential.
• credlen – A TLS/DTLS credential length.

Return values

• 0 – TLS credential successfully added.
• -EACCES – Access to the TLS credential subsystem was denied.
• -ENOMEM – Not enough memory to add new TLS credential.
• -EEXIST – TLS credential of specific tag and type already exists.
int tls_credential_get (sec_tag_t tag, enum tls_credential_type type, void *cred, size_t *credlen)
Get a TLS credential.

This function gets an already registered TLS credential, referenced by tag secure tag of type.

Parameters
• tag – A security tag of requested credential.
• type – A TLS/DTLS credential type of requested credential.
• cred – A buffer for TLS/DTLS credential.
• credlen – A buffer size on input. TLS/DTLS credential length on output.

Return values
• 0 – TLS credential successfully obtained.
• -EACCES – Access to the TLS credential subsystem was denied.
• -ENOENT – Requested TLS credential was not found.
• -EFBIG – Requested TLS credential does not fit in the buffer provided.

int tls_credential_delete (sec_tag_t tag, enum tls_credential_type type)
Delete a TLS credential.

This function removes a TLS credential, referenced by tag secure tag of type.

Parameters
• tag – A security tag corresponding to removed credential.
• type – A TLS/DTLS credential type of removed credential.

Return values
• 0 – TLS credential successfully deleted.
• -EACCES – Access to the TLS credential subsystem was denied.
• -ENOENT – Requested TLS credential was not found.

IPv4/IPv6 Primitives and Helpers

Overview Miscellaneous defines and helper functions for IP addresses and IP protocols.

API Reference

group ip_4_6
IPv4/IPv6 primitives and helpers.

Defines

PF_UNSPEC
Unspecified protocol family.
PF_INET
   IP protocol family version 4.

PF_INET6
   IP protocol family version 6.

PF_PACKET
   Packet family.

PF_CAN
   Controller Area Network.

PF_NET_MGMT
   Network management info.

PF_LOCAL
   Inter-process communication.

PF_UNIX
   Inter-process communication.

AF_UNSPEC
   Unspecified address family.

AF_INET
   IP protocol family version 4.

AF_INET6
   IP protocol family version 6.

AF_PACKET
   Packet family.

AF_CAN
   Controller Area Network.

AF_NET_MGMT
   Network management info.

AF_LOCAL
   Inter-process communication.

AF_UNIX
   Inter-process communication.

ntohs(x)
   Convert 16-bit value from network to host byte order.

Parameters
   • x – The network byte order value to convert.
Returns
Host byte order value.

\texttt{ntohl}(x)
Convert 32-bit value from network to host byte order.

\textbf{Parameters}
\begin{itemize}
\item $x$ – The network byte order value to convert.
\end{itemize}

\textbf{Returns}
Host byte order value.

\texttt{ntohl(l)}(x)
Convert 64-bit value from network to host byte order.

\textbf{Parameters}
\begin{itemize}
\item $x$ – The network byte order value to convert.
\end{itemize}

\textbf{Returns}
Host byte order value.

\texttt{htons}(x)
Convert 16-bit value from host to network byte order.

\textbf{Parameters}
\begin{itemize}
\item $x$ – The host byte order value to convert.
\end{itemize}

\textbf{Returns}
Network byte order value.

\texttt{htonl}(x)
Convert 32-bit value from host to network byte order.

\textbf{Parameters}
\begin{itemize}
\item $x$ – The host byte order value to convert.
\end{itemize}

\textbf{Returns}
Network byte order value.

\texttt{htonl}(l)(x)
Convert 64-bit value from host to network byte order.

\textbf{Parameters}
\begin{itemize}
\item $x$ – The host byte order value to convert.
\end{itemize}

\textbf{Returns}
Network byte order value.

\texttt{NET_IPV6_ADDR\_SIZE}

\texttt{NET_IPV4\_ADDR\_SIZE}

\texttt{ALIGN\_H}(x)

\texttt{ALIGN\_D}(x)

\texttt{CMSG\_FIRSTHDR}(msghdr)

\texttt{CMSG\_NXTHDR}(msghdr, cmsg)

\texttt{CMSG\_DATA}(cmsg)

6.2. Networking
CMG_SPACE(length)
CMG_LEN(length)

INET_ADDRSTRLEN
Max length of the IPv4 address as a string. Defined by POSIX.

INET6_ADDRSTRLEN
Max length of the IPv6 address as a string. Takes into account possible mapped IPv4 addresses.

NET_MAX_PRIORITIES

net_ipaddr_copy(dest, src)
Copy an IPv4 or IPv6 address.

Parameters
• dest – Destination IP address.
• src – Source IP address.

Returns
Destination address.

Typedefs

typedef unsigned short int sa_family_t
Socket address family type

typedef size_t socklen_t
Length of a socket address

Enums

enum net_ip_protocol
Protocol numbers from IANA/BSD
Values:

enumerator IPPROTO_IP = 0
IP protocol (pseudo-val for setsockopt())

enumerator IPPROTO_ICMP = 1
ICMP protocol

enumerator IPPROTO_IGMP = 2
IGMP protocol

enumerator IPPROTO_IPIP = 4
IPIP tunnels
enumerator IPPROTO_TCP = 6
TCP protocol

enumerator IPPROTO_UDP = 17
UDP protocol

enumerator IPPROTO_IPV6 = 41
IPv6 protocol

enumerator IPPROTO_ICMPV6 = 58
ICMPv6 protocol

enumerator IPPROTO_RAW = 255
RAW IP packets

enum net_ip_protocol_secure
Protocol numbers for TLS protocols

Values:

enumerator IPPROTO_TLS_1_0 = 256
TLS 1.0 protocol

enumerator IPPROTO_TLS_1_1 = 257
TLS 1.1 protocol

enumerator IPPROTO_TLS_1_2 = 258
TLS 1.2 protocol

enumerator IPPROTO_DTLS_1_0 = 272
DTLS 1.0 protocol

enumerator IPPROTO_DTLS_1_2 = 273
DTLS 1.2 protocol

enum net_sock_type
Socket type

Values:

enumerator SOCK_STREAM = 1
Stream socket type

enumerator SOCK_DGRAM
Datagram socket type

enumerator SOCK_RAW
RAW socket type
enum net_ip_mtu

Values:

enumerator NET_IPV6_MTU = 1280
IPv6 MTU length. We must be able to receive this size IPv6 packet without fragmentation.

enumerator NET_IPV4_MTU = 576
IPv4 MTU length. We must be able to receive this size IPv4 packet without fragmentation.

enum net_priority

Network packet priority settings described in IEEE 802.1Q Annex I.1

Values:

enumerator NET_PRIORITY_BK = 1
Background (lowest)

enumerator NET_PRIORITY_BE = 0
Best effort (default)

enumerator NET_PRIORITY_EE = 2
Excellent effort

enumerator NET_PRIORITY_CA = 3
Critical applications (highest)

enumerator NET_PRIORITY_VI = 4
Video, < 100 ms latency and jitter

enumerator NET_PRIORITY_VO = 5
Voice, < 10 ms latency and jitter

enumerator NET_PRIORITY_IC = 6
Internetwork control

enumerator NET_PRIORITY_NC = 7
Network control

enum net_addr_state

What is the current state of the network address

Values:

enumerator NET_ADDR_ANY_STATE = -1
Default (invalid) address type

enumerator NET_ADDR_TENTATIVE = 0
Tentative address
enumerator NET_ADDR_PREFERRED
    Preferred address

enumerator NET_ADDR_DEPRECATED
    Deprecated address

def enum net_addr_type
    How the network address is assigned to network interface
    Values:

    enumerator NET_ADDR_ANY = 0
        Default value. This is not a valid value.

    enumerator NET_ADDR_AUTOCONF
        Auto configured address

    enumerator NET_ADDR_DHCP
        Address is from DHCP

    enumerator NET_ADDR_MANUAL
        Manually set address

    enumerator NET_ADDR_OVERRIDABLE
        Manually set address which is overridable by DHCP

Functions

static inline bool net_ipv6_is_addr_loopback(struct in6_addr *addr)
    Check if the IPv6 address is a loopback address (::1).

    Parameters
    • addr – IPv6 address

    Returns
    True if address is a loopback address, False otherwise.

static inline bool net_ipv6_is_addr_mcast(const struct in6_addr *addr)
    Check if the IPv6 address is a multicast address.

    Parameters
    • addr – IPv6 address

    Returns
    True if address is a multicast address, False otherwise.

struct net_if *net_if_ipv6_addr_lookup(const struct in6_addr *addr, struct net_if **iface)

static inline bool net_ipv6_is_my_addr(struct in6_addr *addr)
    Check if IPv6 address is found in one of the network interfaces.

    Parameters
    • addr – IPv6 address
Returns
True if address was found, False otherwise.

struct net_if_mcast_addr *net_if_ipv6_maddr_lookup(const struct in6_addr *addr, struct net_if **iface)

static inline bool net_ipv6_is_my_maddr(struct in6_addr *maddr)
Check if IPv6 multicast address is found in one of the network interfaces.
Parameters
• maddr – Multicast IPv6 address

Returns
True if address was found, False otherwise.

static inline bool net_ipv6_is_prefix(const uint8_t *addr1, const uint8_t *addr2, uint8_t length)
Check if two IPv6 addresses are same when compared after prefix mask.
Parameters
• addr1 – First IPv6 address.
• addr2 – Second IPv6 address.
• length – Prefix length (max length is 128).

Returns
True if IPv6 prefixes are the same, False otherwise.

static inline bool net_ipv4_is_addr_loopback(struct in_addr *addr)
Check if the IPv4 address is a loopback address (127.0.0.0/8).
Parameters
• addr – IPv4 address

Returns
True if address is a loopback address, False otherwise.

static inline bool net_ipv4_is_addr_unspecified(const struct in_addr *addr)
Check if the IPv4 address is unspecified (all bits zero)
Parameters
• addr – IPv4 address.

Returns
True if the address is unspecified, false otherwise.

static inline bool net_ipv4_is_addr_mcast(const struct in_addr *addr)
Check if the IPv4 address is a multicast address.
Parameters
• addr – IPv4 address

Returns
True if address is multicast address, False otherwise.

static inline bool net_ipv4_is_ll_addr(const struct in_addr *addr)
Check if the given IPv4 address is a link local address.
Parameters
• addr – A valid pointer on an IPv4 address

Returns
True if it is, false otherwise.
static inline void net_ipv4_addr_copy_raw(uint8_t *dest, const uint8_t *src)
Copy an IPv4 address raw buffer.

Parameters
• dest – Destination IP address.
• src – Source IP address.

static inline void net_ipv6_addr_copy_raw(uint8_t *dest, const uint8_t *src)
Copy an IPv6 address raw buffer.

Parameters
• dest – Destination IP address.
• src – Source IP address.

static inline bool net_ipv4_addr_cmp(const struct in_addr *addr1, const struct in_addr *addr2)
Compare two IPv4 addresses.

Parameters
• addr1 – Pointer to IPv4 address.
• addr2 – Pointer to IPv4 address.

Returns
True if the addresses are the same, false otherwise.

static inline bool net_ipv4_addr_cmp_raw(const uint8_t *addr1, const uint8_t *addr2)
Compare two raw IPv4 address buffers.

Parameters
• addr1 – Pointer to IPv4 address buffer.
• addr2 – Pointer to IPv4 address buffer.

Returns
True if the addresses are the same, false otherwise.

static inline bool net_ipv6_addr_cmp(const struct in6_addr *addr1, const struct in6_addr *addr2)
Compare two IPv6 addresses.

Parameters
• addr1 – Pointer to IPv6 address.
• addr2 – Pointer to IPv6 address.

Returns
True if the addresses are the same, false otherwise.

static inline bool net_ipv6_addr_cmp_raw(const uint8_t *addr1, const uint8_t *addr2)
Compare two raw IPv6 address buffers.

Parameters
• addr1 – Pointer to IPv6 address buffer.
• addr2 – Pointer to IPv6 address buffer.

Returns
True if the addresses are the same, false otherwise.
static inline bool net_ipv6_is_ll_addr(const struct in6_addr *addr)
Check if the given IPv6 address is a link local address.

Parameters
• addr – A valid pointer on an IPv6 address

Returns
True if it is, false otherwise.

static inline bool net_ipv6_is_ula_addr(const struct in6_addr *addr)
Check if the given IPv6 address is a unique local address.

Parameters
• addr – A valid pointer on an IPv6 address

Returns
True if it is, false otherwise.

const struct in6_addr *net_ipv6_unspecified_address(void)
Return pointer to any (all bits zeros) IPv6 address.

Returns
Any IPv6 address.

const struct in_addr *net_ipv4_unspecified_address(void)
Return pointer to any (all bits zeros) IPv4 address.

Returns
Any IPv4 address.

const struct in_addr *net_ipv4_broadcast_address(void)
Return pointer to broadcast (all bits ones) IPv4 address.

Returns
Broadcast IPv4 address.

bool net_if_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)
static inline bool net_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)
Check if the given address belongs to same subnet that has been configured for the interface.

Parameters
• iface – A valid pointer on an interface
• addr – IPv4 address

Returns
True if address is in same subnet, false otherwise.

bool net_if_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)
static inline bool net_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)
Check if the given IPv4 address is a broadcast address.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr – IPv4 address

Returns
True if address is a broadcast address, false otherwise.

struct net_if_addr *net_if_ipv4_addr_lookup(const struct in_addr *addr, struct net_if **iface)
static inline bool net_ipv4_is_my_addr(const struct in_addr *addr)
    Check if the IPv4 address is assigned to any network interface in the system.

    Parameters
    • addr – A valid pointer on an IPv4 address

    Returns
    True if IPv4 address is found in one of the network interfaces, False otherwise.

static inline bool net_ipv6_is_addr_unspecified(const struct in6_addr *addr)
    Check if the IPv6 address is unspecified (all bits zero)

    Parameters
    • addr – IPv6 address.

    Returns
    True if the address is unspecified, false otherwise.

static inline bool net_ipv6_is_addr_solicited_node(const struct in6_addr *addr)
    Check if the IPv6 address is solicited node multicast address FF02:0:0:0:0:1:FFXX:XXXX defined in RFC 3513.

    Parameters
    • addr – IPv6 address.

    Returns
    True if the address is solicited node address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_scope(const struct in6_addr *addr, int scope)
    Check if the IPv6 address is a given scope multicast address (FFyx::).

    Parameters
    • addr – IPv6 address
    • scope – Scope to check

    Returns
    True if the address is in given scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_global(const struct in6_addr *addr)
    Check if the IPv6 address is a global multicast address (FFxE::/16).

    Parameters
    • addr – IPv6 address.

    Returns
    True if the address is global multicast address, false otherwise.
static inline bool net_ipv6_is_addr_mcast_iface(const struct in6_addr *addr)

Check if the IPv6 address is a interface scope multicast address (FFx1:).

Parameters
• addr – IPv6 address.

Returns
True if the address is a interface scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_link(const struct in6_addr *addr)

Check if the IPv6 address is a link local scope multicast address (FFx2:).

Parameters
• addr – IPv6 address.

Returns
True if the address is a link local scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_mesh(const struct in6_addr *addr)

Check if the IPv6 address is a mesh-local scope multicast address (FFx3:).

Parameters
• addr – IPv6 address.

Returns
True if the address is a mesh-local scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_site(const struct in6_addr *addr)

Check if the IPv6 address is a site scope multicast address (FFx5:).

Parameters
• addr – IPv6 address.

Returns
True if the address is a site scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_org(const struct in6_addr *addr)

Check if the IPv6 address is an organization scope multicast address (FFx8:).

Parameters
• addr – IPv6 address.

Returns
True if the address is an organization scope multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_group(const struct in6_addr *addr, const struct in6_addr *group)

Check if the IPv6 address belongs to certain multicast group.

Parameters
• addr – IPv6 address.
• group – Group id IPv6 address, the values must be in network byte order

Returns
True if the IPv6 multicast address belongs to given multicast group, false other-
wise.

static inline bool net_ipv6_is_addr_mcast_all_nodes_group(const struct in6_addr *addr)

Check if the IPv6 address belongs to the all nodes multicast group.

Parameters
• addr – IPv6 address
Returns
True if the IPv6 multicast address belongs to the all nodes multicast group, false otherwise.

static inline bool net_ipv6_is_addr_mcast_iface_all_nodes(const struct in6_addr *addr)
Check if the IPv6 address is a interface scope all nodes multicast address (FF01::1).

Parameters
• addr – IPv6 address.

Returns
True if the address is a interface scope all nodes multicast address, false otherwise.

static inline bool net_ipv6_is_addr_mcast_link_all_nodes(const struct in6_addr *addr)
Check if the IPv6 address is a link local scope all nodes multicast address (FF02::1).

Parameters
• addr – IPv6 address.

Returns
True if the address is a link local scope all nodes multicast address, false otherwise.

static inline void net_ipv6_addr_create_solicited_node(const struct in6_addr *src, struct in6_addr *dst)
Create solicited node IPv6 multicast address FF02:0:0:0:1:FFXX:XXXX defined in RFC 3513.

Parameters
• src – IPv6 address.
• dst – IPv6 address.

static inline void net_ipv6_addr_create(struct in6_addr *addr, uint16_t addr0, uint16_t addr1,
uint16_t addr2, uint16_t addr3, uint16_t addr4,
uint16_t addr5, uint16_t addr6, uint16_t addr7)
Construct an IPv6 address from eight 16-bit words.

Parameters
• addr – IPv6 address
• addr0 – 16-bit word which is part of the address
• addr1 – 16-bit word which is part of the address
• addr2 – 16-bit word which is part of the address
• addr3 – 16-bit word which is part of the address
• addr4 – 16-bit word which is part of the address
• addr5 – 16-bit word which is part of the address
• addr6 – 16-bit word which is part of the address
• addr7 – 16-bit word which is part of the address

static inline void net_ipv6_addr_create_ll_allnodes_mcast(struct in6_addr *addr)
Create link local allnodes multicast IPv6 address.

Parameters
• addr – IPv6 address
static inline void net_ipv6_addr_create_ll_allrouters_mcast(struct in6_addr *addr)
Create link local allrouters multicast IPv6 address.

Parameters
• addr – IPv6 address

static inline void net_ipv6_addr_create_iid(struct in6_addr *addr, struct net_linkaddr *lladdr)
Create IPv6 address interface identifier.

Parameters
• addr – IPv6 address
• lladdr – Link local address

static inline bool net_ipv6_addr_based_on_ll(const struct in6_addr *addr, const struct net_linkaddr *lladdr)
Check if given address is based on link layer address.

Returns
True if it is, False otherwise

static inline struct sockaddr_in6 *net_sin6(const struct sockaddr *addr)
Get sockaddr_in6 from sockaddr. This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv6 socket address

static inline struct sockaddr_in *net_sin(const struct sockaddr *addr)
Get sockaddr_in from sockaddr. This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv4 socket address

static inline struct sockaddr_in6_ptr *net_sin6_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_in6_ptr from sockaddr_ptr. This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv6 socket address

static inline struct sockaddr_in_ptr *net_sin_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_in_ptr from sockaddr_ptr. This is a helper so that the code calling this function can be made shorter.

Parameters
• addr – Socket address

Returns
Pointer to IPv4 socket address
static inline struct sockaddr_ll_ptr *net_sll_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_ll_ptr from sockaddr_ptr. This is a helper so that the code calling this function can be made shorter.

**Parameters**
- addr – Socket address

**Returns**
Pointer to linklayer socket address

static inline struct sockaddr_can_ptr *net_can_ptr(const struct sockaddr_ptr *addr)
Get sockaddr_can_ptr from sockaddr_ptr. This is a helper so that the code needing this functionality can be made shorter.

**Parameters**
- addr – Socket address

**Returns**
Pointer to CAN socket address

int net_addr_pton(sa_family_t family, const char *src, void *dst)
Convert a string to IP address.

**Parameters**
- family – IP address family (AF_INET or AF_INET6)
- src – IP address in a null terminated string
- dst – Pointer to struct in_addr if family is AF_INET or pointer to struct in6_addr if family is AF_INET6

**Returns**
0 if ok, < 0 if error

char *net_addr_ntop(sa_family_t family, const void *src, char *dst, size_t size)
Convert IP address to string form.

**Parameters**
- family – IP address family (AF_INET or AF_INET6)
- src – Pointer to struct in_addr if family is AF_INET or pointer to struct in6_addr if family is AF_INET6
- dst – Buffer for IP address as a null terminated string
- size – Number of bytes available in the buffer

**Returns**
dst pointer if ok, NULL if error

bool net_ipaddr_parse(const char *str, size_t str_len, struct sockaddr *addr)
Parse a string that contains either IPV4 or IPV6 address and optional port, and store the information in user supplied sockaddr struct.

Syntax of the IP address string: 192.0.2.1:80 192.0.2.42 2001:db8::2 2001:db::42 Note that the str_len parameter is used to restrict the amount of characters that are checked. If the string does not contain port number, then the port number in sockaddr is not modified.
Parameters
- str – String that contains the IP address.
- str_len – Length of the string to be parsed.
- addr – Pointer to user supplied struct sockaddr.

Returns
True if parsing could be done, false otherwise.

static inline int32_t net_tcp_seq_cmp(uint32_t seq1, uint32_t seq2)
Compare TCP sequence numbers.
This function compares TCP sequence numbers, accounting for wraparound effects.

Parameters
- seq1 – First sequence number
- seq2 – Seconds sequence number

Returns
< 0 if seq1 < seq2, 0 if seq1 == seq2, > 0 if seq > seq2

static inline bool net_tcp_seq_greater(uint32_t seq1, uint32_t seq2)
Check that one TCP sequence number is greater.
This is convenience function on top of net_tcp_seq_cmp().

Parameters
- seq1 – First sequence number
- seq2 – Seconds sequence number

Returns
True if seq > seq2

int net_bytes_from_str(uint8_t *buf, int buf_len, const char *src)
Convert a string of hex values to array of bytes.
The syntax of the string is “ab:02:98:fa:42:01”

Parameters
- buf – Pointer to memory where the bytes are written.
- buf_len – Length of the memory area.
- src – String of bytes.

Returns
0 if ok, <0 if error

int net_tx_priority2tc(enum net_priority prio)
Convert Tx network packet priority to traffic class so we can place the packet into correct Tx queue.

Parameters
- prio – Network priority

Returns
Tx traffic class that handles that priority network traffic.

int net_rx_priority2tc(enum net_priority prio)
Convert Rx network packet priority to traffic class so we can place the packet into correct Rx queue.

Parameters
• prio – Network priority

**Returns**
Rx traffic class that handles that priority network traffic.

```c
static inline enum net_priority net_vlan2priority(uint8_t priority)
```

Convert network packet VLAN priority to network packet priority so we can place the packet into correct queue.

**Parameters**
• priority – VLAN priority

**Returns**
Network priority

```c
static inline uint8_t net_priority2vlan(enum net_priority priority)
```

Convert network packet priority to network packet VLAN priority.

**Parameters**
• priority – Packet priority

**Returns**
VLAN priority (PCP)

```c
const char *net_family2str(sa_family_t family)
```

Return network address family value as a string. This is only usable for debugging.

**Parameters**
• family – Network address family code

**Returns**
Network address family as a string, or NULL if family is unknown.

```c
struct in6_addr
    #include <net_ip.h> IPv6 address struct
```

```c
struct in_addr
    #include <net_ip.h> IPv4 address struct
```

```c
struct sockaddr_in6
    #include <net_ip.h> Socket address struct for IPv6.
```

```c
struct sockaddr_in6_ptr
    #include <net_ip.h>
```

```c
struct sockaddr_in
    #include <net_ip.h> Socket address struct for IPv4.
```

```c
struct sockaddr_in_ptr
    #include <net_ip.h>
```

```c
struct sockaddr_ll
    #include <net_ip.h> Socket address struct for packet socket.
```

```c
struct sockaddr_ll_ptr
    #include <net_ip.h>
```

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struct sockaddr_can_ptr
#include <net_ip.h>

struct iovec
#include <net_ip.h>

struct msghdr
#include <net_ip.h>

struct cmsghdr
#include <net_ip.h>

struct sockaddr
#include <net_ip.h> Generic sockaddr struct. Must be cast to proper type.

struct net_tuple
#include <net_ip.h> IPv6/IPv4 network connection tuple

Public Members

struct net_addr *remote_addr
IPv6/IPv4 remote address

struct net_addr *local_addr
IPv6/IPv4 local address

uint16_t remote_port
UDP/TCP remote port

uint16_t local_port
UDP/TCP local port

enum net_ip_protocol ip_proto
IP protocol

DNS Resolve

- **Overview**
  The DNS resolver implements a basic DNS resolver according to IETF RFC1035 on Domain Implementation and Specification. Supported DNS answers are IPv4/IPv6 addresses and CNAME.

  If a CNAME is received, the DNS resolver will create another DNS query. The number of additional queries is controlled by the CONFIG_DNS_RESOLVER_ADDITIONAL_QUERIES Kconfig variable.
The multicast DNS (mDNS) client resolver support can be enabled by setting `CONFIG_MDNS_RESOLVER` Kconfig option. See IETF RFC6762 for more details about mDNS.

The link-local multicast name resolution (LLMNR) client resolver support can be enabled by setting the `CONFIG_LLMNR_RESOLVER` Kconfig variable. See IETF RFC4795 for more details about LLMNR.

For more information about DNS configuration variables, see: subsys/net/lib/dns/Kconfig. The DNS resolver API can be found at include/zephyr/net/dns_resolve.h.

**Sample usage**  See DNS resolve sample application for details.

**API Reference**

*group dns_resolve*

DNS resolving library.

**Defines**

`DNS_MAX_NAME_SIZE`

Max size of the resolved name.

**Typedefs**

typedef void (*dns_resolve_cb_t)(enum dns_resolve_status status, struct dns_addrinfo *info, void *user_data)

DNS resolve callback.

The DNS resolve callback is called after a successful DNS resolving. The resolver can call this callback multiple times, one for each resolved address.

**Param status**

The status of the query: DNS_EAI_INPROGRESS returned for each resolved address DNS_EAI_ALLDONE mark end of the resolving, info is set to NULL in this case DNS_EAI_CANCELED if the query was canceled manually or time-out happened DNS_EAI_FAIL if the name cannot be resolved by the server DNS_EAI_NODATA if there is no such name other values means that an error happened.

**Param info**

Query results are stored here.

**Param user_data**

The user data given in `dns_resolve_name()` call.

**Enums**

enum dns_query_type

DNS query type enum

*Values:*

enumerator DNS_QUERY_TYPE_A = 1

IPv4 query
enumerator DNS_QUERY_TYPE_AAAA = 28
IPv6 query

denum dns_resolve_status
  Status values for the callback.
  Values:

  enumerator DNS_EAI_BADFLAGS = -1
     Invalid value for ai_flags field

  enumerator DNS_EAI_NONAME = -2
     NAME or SERVICE is unknown

  enumerator DNS_EAI_AGAIN = -3
     Temporary failure in name resolution

  enumerator DNS_EAI_FAIL = -4
     Non-recoverable failure in name res

  enumerator DNS_EAI_NODATA = -5
     No address associated with NAME

  enumerator DNS_EAI_FAMILY = -6
     ai_family not supported

  enumerator DNS_EAI_SOCKTYPE = -7
     ai_socktype not supported

  enumerator DNS_EAI_SERVICE = -8
     SRV not supported for ai_socktype

  enumerator DNS_EAI_ADDRFAMILY = -9
     Address family for NAME not supported

  enumerator DNS_EAI_MEMORY = -10
     Memory allocation failure

  enumerator DNS_EAI_SYSTEM = -11
     System error returned in errno

  enumerator DNS_EAI_OVERFLOW = -12
     Argument buffer overflow

  enumerator DNS_EAI_INPROGRESS = -100
     Processing request in progress

  enumerator DNS_EAI_CANCELED = -101
     Request canceled
enumerator DNS_EAI_NOTCANCELED = -102
    Request not canceled
enumerator DNS_EAI_ALLDONE = -103
    All requests done
enumerator DNS_EAI_IDN_ENCODE = -105
    IDN encoding failed

enum dns_resolve_context_state
    Values:
    enumerator DNS_RESOLVE_CONTEXT_ACTIVE
    enumerator DNS_RESOLVE_CONTEXT_DEACTIVATING
    enumerator DNS_RESOLVE_CONTEXT_INACTIVE

Functions

int dns_resolve_init(struct dns_resolve_context *ctx, const char *dns_servers_str[], const struct sockaddr *dns_servers_sa[])
    Init DNS resolving context.
    This function sets the DNS server address and initializes the DNS context that is used by the actual resolver. DNS server addresses can be specified either in textual form, or as struct sockaddr (or both). Note that the recommended way to resolve DNS names is to use the dns_get_addr_info() API. In that case user does not need to call dns_resolve_init() as the DNS servers are already setup by the system.

Parameters
    • ctx – DNS context. If the context variable is allocated from the stack, then the variable needs to be valid for the whole duration of the resolving. Caller does not need to fill the variable beforehand or edit the context afterwards.
    • dns_servers_str – DNS server addresses using textual strings. The array is NULL terminated. The port number can be given in the string. Syntax for the server addresses with or without port numbers: IPv4: 10.0.9.1 IPv4 + port: 10.0.9.1:5353 IPv6: 2001:db8::22:42 IPv6 + port: [2001:db8::22:42]:5353
    • dns_servers_sa – DNS server addresses as struct sockaddr. The array is NULL terminated. Port numbers are optional in struct sockaddr, the default will be used if set to 0.

Returns
    0 if ok, <0 if error.

int dns_resolve_close(struct dns_resolve_context *ctx)
    Close DNS resolving context.
    This releases DNS resolving context and marks the context unusable. Caller must call the dns_resolve_init() again to make context usable.

Parameters
    • ctx – DNS context
Returns
0 if ok, <0 if error.

int dns_resolve_reconfigure(struct dns_resolve_context *ctx, const char *servers_str[], const struct sockaddr *servers_sa[])

Reconfigures DNS resolving context.

Parameters
• ctx – DNS context
• servers_str – DNS server addresses using textual strings. The array is NULL terminated. The port number can be given in the string. Syntax for the server addresses with or without port numbers: IPv4 : 10.0.9.1 IPv4 + port : 10.0.9.1:5353 IPv6 : 2001:db8::22:42 IPv6 + port : [2001:db8::22:42]:5353
• servers_sa – DNS server addresses as struct sockaddr. The array is NULL terminated. Port numbers are optional in struct sockaddr, the default will be used if set to 0.

Returns
0 if ok, <0 if error.

int dns_resolve_cancel(struct dns_resolve_context *ctx, uint16_t dns_id)

Cancel a pending DNS query.

This releases DNS resources used by a pending query.

Parameters
• ctx – DNS context
• dns_id – DNS id of the pending query

Returns
0 if ok, <0 if error.

int dns_resolve_cancel_with_name(struct dns_resolve_context *ctx, uint16_t dns_id, const char *query_name, enum dns_query_type query_type)

Cancel a pending DNS query using id, name and type.

This releases DNS resources used by a pending query.

Parameters
• ctx – DNS context
• dns_id – DNS id of the pending query
• query_name – Name of the resource we are trying to query (hostname)
• query_type – Type of the query (A or AAAA)

Returns
0 if ok, <0 if error.

int dns_resolve_name(struct dns_resolve_context *ctx, const char *query, enum dns_query_type type, uint16_t *dns_id, dns_resolve_cb_t cb, void *user_data, int32_t timeout)

Resolve DNS name.

This function can be used to resolve e.g., IPv4 or IPv6 address. Note that this is asynchronous call, the function will return immediately and system will call the callback after resolving has finished or timeout has occurred. We might send the query to multiple servers (if there are more than one server configured), but we only use the result of the first received response.

Parameters
Zephyr Project Documentation, Release 3.2.99

• **ctx** – DNS context
• **query** – What the caller wants to resolve.
• **type** – What kind of data the caller wants to get.
• **dns_id** – DNS id is returned to the caller. This is needed if one wishes to cancel the query. This can be set to NULL if there is no need to cancel the query.
• **cb** – Callback to call after the resolving has finished or timeout has happened.
• **user_data** – The user data.
• **timeout** – The timeout value for the query. Possible values: SYS_FOREVER_MS: the query is tried forever, user needs to cancel it manually if it takes too long time to finish >0: start the query and let the system timeout it after specified ms

**Returns**
0 if resolving was started ok, < 0 otherwise

```c
struct dns_resolve_context *dns_resolve_get_default(void)
```
Get default DNS context.

The system level DNS context uses DNS servers that are defined in project config file. If no DNS servers are defined by the user, then resolving DNS names using default DNS context will do nothing. The configuration options are described in subsys/net/lib/dns/Kconfig file.

**Returns**
Default DNS context.

```c
static inline int dns_get_addr_info(const char *query, enum dns_query_type type, uint16_t *dns_id, dns_resolve_cb_t cb, void *user_data, int32_t timeout)
```
Get IP address info from DNS.

This function can be used to resolve e.g., IPv4 or IPv6 address. Note that this is asynchronous call, the function will return immediately and system will call the callback after resolving has finished or timeout has occurred. We might send the query to multiple servers (if there are more than one server configured), but we only use the result of the first received response. This variant uses system wide DNS servers.

**Parameters**
• **query** – What the caller wants to resolve.
• **type** – What kind of data the caller wants to get.
• **dns_id** – DNS id is returned to the caller. This is needed if one wishes to cancel the query. This can be set to NULL if there is no need to cancel the query.
• **cb** – Callback to call after the resolving has finished or timeout has happened.
• **user_data** – The user data.
• **timeout** – The timeout value for the connection. Possible values: SYS_FOREVER_MS: the query is tried forever, user needs to cancel it manually if it takes too long time to finish >0: start the query and let the system timeout it after specified ms

**Returns**
0 if resolving was started ok, < 0 otherwise

```c
static inline int dns_cancel_addr_info(uint16_t dns_id)
```
Cancel a pending DNS query.

This releases DNS resources used by a pending query.

**Parameters**

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• dns_id – DNS id of the pending query

**Returns**

  0 if ok, <0 if error.

```c
struct dns_addrinfo
#include <dns_resolve.h> Address info struct is passed to callback that gets all the results.
```

```c
struct dns_resolve_context
#include <dns_resolve.h> DNS resolve context structure.
```

### Public Members

```c
struct sockaddr dns_server
    DNS server information
```

```c
struct net_context *net_ctx
    Connection to the DNS server
```

```c
uint8_t is_mdns
    Is this server mDNS one
```

```c
uint8_t is_llmnr
    Is this server LLMNR one
```

```c
struct k_mutex lock
    Prevent concurrent access
```

```c
k_timeout_t buf_timeout
    This timeout is also used when a buffer is required from the buffer pools.
```

```c
enum dns_resolve_context_state state
    Is this context in use
```

```c
struct dns_pending_query
#include <dns_resolve.h> Result callbacks. We have multiple callbacks here so that it is possible to do multiple queries at the same time.
```

Contents of this structure can be inspected and changed only when the lock is held.

### Public Members

```c
struct k_work_delayable timer
    Timeout timer
```

```c
struct dns_resolve_context *ctx
    Back pointer to ctx, needed in timeout handler
```
dnz_resolve_cb_t cb
    Result callback.
    A null value indicates the slot is not in use.

void *user_data
    User data

k_timeout t timeout
    TX timeout

const char *query
    String containing the thing to resolve like www.example.com
    This is set to a non-null value when the query is started, and is not used thereafter.
    If the query completed at a point where the work item was still pending the pointer
    is cleared to indicate that the query is complete, but release of the query slot will be
    deferred until a request for a slot determines that the work item has been released.

dns_query_type query_type
    Query type

uint16_t id
    DNS id of this query

uint16_t query_hash
    Hash of the DNS name + query type we are querying. This hash is calculated so we
    can match the response that we are receiving. This is needed mainly for mDNS which
    is setting the DNS id to 0, which means that the id alone cannot be used to find correct
    pending query.

Network Management

- Overview
- Requesting a defined procedure
- Listening to network events
- Defining a network management procedure
- Signaling a network event
- API Reference

Overview  The Network Management APIs allow applications, as well as network layer code itself, to
call defined network routines at any level in the IP stack, or receive notifications on relevant network
events. For example, by using these APIs, application code can request a scan be done on a Wi-Fi- or
Bluetooth-based network interface, or request notification if a network interface IP address changes.

The Network Management API implementation is designed to save memory by eliminating code at
build time for management routines that are not used. Distinct and statically defined APIs for net-
work management procedures are not used. Instead, defined procedure handlers are registered by
using a NET_MGMT_REGISTER_REQUEST_HANDLER macro. Procedure requests are done through a single
net_mgmt() API that invokes the registered handler for the corresponding request.
The current implementation is experimental and may change and improve in future releases.

**Requesting a defined procedure** All network management requests are of the form `net_mgmt(mgmt_request, ...)`. The `mgmt_request` parameter is a bit mask that tells which stack layer is targeted, if a `net_if` object is implied, and the specific management procedure being requested. The available procedure requests depend on what has been implemented in the stack.

To avoid extra cost, all `net_mgmt()` calls are direct. Though this may change in a future release, it will not affect the users of this function.

**Listening to network events** You can receive notifications on network events by registering a callback function and specifying a set of events used to filter when your callback is invoked. The callback will have to be unique for a pair of layer and code, whereas on the command part it will be a mask of events.

Two functions are available, `net_mgmt_add_event_callback()` for registering the callback function, and `net_mgmt_del_event_callback()` for unregistering a callback. A helper function, `net_mgmt_init_event_callback()`, can be used to ease the initialization of the callback structure.

When an event occurs that matches a callback's event set, the associated callback function is invoked with the actual event code. This makes it possible for different events to be handled by the same callback function, if desired.

**Warning:** Event set filtering allows false positives for events that have the same layer and layer code. A callback handler function must check the event code (passed as an argument) against the specific network events it will handle, **regardless** of how many events were in the set passed to `net_mgmt_init_event_callback()`.

Note that in order to receive events from multiple layers, one must have multiple listeners registered, one for each layer being listened. The callback handler function can be shared between different layer events.

(Warning: False positives can occur for events which have the same layer and layer code.)

An example follows.

```c
/*
 * Set of events to handle.
 * See e.g. include/net/net_event.h for some NET_EVENT_xxx values.
 */
#define EVENT_IFACE_SET (NET_EVENT_IF_xxx | NET_EVENT_IF_yyy)
#define EVENT_IPV4_SET (NET_EVENT_IPV4_xxx | NET_EVENT_IPV4_yyy)

struct net_mgmt_event_callback iface_callback;
struct net_mgmt_event_callback ipv4_callback;

void callback_handler(struct net_mgmt_event_callback *cb,
                      uint32_t mgmt_event,
                      struct net_if *iface)
{
    if (mgmt_event == NET_EVENT_IF_xxx) {
        /* Handle NET_EVENT_IF_xxx */
    } else if (mgmt_event == NET_EVENT_IF_yyy) {
        /* Handle NET_EVENT_IF_yyy */
    } else if (mgmt_event == NET_EVENT_IPV4_xxx) {
        /* Handle NET_EVENT_IPV4_xxx */
    } else if (mgmt_event == NET_EVENT_IPV4_yyy) {
        /* Handle NET_EVENT_IPV4_yyy */
    }
}
```

(continues on next page)
See include/zephyr/net/net_event.h for available generic core events that can be listened to.

Defining a network management procedure  You can provide additional management procedures specific to your stack implementation by defining a handler and registering it with an associated mgmt_request code.

Management request code are defined in relevant places depending on the targeted layer or eventually, if l2 is the layer, on the technology as well. For instance, all IP layer management request code will be found in the include/zephyr/net/net_event.h header file. But in case of an L2 technology, let’s say Ethernet, these would be found in include/zephyr/net/ethernet.h

You define your handler modeled with this signature:

```
static int your_handler(uint32_t mgmt_event, struct net_if *iface, void *data, size_t len);
```

and then register it with an associated mgmt_request code:

```
NET_MGMT_REGISTER_REQUEST_HANDLER(<mgmt_request code>, your_handler);
```

This new management procedure could then be called by using:

```
net_mgmt(<mgmt_request code>, ...);
```

Signaling a network event You can signal a specific network event using the net_mgmt_event_notify() function and provide the network event code. See include/zephyr/net/net_mgmt.h for details. As for the management request code, event code can be also found on specific L2 technology mgmt headers, for example include/zephyr/net/ieee802154_mgmt.h would be the right place if 802.15.4 L2 is the technology one wants to listen to events.

API Reference

**group net_mgmt**

Network Management.

**Defines**


```
net_mgmt(_mgmt_request, _iface, _data, _len)
```
### Typedefs

```c
typedef int (*net_mgmt_request_handler_t)(uint32_t mgmt_request, struct net_if *iface, void *data, size_t len);
```

Signature which all Net MGMT request handler need to follow.

**Param mgmt_request**
The exact request value the handler is being called through

**Param iface**
A valid pointer on struct `net_if` if the request is meant to be tight to a network interface. NULL otherwise.

**Param data**
A valid pointer on a data understood by the handler. NULL otherwise.

**Param len**
Length in byte of the memory pointed by data.

```c
typedef void (*net_mgmt_event_handler_t)(struct net_mgmt_event_callback *cb, uint32_t mgmt_event, struct net_if *iface);
```

Define the user's callback handler function signature.

**Param cb**
Original struct `net_mgmt_event_callback` owning this handler.

**Param mgmt_event**
The network event being notified.

**Param iface**
A pointer on a struct `net_if` to which the the event belongs to, if it's an event on an iface. NULL otherwise.

### Functions

```c
static inline void net_mgmt_init_event_callback(struct net_mgmt_event_callback *cb, net_mgmt_event_handler_t handler, uint32_t mgmt_event_mask);
```

Helper to initialize a struct `net_mgmt_event_callback` properly.

**Parameters**
- `cb` – A valid application's callback structure pointer.
- `handler` – A valid handler function pointer.
- `mgmt_event_mask` – A mask of relevant events for the handler

```c
void net_mgmt_add_event_callback(struct net_mgmt_event_callback *cb);
```

Add a user callback.

**Parameters**
- `cb` – A valid pointer on user's callback to add.
void net_mgmt_del_event_callback(struct net_mgmt_event_callback *cb)
Delete a user callback.

Parameters
- cb – A valid pointer on user’s callback to delete.

void net_mgmt_event_notify_with_info(uint32_t mgmt_event, struct net_if *iface, const void *info, size_t length)
Used by the system to notify an event.

Note: info and length are disabled if CONFIG_NET_MGMT_EVENT_INFO is not defined.

Parameters
- mgmt_event – The actual network event code to notify
- iface – a valid pointer on a struct net_if if only the event is based on an iface. NULL otherwise.
- info – a valid pointer on the information you want to pass along with the event. NULL otherwise. Note the data pointed there is normalized by the related event.
- length – size of the data pointed by info pointer.

static inline void net_mgmt_event_notify(uint32_t mgmt_event, struct net_if *iface)

int net_mgmt_event_wait(uint32_t mgmt_event_mask, uint32_t *raised_event, struct net_if *iface, const void *info, size_t *info_length, k_timeout_t timeout)
Used to wait synchronously on an event mask.

Parameters
- mgmt_event_mask – A mask of relevant events to wait on.
- raised_event – a pointer on a uint32_t to get which event from the mask generated the event. Can be NULL if the caller is not interested in that information.
- iface – a pointer on a place holder for the iface on which the event has originated from. This is valid if only the event mask has bit NET_MGMT_IFACE_BIT set relevantly, depending on events the caller wants to listen to.
- info – a valid pointer if user wants to get the information the event might bring along. NULL otherwise.
- info_length – tells how long the info memory area is. Only valid if the info is not NULL.
- timeout – A timeout delay. K_FOREVER can be used to wait indefinitely.

Returns
0 on success, a negative error code otherwise. -ETIMEDOUT will be specifically returned if the timeout kick-in instead of an actual event.

int net_mgmt_event_wait_on_iface(struct net_if *iface, uint32_t mgmt_event_mask, uint32_t *raised_event, const void *info, size_t *info_length, k_timeout_t timeout)
Used to wait synchronously on an event mask for a specific iface.

Parameters
- iface – a pointer on a valid network interface to listen event to
- mgmt_event_mask – A mask of relevant events to wait on. Listened to events should be relevant to iface events and thus have the bit NET_MGMT_IFACE_BIT set.
• raised_event – a pointer on a uint32_t to get which event from the mask generated the event. Can be NULL if the caller is not interested in that information.

• info – a valid pointer if user wants to get the information the event might bring along. NULL otherwise.

• info_length – tells how long the info memory area is. Only valid if the info is not NULL.

• timeout – A timeout delay. K_FOREVER can be used to wait indefinitely.

Returns
0 on success, a negative error code otherwise. -ETIMEDOUT will be specifically returned if the timeout kick-in instead of an actual event.

void net_mgmt_event_init(void)

Used by the core of the network stack to initialize the network event processing.

struct net_mgmt_event_callback

#include <net_mgmt.h> Network Management event callback structure Used to register a callback into the network management event part, in order to let the owner of this struct to get network event notification based on given event mask.

Public Members

sys_snode_t node

Meant to be used internally, to insert the callback into a list. So nobody should mess with it.

net_mgmt_event_handler_t handler

Actual callback function being used to notify the owner

struct k_sem *sync_call

Semaphore meant to be used internally for the synchronous net_mgmt_event_wait() function.

uint32_t event_mask

A mask of network events on which the above handler should be called in case those events come. Note that only the command part is treated as a mask, matching one to several commands. Layer and layer code will be made of an exact match. This means that in order to receive events from multiple layers, one must have multiple listeners registered, one for each layer being listened.

uint32_t raised_event

Internal place holder when a synchronous event wait is successfully unlocked on a event.

union net_mgmt_event_callback.[anonymous] [anonymous]

A mask of network events on which the above handler should be called in case those events come. Such mask can be modified whenever necessary by the owner, and thus will affect the handler being called or not.
Overview  Network statistics are collected if CONFIG_NET_STATISTICS is set. Individual component statistics for IPv4 or IPv6 can be turned off if those statistics are not needed. See various options in subsys/net/ip/Kconfig.stats file for details.

By default, the system collects network statistics per network interface. This can be controlled by CONFIG_NET_STATISTICS_PER_INTERFACE option.

The CONFIG_NET_STATISTICS_USER_API option can be set if the application wants to collect statistics for further processing. The network management interface API is used for that. See Network Management for details.

The CONFIG_NET_STATISTICS_ETHERNET option can be set to collect generic Ethernet statistics. If the CONFIG_NET_STATISTICS_ETHERNET_VENDOR option is set, then Ethernet device driver can collect Ethernet device specific statistics. These statistics can then be transferred to application for processing.

If the CONFIG_NET_SHELL option is set, then network shell can show statistics information with `net stats` command.

API Reference

**group net_stats**

Network statistics library.

**Defines**

NET_TC_TX_STATS_COUNT

NET_TC_RX_STATS_COUNT

**Typedefs**

typedef uint32_t net_stats_t

Network statistics counter.

struct net_stats_bytes

#include <net_stats.h>  Number of bytes sent and received.

**Public Members**

net_stats_t sent

Number of bytes sent

net_stats_t received

Number of bytes received

struct net_stats_pkts

#include <net_stats.h>  Number of network packets sent and received.
Public Members

`net_stats_t tx`
Number of packets sent

`net_stats_t rx`
Number of packets received

```c
#include <net_stats.h>
```
IP layer statistics.

Public Members

`net_stats_t recv`
Number of received packets at the IP layer.

`net_stats_t sent`
Number of sent packets at the IP layer.

`net_stats_t forwarded`
Number of forwarded packets at the IP layer.

`net_stats_t drop`
Number of dropped packets at the IP layer.

```c
#include <net_stats.h>
```
IP layer error statistics.

Public Members

`net_stats_t vhlerr`
Number of packets dropped due to wrong IP version or header length.

`net_stats_t hblenerr`
Number of packets dropped due to wrong IP length, high byte.

`net_stats_t lblenerr`
Number of packets dropped due to wrong IP length, low byte.

`net_stats_t fragerr`
Number of packets dropped because they were IP fragments.

`net_stats_t chkerr`
Number of packets dropped due to IP checksum errors.

`net_stats_t protoerr`
Number of packets dropped because they were neither ICMP, UDP nor TCP.
struct net_stats_icmp

    #include <net_stats.h> ICMP statistics.

Public Members

    net_stats_t recv
    Number of received ICMP packets.

    net_stats_t sent
    Number of sent ICMP packets.

    net_stats_t drop
    Number of dropped ICMP packets.

    net_stats_t typeerr
    Number of ICMP packets with a wrong type.

    net_stats_t chkerr
    Number of ICMP packets with a bad checksum.

struct net_stats_tcp

    #include <net_stats.h> TCP statistics.

Public Members

    struct net_stats_bytes bytes
    Amount of received and sent TCP application data.

    net_stats_t resent
    Amount of retransmitted data.

    net_stats_t drop
    Number of dropped packets at the TCP layer.

    net_stats_t recv
    Number of received TCP segments.

    net_stats_t sent
    Number of sent TCP segments.

    net_stats_t seg_drop
    Number of dropped TCP segments.

    net_stats_t chkerr
    Number of TCP segments with a bad checksum.
\textit{net_stats_t} \texttt{ackerr}

Number of received TCP segments with a bad ACK number.

\textit{net_stats_t} \texttt{rsterr}

Number of received bad TCP RST (reset) segments.

\textit{net_stats_t} \texttt{rst}

Number of received TCP RST (reset) segments.

\textit{net_stats_t} \texttt{rexmit}

Number of retransmitted TCP segments.

\textit{net_stats_t} \texttt{conndrop}

Number of dropped connection attempts because too few connections were available.

\textit{net_stats_t} \texttt{connrst}

Number of connection attempts for closed ports, triggering a RST.

\textbf{Public Members}

\textit{net_stats_t} \texttt{drop}

Number of dropped UDP segments.

\textit{net_stats_t} \texttt{recv}

Number of received UDP segments.

\textit{net_stats_t} \texttt{sent}

Number of sent UDP segments.

\textit{net_stats_t} \texttt{chkerr}

Number of UDP segments with a bad checksum.

\textbf{Public Members}

\textit{net_stats_t} \texttt{recv}

Number of received IPv6 MLD queries
\texttt{net_stats_t sent}
Number of sent IPv6 MLD reports

\texttt{net_stats_t drop}
Number of dropped IPv6 MLD packets

\texttt{struct net_stats_ipv4_igmp}
#include <net_stats.h> IPv4 IGMP daemon statistics.

\textbf{Public Members}

\texttt{net_stats_t recv}
Number of received IPv4 IGMP queries

\texttt{net_stats_t sent}
Number of sent IPv4 IGMP reports

\texttt{net_stats_t drop}
Number of dropped IPv4 IGMP packets

\texttt{struct net_stats_tx_time}
#include <net_stats.h> Network packet transfer times for calculating average TX time.

\texttt{struct net_stats_rx_time}
#include <net_stats.h> Network packet receive times for calculating average RX time.

\texttt{struct net_stats_tc}
#include <net_stats.h> Traffic class statistics.

\texttt{struct net_stats_pm}
#include <net_stats.h> Power management statistics.

\texttt{struct net_stats}
#include <net_stats.h> All network statistics in one struct.

\textbf{Public Members}

\texttt{net_stats_t processing_error}
Count of malformed packets or packets we do not have handler for

\texttt{struct net_stats_bytes bytes}
This calculates amount of data transferred through all the network interfaces.

\texttt{struct net_stats_ip_errors ip_errors}
IP layer errors
struct net_stats_eth_errors
#include <net_stats.h> Ethernet error statistics.

struct net_stats_eth_flow
#include <net_stats.h> Ethernet flow control statistics.

struct net_stats_eth_csum
#include <net_stats.h> Ethernet checksum statistics.

struct net_stats_eth_hw_timestamp
#include <net_stats.h> Ethernet hardware timestamp statistics.

struct net_stats_eth
#include <net_stats.h> All Ethernet specific statistics.

struct net_stats_ppp
#include <net_stats.h> All PPP specific statistics.

Public Members

net_stats_t drop
 Number of received and dropped PPP frames.

net_stats_t chkerr
 Number of received PPP frames with a bad checksum.

struct net_stats_sta_mgmt
#include <net_stats.h> All Wi-Fi management statistics.

Public Members

net_stats_t beacons_rx
 Number of received beacons

net_stats_t beacons_miss
 Number of missed beacons

struct net_stats_wifi
#include <net_stats.h> All Wi-Fi specific statistics.

Network Timeout
Overview  Zephyr’s network infrastructure mostly uses the millisecond-resolution uptime clock to track timeouts, with both deadlines and durations measured with 32-bit unsigned values. The 32-bit value rolls over at 49 days 17 hours 2 minutes 47.296 seconds.

Timeout processing is often affected by latency, so that the time at which the timeout is checked may be some time after it should have expired. Handling this correctly without arbitrary expectations of maximum latency requires that the maximum delay that can be directly represented be a 31-bit non-negative number (INT32_MAX), which overflows at 24 days 20 hours 31 minutes 23.648 seconds.

Most network timeouts are shorter than the delay rollover, but a few protocols allow for delays that are represented as unsigned 32-bit values counting seconds, which corresponds to a 42-bit millisecond count.

The net_timeout API provides a generic timeout mechanism to correctly track the remaining time for these extended-duration timeouts.

Use  The simplest use of this API is:

1. Configure a network timeout using net_timeout_set().
2. Use net_timeout_evaluate() to determine how long it is until the timeout occurs. Schedule a timeout to occur after this delay.
3. When the timeout callback is invoked, use net_timeout_evaluate() again to determine whether the timeout has completed, or whether there is additional time remaining. If the latter, reschedule the callback.
4. While the timeout is running, use net_timeout_remaining() to get the number of seconds until the timeout expires. This may be used to explicitly update the timeout, which should be done by canceling any pending callback and restarting from step 1 with the new timeout.

The net_timeout contains a sys_snode_t that allows multiple timeout instances to be aggregated to share a single kernel timer element. The application must use net_timeout_evaluate() on all instances to determine the next timeout event to occur.

net_timeout_deadline() may be used to reconstruct the full-precision deadline of the timeout. This exists primarily for testing but may have use in some applications, as it does allow a millisecond-resolution calculation of remaining time.

API Reference

group net_timeout

Network long timeout primitives and helpers.

Defines

NET_TIMEOUT_MAX_VALUE

Defines used to support ms resolution timeouts.

Because delays are processed in work queues which are not invoked synchronously with clock changes we need to be able to detect timeouts after they occur, which requires comparing “deadline” to “now” with enough “slop” to handle any observable latency due to “now” advancing past “deadline”.

The simplest solution is to use the native conversion of the well-defined 32-bit unsigned difference to a 32-bit signed difference, which caps the maximum delay at INT32_MAX. This is compatible with the standard mechanism for detecting completion of deadlines that do not overflow their representation.
Functions

void net_timeout_set(struct net_timeout *timeout, uint32_t lifetime, uint32_t now)
Configure a network timeout structure.

Parameters
- timeout – a pointer to the timeout state.
- lifetime – the duration of the timeout in seconds.
- now – the time at which the timeout started counting down, in milliseconds.
  This is generally a captured value of k_uptime_get_32().

int64_t net_timeout_deadline(const struct net_timeout *timeout, int64_t now)
Return the 64-bit system time at which the timeout will complete.

Note: Correct behavior requires invocation of net_timeout_evaluate() at its specified intervals.

Parameters
- timeout – state a pointer to the timeout state, initialized by net_timeout_set() and maintained by net_timeout_evaluate().
- now – the full-precision value of k_uptime_get() relative to which the deadline will be calculated.

Returns
the value of k_uptime_get() at which the timeout will expire.

uint32_t net_timeout_remaining(const struct net_timeout *timeout, uint32_t now)
Calculate the remaining time to the timeout in whole seconds.

Note: This function rounds the remaining time down, i.e. if the timeout will occur in 3500 milliseconds the value 3 will be returned.

Note: Correct behavior requires invocation of net_timeout_evaluate() at its specified intervals.

Parameters
- timeout – a pointer to the timeout state
- now – the time relative to which the estimate of remaining time should be calculated. This should be recently captured value from k_uptime_get_32().

Return values
- 0 – if the timeout has completed.
- positive – the remaining duration of the timeout, in seconds.

uint32_t net_timeout_evaluate(struct net_timeout *timeout, uint32_t now)
Update state to reflect elapsed time and get new delay.
This function must be invoked periodically to (1) apply the effect of elapsed time on what remains of a total delay that exceeded the maximum representable delay, and (2) determine that either the timeout has completed or that the infrastructure must wait a certain period before checking again for completion.

Parameters
- `timeout` – a pointer to the timeout state
- `now` – the time relative to which the estimate of remaining time should be calculated. This should be recently captured value from `k_uptime_get_32()`.

**Return values**
- 0 – if the timeout has completed
- positive – the maximum delay until the state of this timeout should be re-evaluated, in milliseconds.

```c
struct net_timeout

#include <net_timeout.h> Generic struct for handling network timeouts.

Except for the linking node, all access to state from these objects must go through the defined API.

**Public Members**

```
sys_snode_t node
Used to link multiple timeouts that share a common timer infrastructure.
For examples a set of related timers may use a single delayed work structure, which is always scheduled at the shortest time to a timeout event.
```

**Networking Context** The `net_context` API is not meant for application use. Application should use `BSD Sockets` API instead.

### Promiscuous Mode

**Overview** Promiscuous mode is a mode for a network interface controller that causes it to pass all traffic it receives to the application rather than passing only the frames that the controller is specifically programmed to receive. This mode is normally used for packet sniffing as used to diagnose network connectivity issues by showing an application all the data being transferred over the network. (See the Wikipedia article on promiscuous mode for more information.)

The network promiscuous APIs are used to enable and disable this mode, and to wait for and receive a network data to arrive. Not all network technologies or network device drivers support promiscuous mode.

**Sample usage** First the promiscuous mode needs to be turned ON by the application like this:

```c
ret = net_promisc_mode_on(iface);
if (ret < 0) {
    if (ret == -EALREADY) {
        printf("Promiscuous mode already enabled\n");
    } else {
        printf("Cannot enable promiscuous mode for "
```

(continues on next page)
"interface %p (%d)\n", iface, ret);}
}

If there is no error, then the application can start to wait for network data:

```c
while (true) {
    pkt = net_promisc_mode_wait_data(K_FOREVER);
    if (pkt) {
        print_info(pkt);
    }
    net_pkt_unref(pkt);
}
```

Finally the promiscuous mode can be turned OFF by the application like this:

```c
ret = net_promisc_mode_off(iface);
if (ret < 0) {
    if (ret == -EALREADY) {
        printf("Promiscuous mode already disabled\n");
    } else {
        printf("Cannot disable promiscuous mode for 
        "interface %p (%d)\n", iface, ret);
    }
}
```

See net-promiscuous-mode-sample for a more comprehensive example.

### API Reference

**group promiscuous**

Promiscuous mode support.

#### Functions

- **static inline struct net_pkt *net_promisc_mode_wait_data(k_timeout_t timeout)**
  
  Start to wait received network packets.

  **Parameters**
  
  - timeout – How long to wait before returning.

  **Returns**
  
  Received *net_pkt*, NULL if not received any packet.

- **static inline int net_promisc_mode_on(struct net_if *iface)**
  
  Enable promiscuous mode for a given network interface.

  **Parameters**
  
  - iface – Network interface

  **Returns**
  
  0 if ok, <0 if error

- **static inline int net_promisc_mode_off(struct net_if *iface)**
  
  Disable promiscuous mode for a given network interface.

  **Parameters**
Simple Network Time Protocol Library

Overview

The SNTP library implements IETF RFC4330 (Simple Network Time Protocol v4). SNTP provides a way to synchronize clocks in computer networks.

API Reference

group sntp

Simple Network Time Protocol API.

Functions

int sntp_init(struct sntp_ctx *ctx, struct sockaddr *addr, socklen_t addr_len)

Initialize SNTP context.

Parameters

• ctx – Address of sntp context.
• addr – IP address of NTP/SNTP server.
• addr_len – IP address length of NTP/SNTP server.

Returns

0 if ok, <0 if error.

int sntp_query(struct sntp_ctx *ctx, uint32_t timeout, struct sntp_time *time)

Perform SNTP query.

Parameters

• ctx – Address of sntp context.
• timeout – Timeout of waiting for sntp response (in milliseconds).
• time – Timestamp including integer and fractional seconds since 1 Jan 1970 (output).

Returns

0 if ok, <0 if error (-ETIMEDOUT if timeout).

void sntp_close(struct sntp_ctx *ctx)

Release SNTP context.

Parameters

• ctx – Address of sntp context.
int sntp_simple(const char *server, uint32_t timeout, struct sntp_time *time)

Convenience function to query SNTP in one-shot fashion.

Convenience wrapper which calls getaddrinfo(), sntp_init, sntp_query, and sntp_close().

Parameters

- server – Address of server in format addr[:port]
- timeout – Query timeout
- time – Timestamp including integer and fractional seconds since 1 Jan 1970 (output).

Returns

0 if ok, <0 if error (-ETIMEDOUT if timeout).

struct sntp_ctx

#include <sntp.h> SNTP context

Public Members

uint32_t expected_orig_ts

Timestamp when the request was sent from client to server. This is used to check if the originated timestamp in the server reply matches the one in client request.

struct sntp_time

#include <sntp.h> Time as returned by SNTP API, fractional seconds since 1 Jan 1970

SOCKS5 Proxy Support

- Overview
- SOCKS5 API
- SOCKS5 Proxy Usage in MQTT

Overview

The SOCKS library implements SOCKS5 support, which allows Zephyr to connect to peer devices via a network proxy.

See this SOCKS5 Wikipedia article for a detailed overview of how SOCKS5 works.

For more information about the protocol itself, see IETF RFC1928 SOCKS Protocol Version 5.

SOCKS5 API

The SOCKS5 support is enabled by CONFIG_SOCKS Kconfig variable. Application wanting to use the SOCKS5 must set the SOCKS5 proxy host address by calling setsockopt() like this:

```c
static int set_proxy(int sock, const struct sockaddr *proxy_addr, socklen_t proxy_addrlen)
{
    int ret;

    ret = setsockopt(sock, SOL_SOCKET, SO_SOCKS5, proxy_addr, proxy_addrlen);
    if (ret < 0) {
```
SOCKS5 Proxy Usage in MQTT For MQTT client, there is `mqtt_client_set_proxy()` API that the application can call to setup SOCKS5 proxy. See `mqtt-publisher-sample` for usage example.

Trickle Timer Library

**Overview** The Trickle timer library implements IETF RFC6206 (Trickle Algorithm). The Trickle algorithm allows nodes in a lossy shared medium (e.g., low-power and lossy networks) to exchange information in a highly robust, energy efficient, simple, and scalable manner.

**API Reference**

*group trickle*  
Trickle algorithm library.

**Types**

typedef void (*net_trickle_cb_t)(struct net_trickle *trickle, bool do_suppress, void *user_data)  
Trickle timer callback.  
The callback is called after Trickle timeout expires.

- **Param trickle**  
The trickle context to use.

- **Param do_suppress**  
Is TX allowed (true) or not (false).

- **Param user_data**  
The user data given in `net_trickle_start()` call.

**Functions**

```c
int net_trickle_create(struct net_trickle *trickle, uint32_t Imin, uint8_t Imax, uint8_t k)
```

Create a Trickle timer.

**Parameters**

- **trickle** – Pointer to Trickle struct.
- **Imin** – Imin configuration parameter in ms.
- **Imax** – Max number of doublings.
• k – Redundancy constant parameter. See RFC 6206 for details.

**Returns**
Return 0 if ok and <0 if error.

```c
int net_trickle_start(struct net_trickle *trickle, net_trickle_cb_t cb, void *user_data)
```
Start a Trickle timer.

**Parameters**
- `trickle` – Pointer to Trickle struct.
- `cb` – User callback to call at time T within the current trickle interval
- `user_data` – User pointer that is passed to callback.

**Returns**
Return 0 if ok and <0 if error.

```c
int net_trickle_stop(struct net_trickle *trickle)
```
Stop a Trickle timer.

**Parameters**
- `trickle` – Pointer to Trickle struct.

**Returns**
Return 0 if ok and <0 if error.

```c
void net_trickle_consistency(struct net_trickle *trickle)
```
To be called by the protocol handler when it hears a consistent network transmission.

**Parameters**
- `trickle` – Pointer to Trickle struct.

```c
void net_trickle_inconsistency(struct net_trickle *trickle)
```
To be called by the protocol handler when it hears an inconsistent network transmission.

**Parameters**
- `trickle` – Pointer to Trickle struct.

```c
static inline bool net_trickle_is_running(struct net_trickle *trickle)
```
Check if the Trickle timer is running or not.

**Parameters**
- `trickle` – Pointer to Trickle struct.

```c
struct net_trickle
```
#include <trickle.h> The variable names are taken directly from RFC 6206 when applicable. Note that the struct members should not be accessed directly but only via the Trickle API.

**Public Members**

```c
uint32_t Imin
```
Min interval size in ms

```c
uint8_t Imax
```
Max number of doublings
uint8_t k
    Redundancy constant

uint32_t I
    Current interval size

uint32_t Istart
    Start of the interval in ms

uint8_t c
    Consistency counter

uint32_t Imax_abs
    Max interval size in ms (not doublings)

net_trickle_cb_t cb
    Callback to be called when timer expires

Websocket Client API

- Overview
- Websocket Transport
- API Reference

Overview
The Websocket client library allows Zephyr to connect to a Websocket server. The Websocket client API can be used directly by application to establish a Websocket connection to server, or it can be used as a transport for other network protocols like MQTT.

See this Websocket Wikipedia article for a detailed overview of how Websocket works.

For more information about the protocol itself, see IETF RFC6455 The WebSocket Protocol.

Websocket Transport
The Websocket API allows it to be used as a transport for other high level protocols like MQTT. The Zephyr MQTT client library can be configured to use Websocket transport by enabling CONFIG_MQTT_LIB_WEBSOCKET and CONFIG_WEBSOCKET_CLIENT Kconfig options.

First a socket needs to be created and connected to the Websocket server:

```c
sock = socket(family, SOCK_STREAM, IPPROTO_TCP);
...
ret = connect(sock, addr, addr_len);
...
```

The Websocket transport socket is then created like this:

```c
ws_sock = websocket_connect(sock, &config, timeout, user_data);
```

The Websocket socket can then be used to send or receive data, and the Websocket client API will encapsulate the sent or received data to/from Websocket packet payload. Both the websocket_xxx() API or normal BSD socket API functions can be used to send and receive application data.
If normal BSD socket functions are used, then currently only TEXT data is supported. In order to send BINARY data, the `websocket_send_msg()` must be used.

When done, the Websocket transport socket must be closed.

```c
ret = close(ws_sock);
```
or

```c
ret = websocket_disconnect(ws_sock);
```

### API Reference

**group** websocket

Websocket API.

**Defines**

- **WEBSOCKET_FLAG_FINAL**
  
  Message type values. Returned in `websocket_recv_msg()` Final frame

- **WEBSOCKET_FLAG_TEXT**
  
  Textual data

- **WEBSOCKET_FLAG_BINARY**
  
  Binary data

- **WEBSOCKET_FLAG_CLOSE**
  
  Closing connection

- **WEBSOCKET_FLAG_PING**
  
  Ping message

- **WEBSOCKET_FLAG_PONG**
  
  Pong message

**Typedefs**

```c
typedef int (*websocket_connect_cb_t)(int ws_sock, struct http_request *req, void *user_data)
```

Callback called after Websocket connection is established.

**Param ws_sock**

Websocket id

**Param req**

HTTP handshake request
**Param user_data**
A valid pointer on some user data or NULL

**Return**
0 if ok, <0 if there is an error and connection should be aborted

** Enums **

enum websocket_opcode

Values:

enumerator WEBSOCKET_OPCODE_CONTINUE = 0x00

enumerator WEBSOCKET_OPCODE_DATA_TEXT = 0x01

enumerator WEBSOCKET_OPCODE_DATA_BINARY = 0x02

enumerator WEBSOCKET_OPCODE_CLOSE = 0x08

enumerator WEBSOCKET_OPCODE_PING = 0x09

enumerator WEBSOCKET_OPCODE_PONG = 0x0A

** Functions **

int websocket_connect(int http_sock, struct websocket_request *req, int timeout, void *user_data)

Connect to a server that provides Websocket service. The callback is called after connection is established. The returned value is a new socket descriptor that can be used to send / receive data using the BSD socket API.

** Parameters **

- **http_sock** – Socket id to the server. Note that this socket is used to do HTTP handshakes etc. The actual Websocket connectivity is done via the returned websocket id. Note that the http_sock must not be closed after this function returns as it is used to deliver the Websocket packets to the Websocket server.
- **req** – Websocket request. User should allocate and fill the request data.
- **timeout** – Max timeout to wait for the connection. The timeout value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.
- **user_data** – User specified data that is passed to the callback.

** Returns **

Websocket id to be used when sending/receiving Websocket data.

int websocket_send_msg(int ws_sock, const uint8_t *payload, size_t payload_len, enum websocket_opcode opcode, bool mask, bool final, int32_t timeout)

Send websocket msg to peer.

The function will automatically add websocket header to the message.

** Parameters **

- **ws_sock** – Websocket id returned by websocket_connect().
• payload – Websocket data to send.
• payload_len – Length of the data to be sent.
• opcode – Operation code (text, binary, ping, pong, close)
• mask – Mask the data, see RFC 6455 for details
• final – Is this final message for this message send. If final == false, then the first message must have valid opcode and subsequent messages must have opcode WEB_SOCKET_OPCODE_CONTINUE. If final == true and this is the only message, then opcode should have proper opcode (text or binary) set.
• timeout – How long to try to send the message. The value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.

**Returns**

<0 if error, >=0 amount of bytes sent

```c
int websocket_recv_msg(int ws_sock, uint8_t *buf, size_t buf_len, uint32_t *message_type, uint64_t *remaining, int32_t timeout)
```

Receive websocket msg from peer.
The function will automatically remove websocket header from the message.

**Parameters**

• ws_sock – Websocket id returned by websocket_connect().
• buf – Buffer where websocket data is read.
• buf_len – Length of the data buffer.
• message_type – Type of the message.
• remaining – How much there is data left in the message after this read.
• timeout – How long to try to receive the message. The value is in milliseconds. Value SYS_FOREVER_MS means to wait forever.

**Returns**

<0 if error, >=0 amount of bytes received

```c
int websocket_disconnect(int ws_sock)
```

Close websocket.
One must call websocket_connect() after this call to re-establish the connection.

**Parameters**

• ws_sock – Websocket id returned by websocket_connect().

```c
static inline void websocket_init(void)
```

```c
struct websocket_request
```

#include <websocket.h> Websocket client connection request. This contains all the data that is needed when doing a Websocket connection request.

**Public Members**

```c
const char *host
Host of the Websocket server when doing HTTP handshakes.
```

```c
const char *url
URL of the Websocket.
```
**http_header_cb_t** optional_headers_cb

User supplied callback function to call when optional headers need to be sent. This can be NULL, in which case the optional_headers field in http_request is used. The idea of this optional_headers callback is to allow user to send more HTTP header data that is practical to store in allocated memory.

```c
const char **optional_headers
```

A NULL terminated list of any optional headers that should be added to the HTTP request. May be NULL. If the optional_headers_cb is specified, then this field is ignored.

**websocket_connect_cb_t** cb

User supplied callback function to call when a connection is established.

```c
const struct http_parser_settings *http_cb
```

User supplied list of callback functions if the calling application wants to know the parsing status or the HTTP fields during the handshake. This is optional parameter and normally not needed but is useful if the caller wants to know something about the fields that the server is sending.

```c
uint8_t *tmp_buf
```

User supplied buffer where HTTP connection data is stored

```c
size_t tmp_buf_len
```

Length of the user supplied temp buffer

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**Network Packet Capture**

- **Overview**
- **Sample usage**
- **API Reference**

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**Overview**  The **net_capture** API allows user to monitor the network traffic in one of the Zephyr network interfaces and send that traffic to external system for analysis. The monitoring can be setup either manually using **net-shell** or automatically by using the **net_capture** API.

**Sample usage**  See Network capture sample application and **Monitor Network Traffic** for details.

**API Reference**

**group** net_capture

Network packet capture support functions.

**Functions**

```c
int net_capture_setup(const char *remote_addr, const char *my_local_addr, const char *peer_addr, const struct device **dev)
```

Setup network packet capturing support.
Parameters

- **remote_addr** – The value tells the tunnel remote/outer endpoint IP address. The IP address can be either IPv4 or IPv6 address. This address is used to select the network interface where the tunnel is created.

- **my_local_addr** – The local/inner IP address of the tunnel. Can contain also port number which is used as UDP source port.

- **peer_addr** – The peer/inner IP address of the tunnel. Can contain also port number which is used as UDP destination port.

- **dev** – Network capture device. This is returned to the caller.

Returns

0 if ok, <0 if network packet capture setup failed

```c
static inline int net_capture_cleanup(const struct device *dev)
```

Cleanup network packet capturing support.

This should be called after the capturing is done and resources can be released.

Parameters

- **dev** – Network capture device. User must allocate using the `net_capture_setup()` function.

Returns

0 if ok, <0 if network packet capture cleanup failed

```c
static inline int net_capture_enable(const struct device *dev, struct net_if *iface)
```

Enable network packet capturing support.

This creates tunnel network interface where all the captured packets are pushed. The captured network packets are placed in UDP packets that are sent to tunnel peer.

Parameters

- **dev** – Network capture device
- **iface** – Network interface we are starting to capture packets.

Returns

0 if ok, <0 if network packet capture enable failed

```c
static inline bool net_capture_is_enabled(const struct device *dev)
```

Is network packet capture enabled or disabled.

Parameters

- **dev** – Network capture device

Returns

True if enabled, False if network capture is disabled.

```c
static inline int net_capture_disable(const struct device *dev)
```

Disable network packet capturing support.

Parameters

- **dev** – Network capture device

Returns

0 if ok, <0 if network packet capture disable failed

```c
static inline int net_capture_send(const struct device *dev, struct net_if *iface, struct net_pkt *pkt)
```

Send captured packet.

Parameters
Zephyr Project Documentation, Release 3.2.99

- `dev` – Network capture device
- `iface` – Network interface the packet is being sent
- `pkt` – The network packet that is sent

**Returns**

0 if ok, <0 if network packet capture send failed

### Network Buffer Management

#### Network Buffer

- **Overview**
- **Creating buffers**
- **Common Operations**
- **Reference Counting**
- **API Reference**

**Overview**  
Network buffers are a core concept of how the networking stack (as well as the Bluetooth stack) pass data around. The API for them is defined in `include/zephyr/net(buf.h)`.

**Creating buffers**  
Network buffers are created by first defining a pool of them:

```c
NET_BUF_POOL_DEFINE(pool_name, buf_count, buf_size, user_data_size, NULL);
```

The pool is a static variable, so if it's needed to be exported to another module a separate pointer is needed.

Once the pool has been defined, buffers can be allocated from it with:

```c
buf = net_buf_alloc(&pool_name, timeout);
```

There is no explicit initialization function for the pool or its buffers, rather this is done implicitly as `net_buf_alloc()` gets called.

If there is a need to reserve space in the buffer for protocol headers to be prepended later, it's possible to reserve this headroom with:

```c
net_buf_reserve(buf, headroom);
```

In addition to actual protocol data and generic parsing context, network buffers may also contain protocol-specific context, known as user data. Both the maximum data and user data capacity of the buffers is compile-time defined when declaring the buffer pool.

The buffers have native support for being passed through `kfifo` kernel objects. This is a very practical feature when the buffers need to be passed from one thread to another. However, since a `net_buf` may have a fragment chain attached to it, instead of using the `kfifo_put()` and `kfifo_get()` APIs, special `net_buf_put()` and `net_buf_get()` APIs must be used when passing buffers through FIFOs. These APIs ensure that the buffer chains stay intact. The same applies for passing buffers through a singly linked list, in which case the `net_buf_slist_put()` and `net_buf_slist_get()` functions must be used instead of `sys_slist_append()` and `sys_slist_get()`.

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6.2. Networking
Common Operations  The network buffer API provides some useful helpers for encoding and decoding data in the buffers. To fully understand these helpers it’s good to understand the basic names of operations used with them:

Add  Add data to the end of the buffer. Modifies the data length value while leaving the actual data pointer intact. Requires that there is enough tailroom in the buffer. Some examples of APIs for adding data:

```c
void *net_buf_add(struct net_buf *buf, size_t len);
void *net_buf_add_mem(struct net_buf *buf, const void *mem, size_t len);
uint8_t *net_buf_add_u8(struct net_buf *buf, uint8_t value);
void net_buf_add_le16(struct net_buf *buf, uint16_t value);
void net_buf_add_le32(struct net_buf *buf, uint32_t value);
```

Remove  Remove data from the end of the buffer. Modifies the data length value while leaving the actual data pointer intact. Some examples of APIs for removing data:

```c
void *net_buf_remove_mem(struct net_buf *buf, size_t len);
uint8_t net_buf_remove_u8(struct net_buf *buf);
uint16_t net_buf_remove_le16(struct net_buf *buf);
uint32_t net_buf_remove_le32(struct net_buf *buf);
```

Push  Prepend data to the beginning of the buffer. Modifies both the data length value as well as the data pointer. Requires that there is enough headroom in the buffer. Some examples of APIs for pushing data:

```c
void *net_buf_push(struct net_buf *buf, size_t len);
void *net_buf_push_mem(struct net_buf *buf, const void *mem, size_t len);
void net_buf_push_u8(struct net_buf *buf, uint8_t value);
void net_buf_push_le16(struct net_buf *buf, uint16_t value);
```

Pull  Remove data from the beginning of the buffer. Modifies both the data length value as well as the data pointer. Some examples of APIs for pulling data:

```c
void *net_buf_pull(struct net_buf *buf, size_t len);
void *net_buf_pull_mem(struct net_buf *buf, size_t len);
uint8_t net_buf_pull_u8(struct net_buf *buf);
uint16_t net_buf_pull_le16(struct net_buf *buf);
uint32_t net_buf_pull_le32(struct net_buf *buf);
```

The Add and Push operations are used when encoding data into the buffer, whereas the Remove and Pull operations are used when decoding data from a buffer.

Reference Counting  Each network buffer is reference counted. The buffer is initially acquired from a free buffers pool by calling `net_buf_alloc()`, resulting in a buffer with reference count 1. The reference count can be incremented with `net_buf_ref()` or decremented with `net_buf_unref()`. When the count drops to zero the buffer is automatically placed back to the free buffers pool.

API Reference

`group net_buf`

Network buffer library.
Defines

**NET_BUF_SIMPLE_DEFINE(_name, _size)**

Define a `net_buf_simple` stack variable.

This is a helper macro which is used to define a `net_buf_simple` object on the stack.

**Parameters**

- `_name` – Name of the `net_buf_simple` object.
- `_size` – Maximum data storage for the buffer.

**NET_BUF_SIMPLE_DEFINE_STATIC(_name, _size)**

Define a static `net_buf_simple` variable.

This is a helper macro which is used to define a static `net_buf_simple` object.

**Parameters**

- `_name` – Name of the `net_buf_simple` object.
- `_size` – Maximum data storage for the buffer.

**NET_BUF_SIMPLE(_size)**

Define a `net_buf_simple` stack variable and get a pointer to it.

This is a helper macro which is used to define a `net_buf_simple` object on the stack and the get a pointer to it as follows:

```c
struct net_buf_simple *my_buf = NET_BUF_SIMPLE(10);
```

After creating the object it needs to be initialized by calling `net_buf_simple_init()`.

**Parameters**

- `_size` – Maximum data storage for the buffer.

**Returns**

Pointer to stack-allocated `net_buf_simple` object.

**NET_BUF_FRAGS**

Flag indicating that the buffer has associated fragments. Only used internally by the buffer handling code while the buffer is inside a FIFO, meaning this never needs to be explicitly set or unset by the `net_buf` API user. As long as the buffer is outside of a FIFO, i.e. in practice always for the user for this API, the buf->frags pointer should be used instead.

**NET_BUF_EXTERNAL_DATA**

Flag indicating that the buffer’s associated data pointer points to externally allocated memory. Therefore once ref goes down to zero, the pointed data will not need to be deallocated. This never needs to be explicitly set or unset by the `net_buf` API user. Such `net_buf` is exclusively instantiated via `net_buf_alloc_with_data()` function. Reference count mechanism however will behave the same way, and ref count going to 0 will free the `net_buf` but no the data pointer in it.

**NET_BUF_POOL_HEAP_DEFINE(_name, _count, _ud_size, _destroy)**

Define a new pool for buffers using the heap for the data.

Defines a `net_buf_pool` struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through `net_buf_alloc`. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

The data payload of the buffers will be allocated from the heap using `k_malloc`, so `CONFIG_HEAP_MEM_POOL_SIZE` must be set to a positive value. This kind of pool does not
support blocking on the data allocation, so the timeout passed to net_buf_alloc will be always treated as K_NO_WAIT when trying to allocate the data. This means that allocation failures, i.e. NULL returns, must always be handled cleanly.

If provided with a custom destroy callback, this callback is responsible for eventually calling net_buf_destroy() to complete the process of returning the buffer to the pool.

Parameters

- _name – Name of the pool variable.
- _count – Number of buffers in the pool.
- _ud_size – User data space to reserve per buffer.
- _destroy – Optional destroy callback when buffer is freed.

NET_BUF_POOL_FIXED_DEFINE(_name, _count, _data_size, _ud_size, _destroy)
Define a new pool for buffers based on fixed-size data.

Defines a net_buf_pool struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through net_buf_alloc. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

The data payload of the buffers will be allocated from a byte array of fixed sized chunks. This kind of pool does not support blocking on the data allocation, so the timeout passed to net_buf_alloc will be always treated as K_NO_WAIT when trying to allocate the data. This means that allocation failures, i.e. NULL returns, must always be handled cleanly.

If provided with a custom destroy callback, this callback is responsible for eventually calling net_buf_destroy() to complete the process of returning the buffer to the pool.

Parameters

- _name – Name of the pool variable.
- _count – Number of buffers in the pool.
- _data_size – Total amount of memory available for data payloads.
- _ud_size – User data space to reserve per buffer.

NET_BUF_POOL_VAR_DEFINE(_name, _count, _data_size, _ud_size, _destroy)
Define a new pool for buffers with variable size payloads.

Defines a net_buf_pool struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through net_buf_alloc. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

The data payload of the buffers will be based on a memory pool from which variable size payloads may be allocated.

If provided with a custom destroy callback, this callback is responsible for eventually calling net_buf_destroy() to complete the process of returning the buffer to the pool.

Parameters

- _name – Name of the pool variable.
- _count – Number of buffers in the pool.
- _data_size – Total amount of memory available for data payloads.
- _ud_size – User data space to reserve per buffer.
NET_BUF_POOL_DEFINE(_name, _count, _size, _ud_size, _destroy)

Define a new pool for buffers.

Defines a net_buf_pool struct and the necessary memory storage (array of structs) for the needed amount of buffers. After this, the buffers can be accessed from the pool through net_buf_alloc. The pool is defined as a static variable, so if it needs to be exported outside the current module this needs to happen with the help of a separate pointer rather than an extern declaration.

If provided with a custom destroy callback this callback is responsible for eventually calling net_buf_destroy() to complete the process of returning the buffer to the pool.

Parameters

- _name – Name of the pool variable.
- _count – Number of buffers in the pool.
- _size – Maximum data size for each buffer.
- _ud_size – Amount of user data space to reserve.
- _destroy – Optional destroy callback when buffer is freed.

Typedefs

typedef struct net_buf *(*net_buf_allocator_cb)(k_timeout_t timeout, void *user_data)

Network buffer allocator callback.

The allocator callback is called when net_buf_append_bytes needs to allocate a new net_buf.

Param timeout
Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.

Param user_data
The user data given in net_buf_append_bytes call.

Return
pointer to allocated net_buf or NULL on error.

Functions

static inline void net_buf_simple_init(struct net_buf_simple *buf, size_t reserve_head)

Initialize a net_buf_simple object.

This needs to be called after creating a net_buf_simple object using the NET_BUF_SIMPLE macro.

Parameters

- buf – Buffer to initialize.
- reserve_head – Headroom to reserve.

void net_buf_simple_init_with_data(struct net_buf_simple *buf, void *data, size_t size)

Initialize a net_buf_simple object with data.

Initialized buffer object with external data.

Parameters
• buf – Buffer to initialize.
• data – External data pointer
• size – Amount of data the pointed data buffer if able to fit.

static inline void net_buf_simple_reset(struct net_buf_simple *buf)

Reset buffer.
Reset buffer data so it can be reused for other purposes.

Parameters
• buf – Buffer to reset.

void net_buf_simple_clone(const struct net_buf_simple *original, struct net_buf_simple *clone)

Clone buffer state, using the same data buffer.
Initializes a buffer to point to the same data as an existing buffer. Allows operations on the
same data without altering the length and offset of the original.

Parameters
• original – Buffer to clone.
• clone – The new clone.

void *net_buf_simple_add(struct net_buf_simple *buf, size_t len)

Prepare data to be added at the end of the buffer.
Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• len – Number of bytes to increment the length with.

Returns
The original tail of the buffer.

void *net_buf_simple_add_mem(struct net_buf_simple *buf, const void *mem, size_t len)

Copy given number of bytes from memory to the end of the buffer.
Increments the data length of the buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• mem – Location of data to be added.
• len – Length of data to be added

Returns
The original tail of the buffer.

uint8_t *net_buf_simple_add_u8(struct net_buf_simple *buf, uint8_t val)

Add (8-bit) byte at the end of the buffer.
Increments the data length of the buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – byte value to be added.

Returns
Pointer to the value added
void net_buf_simple_add_le16(struct net_buf_simple *buf, uint16_t val)
Add 16-bit value at the end of the buffer.

Adds 16-bit value in little endian format at the end of buffer. Increments the data length of a
buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 16-bit value to be added.

void net_buf_simple_add_be16(struct net_buf_simple *buf, uint16_t val)
Add 16-bit value at the end of the buffer.

Adds 16-bit value in big endian format at the end of buffer. Increments the data length of a
buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 16-bit value to be added.

void net_buf_simple_add_le24(struct net_buf_simple *buf, uint32_t val)
Add 24-bit value at the end of the buffer.

Adds 24-bit value in little endian format at the end of buffer. Increments the data length of a
buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be added.

void net_buf_simple_add_be24(struct net_buf_simple *buf, uint32_t val)
Add 24-bit value at the end of the buffer.

Adds 24-bit value in big endian format at the end of buffer. Increments the data length of a
buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 24-bit value to be added.

void net_buf_simple_add_le32(struct net_buf_simple *buf, uint32_t val)
Add 32-bit value at the end of the buffer.

Adds 32-bit value in little endian format at the end of buffer. Increments the data length of a
buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• val – 32-bit value to be added.
void net_buf_simple_add_le48(struct net_buf_simple *buf, uint64_t val)
Add 48-bit value at the end of the buffer.

Add 48-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

• buf – Buffer to update.
• val – 48-bit value to be added.

void net_buf_simple_add_be48(struct net_buf_simple *buf, uint64_t val)
Add 48-bit value at the end of the buffer.

Add 48-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

• buf – Buffer to update.
• val – 48-bit value to be added.

void net_buf_simple_add_le64(struct net_buf_simple *buf, uint64_t val)
Add 64-bit value at the end of the buffer.

Add 64-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

• buf – Buffer to update.
• val – 64-bit value to be added.

void net_buf_simple_add_be64(struct net_buf_simple *buf, uint64_t val)
Add 64-bit value at the end of the buffer.

Add 64-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

• buf – Buffer to update.
• val – 64-bit value to be added.

void *net_buf_simple_remove_mem(struct net_buf_simple *buf, size_t len)
Remove data from the end of the buffer.

Removes data from the end of the buffer by modifying the buffer length.

Parameters

• buf – Buffer to update.
• len – Number of bytes to remove.

Returns

New end of the buffer data.

uint8_t net_buf_simple_remove_u8(struct net_buf_simple *buf)
Remove a 8-bit value from the end of the buffer.

Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 8-bit values.

Parameters

• buf – A valid pointer on a buffer.
Returns
The 8-bit removed value

uint16_t net_buf_simple_remove_le16(struct net_buf_simple *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 16-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.

uint16_t net_buf_simple_remove_be16(struct net_buf_simple *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 16-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from big endian to host endian.

uint32_t net_buf_simple_remove_le24(struct net_buf_simple *buf)
Remove and convert 24 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 24-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
24-bit value converted from little endian to host endian.

uint32_t net_buf_simple_remove_be24(struct net_buf_simple *buf)
Remove and convert 24 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 24-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
24-bit value converted from big endian to host endian.

uint32_t net_buf_simple_remove_le32(struct net_buf_simple *buf)
Remove and convert 32 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 32-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
32-bit value converted from little endian to host endian.
uint32_t net_buf_simple_remove_be32(struct net_buf_simple *buf)
Remove and convert 32 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 32-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
32-bit value converted from big endian to host endian.

uint64_t net_buf_simple_remove_le48(struct net_buf_simple *buf)
Remove and convert 48 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 48-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from little endian to host endian.

uint64_t net_buf_simple_remove_be48(struct net_buf_simple *buf)
Remove and convert 48 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 48-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from big endian to host endian.

uint64_t net_buf_simple_remove_le64(struct net_buf_simple *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 64-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from little endian to host endian.

uint64_t net_buf_simple_remove_be64(struct net_buf_simple *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_simple_remove_mem(), but a helper for operating on 64-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from big endian to host endian.

void *net_buf_simple_push(struct net_buf_simple *buf, size_t len)
Prepare data to be added to the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.
Parameters

- buf – Buffer to update.
- len – Number of bytes to add to the beginning.

Returns
The new beginning of the buffer data.

```c
void *net_buf_simple_push_mem(
    struct net_buf_simple *buf,
    const void *mem,
    size_t len)
```
Copy given number of bytes from memory to the start of the buffer.

Parameters

- buf – Buffer to update.
- mem – Location of data to be added.
- len – Length of data to be added.

Returns
The new beginning of the buffer data.

```c
void net_buf_simple_push_le16(
    struct net_buf_simple *buf,
    uint16_t val)
```
Push 16-bit value to the beginning of the buffer.

Parameters

- buf – Buffer to update.
- val – 16-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_be16(
    struct net_buf_simple *buf,
    uint16_t val)
```
Push 16-bit value to the beginning of the buffer.

Parameters

- buf – Buffer to update.
- val – 16-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_u8(
    struct net_buf_simple *buf,
    uint8_t val)
```
Push 8-bit value to the beginning of the buffer.

Parameters

- buf – Buffer to update.
- val – 8-bit value to be pushed to the buffer.

```c
void net_buf_simple_push_le24(
    struct net_buf_simple *buf,
    uint32_t val)
```
Push 24-bit value to the beginning of the buffer.

Parameters

- buf – Buffer to update.
- val – 24-bit value to be pushed to the buffer.
void net_buf_simple_push_be24(struct net_buf_simple *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.

Adds 24-bit value in big endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 24-bit value to be pushed to the buffer.

void net_buf_simple_push_le32(struct net_buf_simple *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.

Adds 32-bit value in little endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 32-bit value to be pushed to the buffer.

void net_buf_simple_push_be32(struct net_buf_simple *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.

Adds 32-bit value in big endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 32-bit value to be pushed to the buffer.

void net_buf_simple_push_le48(struct net_buf_simple *buf, uint64_t val)
Push 48-bit value to the beginning of the buffer.

Adds 48-bit value in little endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 48-bit value to be pushed to the buffer.

void net_buf_simple_push_be48(struct net_buf_simple *buf, uint64_t val)
Push 48-bit value to the beginning of the buffer.

Adds 48-bit value in big endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 48-bit value to be pushed to the buffer.

void net_buf_simple_push_le64(struct net_buf_simple *buf, uint64_t val)
Push 64-bit value to the beginning of the buffer.

Adds 64-bit value in little endian format to the beginning of the buffer.

Parameters

• buf – Buffer to update.
• val – 64-bit value to be pushed to the buffer.

void net_buf_simple_push_be64(struct net_buf_simple *buf, uint64_t val)
Push 64-bit value to the beginning of the buffer.

Adds 64-bit value in big endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 64-bit value to be pushed to the buffer.

```c
void *net_buf_simple_pull(struct net_buf_simple *buf, size_t len)
```

Removes data from the beginning of the buffer.

Parameters
• buf – Buffer to update.
• len – Number of bytes to remove.

Returns
New beginning of the buffer data.

```c
void *net_buf_simple_pull_mem(struct net_buf_simple *buf, size_t len)
```

Removes data from the beginning of the buffer.

Parameters
• buf – Buffer to update.
• len – Number of bytes to remove.

Returns
Pointer to the old location of the buffer data.

```c
uint8_t net_buf_simple_pull_u8(struct net_buf_simple *buf)
```

Remove a 8-bit value from the beginning of the buffer.

Same idea as with `net_buf_simple_pull()`, but a helper for operating on 8-bit values.

Parameters
• buf – A valid pointer on a buffer.

Returns
The 8-bit removed value

```c
uint16_t net_buf_simple_pull_le16(struct net_buf_simple *buf)
```

Remove and convert 16 bits from the beginning of the buffer.

Same idea as with `net_buf_simple_pull()`, but a helper for operating on 16-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.

```c
uint16_t net_buf_simple_pull_be16(struct net_buf_simple *buf)
```

Remove and convert 16 bits from the beginning of the buffer.

Same idea as with `net_buf_simple_pull()`, but a helper for operating on 16-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
16-bit value converted from big endian to host endian.
uint32_t net_buf_simple_pull_le24(struct net_buf_simple *buf)
Remove and convert 24 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 24-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
24-bit value converted from little endian to host endian.

uint32_t net_buf_simple_pull_be24(struct net_buf_simple *buf)
Remove and convert 24 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 24-bit big endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
24-bit value converted from big endian to host endian.

uint32_t net_buf_simple_pull_le32(struct net_buf_simple *buf)
Remove and convert 32 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 32-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
32-bit value converted from little endian to host endian.

uint32_t net_buf_simple_pull_be32(struct net_buf_simple *buf)
Remove and convert 32 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 32-bit big endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
32-bit value converted from big endian to host endian.

uint64_t net_buf_simple_pull_le48(struct net_buf_simple *buf)
Remove and convert 48 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 48-bit little endian data.

**Parameters**
- buf – A valid pointer on a buffer.

**Returns**
48-bit value converted from little endian to host endian.

uint64_t net_buf_simple_pull_be48(struct net_buf_simple *buf)
Remove and convert 48 bits from the beginning of the buffer.

Same idea as with net_buf_simple_pull(), but a helper for operating on 48-bit big endian data.

**Parameters**
- buf – A valid pointer on a buffer.
Returns
48-bit value converted from big endian to host endian.

uint64_t net_buf_simple_pull_le64(struct net_buf_simple *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 64-bit little endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from little endian to host endian.

uint64_t net_buf_simple_pull_be64(struct net_buf_simple *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_simple_pull(), but a helper for operating on 64-bit big endian data.

Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from big endian to host endian.

static inline uint8_t *net_buf_simple_tail(struct net_buf_simple *buf)
Get the tail pointer for a buffer.
Get a pointer to the end of the data in a buffer.

Parameters
• buf – Buffer.

Returns
Tail pointer for the buffer.

size_t net_buf_simple_headroom(struct net_buf_simple *buf)
Check buffer headroom.
Check how much free space there is in the beginning of the buffer.
buf A valid pointer on a buffer

Returns
Number of bytes available in the beginning of the buffer.

size_t net_buf_simple_tailroom(struct net_buf_simple *buf)
Check buffer tailroom.
Check how much free space there is at the end of the buffer.

Parameters
• buf – A valid pointer on a buffer

Returns
Number of bytes available at the end of the buffer.

uint16_t net_buf_simple_max_len(struct net_buf_simple *buf)
Check maximum net_buf_simple::len value.
This value is depending on the number of bytes being reserved as headroom.

Parameters
• buf – A valid pointer on a buffer
Returns
Number of bytes usable behind the \texttt{net\_buf\_simple::data} pointer.

\begin{verbatim}
static inline void net_buf_simple_save(struct net_buf_simple *buf, struct net_buf_simple_state *state)

Save the parsing state of a buffer.

Saves the parsing state of a buffer so it can be restored later.

Parameters
\begin{itemize}
  \item buf – Buffer from which the state should be saved.
  \item state – Storage for the state.
\end{itemize}
\end{verbatim}

\begin{verbatim}
static inline void net_buf_simple_restore(struct net_buf_simple *buf, struct net_buf_simple_state *state)

Restore the parsing state of a buffer.

Restores the parsing state of a buffer from a state previously stored by \texttt{net\_buf\_simple\_save()}.

Parameters
\begin{itemize}
  \item buf – Buffer to which the state should be restored.
  \item state – Stored state.
\end{itemize}
\end{verbatim}

\begin{verbatim}
struct net_buf_pool *net_buf_pool_get(int id)

Looks up a pool based on its ID.

Parameters
\begin{itemize}
  \item id – Pool ID (e.g. from buf->pool_id).
\end{itemize}

Returns
Pointer to pool.
\end{verbatim}

\begin{verbatim}
int net_buf_id(struct net_buf *buf)

Get a zero-based index for a buffer.

This function will translate a buffer into a zero-based index, based on its placement in its buffer pool. This can be useful if you want to associate an external array of meta-data contexts with the buffers of a pool.

Parameters
\begin{itemize}
  \item buf – Network buffer.
\end{itemize}

Returns
Zero-based index for the buffer.
\end{verbatim}

\begin{verbatim}
struct net_buf *net_buf_alloc_fixed(struct net_buf_pool *pool, k_timeout_t timeout)

Allocate a new fixed buffer from a pool.

Parameters
\begin{itemize}
  \item pool – Which pool to allocate the buffer from.
  \item timeout – Affects the action taken should the pool be empty. If K\_NO\_WAIT, then return immediately. If K\_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it's still possible for \texttt{net\_buf\_alloc()} to fail (return NULL) even if it was given K\_FOREVER.
\end{itemize}

Returns
New buffer or NULL if out of buffers.
static inline struct net_buf *net_buf_alloc(struct net_buf_pool *pool, k_timeout_t timeout)

**Parameters**
- `pool` – Which pool to allocate the buffer from.
- `timeout` – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it’s still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

**Returns**
New buffer or NULL if out of buffers.

struct net_buf *net_buf_alloc_len(struct net_buf_pool *pool, size_t size, k_timeout_t timeout)

Allocate a new variable length buffer from a pool.

**Parameters**
- `pool` – Which pool to allocate the buffer from.
- `size` – Amount of data the buffer must be able to fit.
- `timeout` – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it’s still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

**Returns**
New buffer or NULL if out of buffers.

struct net_buf *net_buf_alloc_with_data(struct net_buf_pool *pool, void *data, size_t size, k_timeout_t timeout)

Allocate a new buffer from a pool but with external data pointer.

Allocate a new buffer from a pool, where the data pointer comes from the user and not from the pool.

**Parameters**
- `pool` – Which pool to allocate the buffer from.
- `data` – External data pointer
- `size` – Amount of data the pointed data buffer if able to fit.
- `timeout` – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout. Note that some types of data allocators do not support blocking (such as the HEAP type). In this case it’s still possible for `net_buf_alloc()` to fail (return NULL) even if it was given K_FOREVER.

**Returns**
New buffer or NULL if out of buffers.

struct net_buf *net_buf_get(struct k_fifo *fifo, k_timeout_t timeout)

Get a buffer from a FIFO.

This function is NOT thread-safe if the buffers in the FIFO contain fragments.

**Parameters**
- `fifo` – Which FIFO to take the buffer from.
- `timeout` – Affects the action taken should the FIFO be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.
Returns

New buffer or NULL if the FIFO is empty.

static inline void net_buf_destroy(struct net_buf *buf)
Destroy buffer from custom destroy callback.

This helper is only intended to be used from custom destroy callbacks. If no custom destroy
callback is given to NET_BUF_POOL_*_DEFINE() then there is no need to use this API.

Parameters

• buf – Buffer to destroy.

void net_buf_reset(struct net_buf *buf)
Reset buffer.

Reset buffer data and flags so it can be reused for other purposes.

Parameters

• buf – Buffer to reset.

void net_buf_simple_reserve(struct net_buf_simple *buf, size_t reserve)
Initialize buffer with the given headroom.

The buffer is not expected to contain any data when this API is called.

Parameters

• buf – Buffer to initialize.
• reserve – How much headroom to reserve.

void net_buf_slist_put(sys_slist_t *list, struct net_buf *buf)
Put a buffer into a list.

If the buffer contains follow-up fragments this function will take care of inserting them as well
into the list.

Parameters

• list – Which list to append the buffer to.
• buf – Buffer.

struct net_buf *net_buf_slist_get(sys_slist_t *list)
Get a buffer from a list.

If the buffer had any fragments, these will automatically be recovered from the list as well
and be placed to the buffer's fragment list.

Parameters

• list – Which list to take the buffer from.

Returns

New buffer or NULL if the FIFO is empty.

void net_buf_put(struct k_fifo *fifo, struct net_buf *buf)
Put a buffer to the end of a FIFO.

If the buffer contains follow-up fragments this function will take care of inserting them as well
into the FIFO.

Parameters

• fifo – Which FIFO to put the buffer to.
• buf – Buffer.
void net_buf_unref(struct net_buf *buf)
Decrments the reference count of a buffer.
The buffer is put back into the pool if the reference count reaches zero.

Parameters
• buf – A valid pointer on a buffer

struct net_buf *net_buf_ref(struct net_buf *buf)
Increment the reference count of a buffer.

Parameters
• buf – A valid pointer on a buffer

Returns
the buffer newly referenced

struct net_buf *net_buf_clone(struct net_buf *buf, k_timeout_t timeout)
Clone buffer.
Duplicate given buffer including any data and headers currently stored.

Parameters
• buf – A valid pointer on a buffer
• timeout – Affects the action taken should the pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait until the specified timeout.

Returns
Cloned buffer or NULL if out of buffers.

static inline void *net_buf_user_data(const struct net_buf *buf)
Get a pointer to the user data of a buffer.

Parameters
• buf – A valid pointer on a buffer

Returns
Pointer to the user data of the buffer.

static inline void net_buf_reserve(struct net_buf *buf, size_t reserve)
Initialize buffer with the given headroom.
The buffer is not expected to contain any data when this API is called.

Parameters
• buf – Buffer to initialize.
• reserve – How much headroom to reserve.

static inline void *net_buf_add(struct net_buf *buf, size_t len)
Prepare data to be added at the end of the buffer.
Increments the data length of a buffer to account for more data at the end.

Parameters
• buf – Buffer to update.
• len – Number of bytes to increment the length with.

Returns
The original tail of the buffer.
static inline void *net_buf_add_mem(struct net_buf *buf, const void *mem, size_t len)
Copies the given number of bytes to the end of the buffer.
Increment the data length of the buffer to account for more data at the end.

**Parameters**
- **buf** – Buffer to update.
- **mem** – Location of data to be added.
- **len** – Length of data to be added

**Returns**
The original tail of the buffer.

static inline uint8_t *net_buf_add_u8(struct net_buf *buf, uint8_t val)
Add (8-bit) byte at the end of the buffer.
Increment the data length of the buffer to account for more data at the end.

**Parameters**
- **buf** – Buffer to update.
- **val** – byte value to be added.

**Returns**
Pointer to the value added

static inline void net_buf_add_le16(struct net_buf *buf, uint16_t val)
Add 16-bit value at the end of the buffer.
Add 16-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**
- **buf** – Buffer to update.
- **val** – 16-bit value to be added.

static inline void net_buf_add_be16(struct net_buf *buf, uint16_t val)
Add 16-bit value at the end of the buffer.
Add 16-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**
- **buf** – Buffer to update.
- **val** – 16-bit value to be added.

static inline void net_buf_add_le24(struct net_buf *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Add 24-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

**Parameters**
- **buf** – Buffer to update.
- **val** – 24-bit value to be added.

static inline void net_buf_add_be24(struct net_buf *buf, uint32_t val)
Add 24-bit value at the end of the buffer.
Add 24-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.
Parameters

- buf – Buffer to update.
- val – 24-bit value to be added.

static inline void net_buf_add_le32(struct net_buf *buf, uint32_t val)
Add 32-bit value at the end of the buffer.
Adds 32-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

- buf – Buffer to update.
- val – 32-bit value to be added.

static inline void net_buf_add_be32(struct net_buf *buf, uint32_t val)
Add 32-bit value at the end of the buffer.
Adds 32-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

- buf – Buffer to update.
- val – 48-bit value to be added.

static inline void net_buf_add_le48(struct net_buf *buf, uint64_t val)
Add 48-bit value at the end of the buffer.
Adds 48-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

- buf – Buffer to update.
- val – 48-bit value to be added.

static inline void net_buf_add_be48(struct net_buf *buf, uint64_t val)
Add 48-bit value at the end of the buffer.
Adds 48-bit value in big endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.

Parameters

- buf – Buffer to update.
- val – 64-bit value to be added.

static inline void net_buf_add_le64(struct net_buf *buf, uint64_t val)
Add 64-bit value at the end of the buffer.
Adds 64-bit value in little endian format at the end of buffer. Increments the data length of a buffer to account for more data at the end.
Parameters

- buf – Buffer to update.
- val – 64-bit value to be added.

static inline void *net_buf_remove_mem(struct net_buf *buf, size_t len)
Remove data from the end of the buffer.
Removes data from the end of the buffer by modifying the buffer length.

Parameters

- buf – Buffer to update.
- len – Number of bytes to remove.

Returns

New end of the buffer data.

static inline uint8_t net_buf_remove_u8(struct net_buf *buf)
Remove a 8-bit value from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 8-bit values.

Parameters

- buf – A valid pointer on a buffer.

Returns

The 8-bit removed value

static inline uint16_t net_buf_remove_le16(struct net_buf *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 16-bit little endian data.

Parameters

- buf – A valid pointer on a buffer.

Returns

16-bit value converted from little endian to host endian.

static inline uint16_t net_buf_remove_be16(struct net_buf *buf)
Remove and convert 16 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 16-bit big endian data.

Parameters

- buf – A valid pointer on a buffer.

Returns

16-bit value converted from big endian to host endian.

static inline uint32_t net_buf_remove_be24(struct net_buf *buf)
Remove and convert 24 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 24-bit big endian data.

Parameters

- buf – A valid pointer on a buffer.

Returns

24-bit value converted from big endian to host endian.
static inline uint32_t net_buf_remove_le24(struct net_buf *buf)
    Remove and convert 24 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 24-bit little endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    24-bit value converted from little endian to host endian.

static inline uint32_t net_buf_remove_le32(struct net_buf *buf)
    Remove and convert 32 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 32-bit little endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    32-bit value converted from little endian to host endian.

static inline uint32_t net_buf_remove_be32(struct net_buf *buf)
    Remove and convert 32 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 32-bit big endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    32-bit value converted from big endian to host endian.

static inline uint64_t net_buf_remove_le48(struct net_buf *buf)
    Remove and convert 48 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 48-bit little endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    48-bit value converted from little endian to host endian.

static inline uint64_t net_buf_remove_be48(struct net_buf *buf)
    Remove and convert 48 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 48-bit big endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    48-bit value converted from big endian to host endian.

static inline uint64_t net_buf_remove_le64(struct net_buf *buf)
    Remove and convert 64 bits from the end of the buffer.
    Same idea as with net_buf_remove_mem(), but a helper for operating on 64-bit little endian data.
    Parameters
    • buf – A valid pointer on a buffer.
    Returns
    64-bit value converted from little endian to host endian.
Parameters
• buf – A valid pointer on a buffer.

Returns
64-bit value converted from little endian to host endian.

static inline uint64_t net_buf_remove_be64(struct net_buf *buf)
Remove and convert 64 bits from the end of the buffer.
Same idea as with net_buf_remove_mem(), but a helper for operating on 64-bit big endian data.

Parameters
• buf – A valid pointer on a buffer

Returns
64-bit value converted from big endian to host endian.

static inline void *net_buf_push(struct net_buf *buf, size_t len)
Prepare data to be added at the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters
• buf – Buffer to update.
• len – Number of bytes to add to the beginning.

Returns
The new beginning of the buffer data.

static inline void *net_buf_push_mem(struct net_buf *buf, const void *mem, size_t len)
Copies the given number of bytes to the start of the buffer.
Modifies the data pointer and buffer length to account for more data in the beginning of the buffer.

Parameters
• buf – Buffer to update.
• mem – Location of data to be added.
• len – Length of data to be added.

Returns
The new beginning of the buffer data.

static inline void net_buf_push_u8(struct net_buf *buf, uint8_t val)
Push 8-bit value to the beginning of the buffer.
Adds 8-bit value the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 8-bit value to be pushed to the buffer.

static inline void net_buf_push_le16(struct net_buf *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.
Adds 16-bit value in little endian format to the beginning of the buffer.

Parameters
• buf – Buffer to update.
• val – 16-bit value to be pushed to the buffer.

static inline void net_buf_push_be16(struct net_buf *buf, uint16_t val)
Push 16-bit value to the beginning of the buffer.

Adds 16-bit value in big endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 16-bit value to be pushed to the buffer.

static inline void net_buf_push_le24(struct net_buf *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.

Adds 24-bit value in little endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 24-bit value to be pushed to the buffer.

static inline void net_buf_push_be24(struct net_buf *buf, uint32_t val)
Push 24-bit value to the beginning of the buffer.

Adds 24-bit value in big endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 24-bit value to be pushed to the buffer.

static inline void net_buf_push_le32(struct net_buf *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.

Adds 32-bit value in little endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 32-bit value to be pushed to the buffer.

static inline void net_buf_push_be32(struct net_buf *buf, uint32_t val)
Push 32-bit value to the beginning of the buffer.

Adds 32-bit value in big endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 32-bit value to be pushed to the buffer.

static inline void net_buf_push_le48(struct net_buf *buf, uint64_t val)
Push 48-bit value to the beginning of the buffer.

Adds 48-bit value in little endian format to the beginning of the buffer.

**Parameters**

• buf – Buffer to update.
• val – 48-bit value to be pushed to the buffer.
static inline void net_buf_push_be48(struct net_buf *buf, uint64_t val)
    Push 48-bit value in big endian format to the beginning of the buffer.
Parameters
• buf – Buffer to update.
• val – 48-bit value to be pushed to the buffer.

static inline void net_buf_push_le64(struct net_buf *buf, uint64_t val)
    Push 64-bit value to the beginning of the buffer.
    Adds 64-bit value in little endian format to the beginning of the buffer.
Parameters
• buf – Buffer to update.
• val – 64-bit value to be pushed to the buffer.

static inline void net_buf_push_be64(struct net_buf *buf, uint64_t val)
    Push 64-bit value to the beginning of the buffer.
    Adds 64-bit value in big endian format to the beginning of the buffer.
Parameters
• buf – Buffer to update.
• val – 64-bit value to be pushed to the buffer.

static inline void *net_buf_pull(struct net_buf *buf, size_t len)
    Remove data from the beginning of the buffer.
Parameters
• buf – Buffer to update.
• len – Number of bytes to remove.
Returns
New beginning of the buffer data.

static inline void *net_buf_pull_mem(struct net_buf *buf, size_t len)
    Remove data from the beginning of the buffer by modifying the data pointer and buffer length.
Parameters
• buf – Buffer to update.
• len – Number of bytes to remove.
Returns
Pointer to the old beginning of the buffer data.

static inline uint8_t net_buf_pull_u8(struct net_buf *buf)
    Remove a 8-bit value from the beginning of the buffer.
    Same idea as with net_buf_pull(), but a helper for operating on 8-bit values.
Parameters
• buf – A valid pointer on a buffer.
Returns
The 8-bit removed value

\[
\text{static inline uint16_t net_buf_pull_le16(struct net_buf *buf)}
\]
Remove and convert 16 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 16-bit little endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.

Returns
16-bit value converted from little endian to host endian.

\[
\text{static inline uint16_t net_buf_pull_be16(struct net_buf *buf)}
\]
Remove and convert 16 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 16-bit big endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.

Returns
24-bit value converted from little endian to host endian.

\[
\text{static inline uint32_t net_buf_pull_le24(struct net_buf *buf)}
\]
Remove and convert 24 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 24-bit little endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.

Returns
24-bit value converted from big endian to host endian.

\[
\text{static inline uint32_t net_buf_pull_be24(struct net_buf *buf)}
\]
Remove and convert 24 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 24-bit big endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.

Returns
32-bit value converted from little endian to host endian.

\[
\text{static inline uint32_t net_buf_pull_le32(struct net_buf *buf)}
\]
Remove and convert 32 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 32-bit little endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.

Returns
32-bit value converted from big endian to host endian.

\[
\text{static inline uint32_t net_buf_pull_be32(struct net_buf *buf)}
\]
Remove and convert 32 bits from the beginning of the buffer.
Same idea as with \text{net_buf_pull()}, but a helper for operating on 32-bit big endian data.

Parameters
- \text{buf} – A valid pointer on a buffer.
Returns
32-bit value converted from big endian to host endian.
static inline uint64_t net_buf_pull_le48(struct net_buf *buf)
Remove and convert 48 bits from the beginning of the buffer.
Same idea as with net_buf_pull(), but a helper for operating on 48-bit little endian data.
Parameters
• buf – A valid pointer on a buffer.

Returns
48-bit value converted from little endian to host endian.
static inline uint64_t net_buf_pull_be48(struct net_buf *buf)
Remove and convert 48 bits from the beginning of the buffer.
Same idea as with net_buf_pull(), but a helper for operating on 48-bit big endian data.
Parameters
• buf – A valid pointer on a buffer

Returns
64-bit value converted from big endian to host endian.
static inline uint64_t net_buf_pull_le64(struct net_buf *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_pull(), but a helper for operating on 64-bit little endian data.
Parameters
• buf – A valid pointer on a buffer

Returns
64-bit value converted from little endian to host endian.
static inline uint64_t net_buf_pull_be64(struct net_buf *buf)
Remove and convert 64 bits from the beginning of the buffer.
Same idea as with net_buf_pull(), but a helper for operating on 64-bit big endian data.
Parameters
• buf – A valid pointer on a buffer

Returns
Check buffer tailroom.
static inline size_t net_buf_tailroom(struct net_buf *buf)
Check how much free space there is at the end of the buffer.
Parameters
• buf – A valid pointer on a buffer

Returns
Number of bytes available at the end of the buffer.
static inline size_t net_buf_headroom(struct net_buf *buf)
Check buffer headroom.
Check how much free space there is in the beginning of the buffer.
buf A valid pointer on a buffer
Returns
Number of bytes available in the beginning of the buffer.

static inline uint16_t net_buf_max_len(struct net_buf *buf)
Check maximum net_buf::len value.
This value is depending on the number of bytes being reserved as headroom.

Parameters
• buf – A valid pointer on a buffer

Returns
Number of bytes usable behind the net_buf::data pointer.

static inline uint8_t *net_buf_tail(struct net_buf *buf)
Get the tail pointer for a buffer.
Get a pointer to the end of the data in a buffer.

Parameters
• buf – Buffer.

Returns
Tail pointer for the buffer.

struct net_buf *net_buf_frag_last(struct net_buf *frags)
Find the last fragment in the fragment list.

Returns
Pointer to last fragment in the list.

void net_buf_frag_insert(struct net_buf *parent, struct net_buf *frag)
Insert a new fragment to a chain of bufs.
Insert a new fragment into the buffer fragments list after the parent.
Note: This function takes ownership of the fragment reference so the caller is not required to unref.

Parameters
• parent – Parent buffer/fragment.
• frag – Fragment to insert.

struct net_buf *net_buf_frag_add(struct net_buf *head, struct net_buf *frag)
Add a new fragment to the end of a chain of bufs.
Append a new fragment into the buffer fragments list.
Note: This function takes ownership of the fragment reference so the caller is not required to unref.

Parameters
• head – Head of the fragment chain.
• frag – Fragment to add.

Returns
New head of the fragment chain. Either head (if head was non-NULL) or frag (if head was NULL).

struct net_buf *net_buf_frag_del(struct net_buf *parent, struct net_buf *frag)
Delete existing fragment from a chain of bufs.

Parameters
• parent – Parent buffer/fragment, or NULL if there is no parent.
• **frag** – Fragment to delete.

**Returns**

Pointer to the buffer following the fragment, or NULL if it had no further fragments.

```c
size_t net_buf_linearize(void *dst, size_t dst_len, struct net_buf *src, size_t offset, size_t len)
```

Copy bytes from `net_buf` chain starting at offset to linear buffer.

Copy (extract) `len` bytes from `src net_buf` chain, starting from `offset` in it, to a linear buffer `dst`.

Return number of bytes actually copied, which may be less than requested, if `net_buf` chain doesn't have enough data, or destination buffer is too small.

**Parameters**

- `dst` – Destination buffer
- `dst_len` – Destination buffer length
- `src` – Source `net_buf` chain
- `offset` – Starting offset to copy from
- `len` – Number of bytes to copy

**Returns**

Number of bytes actually copied

```c
size_t net_buf_append_bytes(struct net_buf *buf, size_t len, const void *value, k_timeout_t timeout, net_buf_allocator_cb allocate_cb, void *user_data)
```

Append data to a list of `net_buf`.

Append data to a `net_buf`. If there is not enough space in the `net_buf` then more `net_buf` will be added, unless there are no free `net_buf` and timeout occurs. If not allocator is provided it attempts to allocate from the same pool as the original buffer.

**Parameters**

- `buf` – Network buffer.
- `len` – Total length of input data
- `value` – Data to be added
- `timeout` – Timeout is passed to the `net_buf` allocator callback.
- `allocate_cb` – When a new `net_buf` is required, use this callback.
- `user_data` – A user data pointer to be supplied to the `allocate_cb`. This pointer is can be anything from a `mem_pool` or a `net_pkt`, the logic is left up to the `allocate_cb` function.

**Returns**

Length of data actually added. This may be less than input length if other timeout than `K_FOREVER` was used, and there were no free fragments in a pool to accommodate all data.

```c
static inline struct net_buf *net_buf_skip(struct net_buf *buf, size_t len)
```

Skip N number of bytes in a `net_buf`.

Skip N number of bytes starting from fragment’s offset. If the total length of data is placed in multiple fragments, this function will skip from all fragments until it reaches N number of bytes. Any fully skipped buffers are removed from the `net_buf` list.

**Parameters**

- `buf` – Network buffer.
- `len` – Total length of data to be skipped.
Returns

Pointer to the fragment or NULL and pos is 0 after successful skip, NULL and pos
is 0xffff otherwise.

static inline size_t net_buf_frags_len(struct net_buf *buf)

Calculates amount of bytes stored in fragments.

Calculates the total amount of data stored in the given buffer and the fragments linked to it.

Parameters

• buf – Buffer to start off with.

Returns

Number of bytes in the buffer and its fragments.

struct net_buf_simple

#include <buf.h> Simple network buffer representation.

This is a simpler variant of the net_buf object (in fact net_buf uses net_buf_simple internally).

It doesn’t provide any kind of reference counting, user data, dynamic allocation, or in general
the ability to pass through kernel objects such as FIFOs.

The main use of this is for scenarios where the meta-data of the normal net_buf isn’t needed
and causes too much overhead. This could be e.g. when the buffer only needs to be allocated
on the stack or when the access to and lifetime of the buffer is well controlled and constrained.

Public Members

uint8_t *data

Pointer to the start of data in the buffer.

uint16_t len

Length of the data behind the data pointer.

To determine the max length, use net_buf_simple_max_len(), not size!

uint16_t size

Amount of data that net_buf_simple::__buf can store.

struct net_buf_simple_state

#include <buf.h> Parsing state of a buffer.

This is used for temporarily storing the parsing state of a buffer while giving control of the
 parsing to a routine which we don’t control.

Public Members

uint16_t offset

Offset of the data pointer from the beginning of the storage

uint16_t len

Length of data
struct net_buf
    #include <buf.h> Network buffer representation.
    This struct is used to represent network buffers. Such buffers are normally defined through
the NET_BUF_POOL_*_DEFINE() APIs and allocated using the net_buf_alloc() API.

Public Members

sys_snode_t node
    Allow placing the buffer into sys_slist_t

struct net_buf *frags
    Fragments associated with this buffer.

uint8_t ref
    Reference count.

uint8_t flags
    Bit-field of buffer flags.

uint8_t pool_id
    Where the buffer should go when freed up.

uint8_t *data
    Pointer to the start of data in the buffer.

uint16_t len
    Length of the data behind the data pointer.

uint16_t size
    Amount of data that this buffer can store.

uint8_t user_data[]
    System metadata for this buffer.

struct net_buf_data_cb
    #include <buf.h>

struct net_buf_data_alloc
    #include <buf.h>

struct net_buf_pool
    #include <buf.h> Network buffer pool representation.
    This struct is used to represent a pool of network buffers.

Public Members
struct k_lifo_free
    LIFO to place the buffer into when free

const uint16_t buf_count
    Number of buffers in pool

uint16_t uninit_count
    Number of uninitialized buffers

void (*const destroy)(struct net_buf *buf)
    Optional destroy callback when buffer is freed.

const struct net_buf_data_alloc *alloc
    Data allocation handlers.

struct net_buf_pool_fixed
    #include <buf.h>

Packet Management

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Overview  Network packets are the main data the networking stack manipulates. Such data is represented through the net_pkt structure which provides a means to hold the packet, write and read it, as well as necessary metadata for the core to hold important information. Such an object is called net_pkt in this document.

The data structure and the whole API around it are defined in include/zephyr/net/net_pkt.h.

Architectural notes  There are two network packets flows within the stack, TX for the transmission path, and RX for the reception one. In both paths, each net_pkt is written and read from the beginning to the end, or more specifically from the headers to the payload.

Memory management
### Allocation

All net_pkt objects come from a pre-defined pool of struct net_pkt. Such pool is defined via

\[
\text{NET_PKT_SLAB_DEFINE(name, count)}
\]

Note, however, one will rarely have to use it, as the core provides already two pools, one for the TX path and one for the RX path.

Allocating a raw net_pkt can be done through:

\[
\text{pkt = net_pkt_alloc(timeout);}
\]

However, by its nature, a raw net_pkt is useless without a buffer and needs various metadata information to become relevant as well. It requires at least to get the network interface it is meant to be sent through or through which it was received. As this is a very common operation, a helper exist:

\[
\text{pkt = net_pkt_alloc_on_iface(iface, timeout);}
\]

A more complete allocator exists, where both the net_pkt and its buffer can be allocated at once:

\[
\text{pkt = net_pkt_alloc_with_buffer(iface, size, family, proto, timeout);}
\]

See below how the buffer is allocated.

### Buffer allocation

The net_pkt object does not define its own buffer, but instead uses an existing object for this: `net_buf`. (See Network Buffer for more information). However, it mostly hides the usage of such a buffer because net_pkt brings network awareness to buffer allocation and, as we will see later, its operation too.

To allocate a buffer, a net_pkt needs to have at least its network interface set. This works if the family of the packet is unknown at the time of buffer allocation. Then one could do:

\[
\text{net_pkt_alloc_buffer(pkt, size, proto, timeout);}
\]

Where proto could be 0 if unknown (there is no IPPROTO_UNSPEC).

As seen previously, the net_pkt and its buffer can be allocated at once via `net_pkt_alloc_with_buffer()`. It is actually the most widely used allocator.

The network interface, the family, and the protocol of the packet are used by the buffer allocation to determine if the requested size can be allocated. Indeed, the allocator will use the network interface to know the MTU and then the family and protocol for the headers space (if only these 2 are specified). If the whole fits within the MTU, the allocated space will be of the requested size plus, eventually, the headers space. If there is insufficient MTU space, the requested size will be shrunk so the possible headers space and new size will fit within the MTU.

For instance, on an Ethernet network interface, with an MTU of 1500 bytes:

\[
\text{pkt = net_pkt_alloc_with_buffer(iface, 800, AF_INET4, IPPROTO_UDP, K_FOREVER);}
\]

will successfully allocate 800 + 20 + 8 bytes of buffer for the new net_pkt where:

\[
\text{pkt = net_pkt_alloc_with_buffer(iface, 1600, AF_INET4, IPPROTO_UDP, K_FOREVER);}
\]

will successfully allocate 1500 bytes, and where 20 + 8 bytes (IPv4 + UDP headers) will not be used for the payload.

On the receiving side, when the family and protocol are not known:

\[
\text{pkt = net_pkt_rx_alloc_with_buffer(iface, 800, AF_UNSPEC, 0, K_FOREVER);}
\]

will allocate 800 bytes and no extra header space. But a:
pkt = net_pkt_rx_alloc_with_buffer(iface, 1600, AF_UNSPEC, 0, K_FOREVER);

will allocate 1514 bytes, the MTU + Ethernet header space.

One can increase the amount of buffer space allocated by calling net_pkt_alloc_buffer(), as it will take into account the existing buffer. It will also account for the header space if net_pkt’s family is a valid one, as well as the proto parameter. In that case, the newly allocated buffer space will be appended to the existing one, and not inserted in the front. Note however such a use case is rather limited. Usually, one should know from the start how much size should be requested.

Deallocation Each net_pkt is reference counted. At allocation, the reference is set to 1. The reference count can be incremented with net_pkt_ref() or decremented with net_pkt_unref(). When the count drops to zero the buffer is also un-referenced and net_pkt is automatically placed back into the free net_pkt slabs.

If net_pkt’s buffer is needed even after net_pkt deallocation, one will need to reference once more all the chain of net_buf before calling last net_pkt_unref. See Network Buffer for more information.

Operations There are two ways to access the net_pkt buffer, explained in the following sections: basic read/write access and data access, the latter being the preferred way.

Read and Write access As said earlier, though net_pkt uses net_buf for its buffer, it provides its own API to access it. Indeed, a network packet might be scattered over a chain of net_buf objects, the functions provided by net_buf are then limited for such case. Instead, net_pkt provides functions which hide all the complexity of potential non-contiguous access.

Data movement into the buffer is made through a cursor maintained within each net_pkt. All read/write operations affect this cursor. Note as well that read or write functions are strict on their length parameters: if it cannot r/w the given length it will fail. Length is not interpreted as an upper limit, it is instead the exact amount of data that must be read or written.

As there are two paths, TX and RX, there are two access modes: write and overwrite. This might sound a bit unusual, but is in fact simple and provides flexibility.

In write mode, whatever is written in the buffer affects the length of actual data present in the buffer. Buffer length should not be confused with the buffer size which is a limit any mode cannot pass. In overwrite mode then, whatever is written must happen on valid data, and will not affect the buffer length. By default, a newly allocated net_pkt is on write mode, and its cursor points to the beginning of its buffer.

Let’s see now, step by step, the functions and how they behave depending on the mode.

When freshly allocated with a buffer of 500 bytes, a net_pkt has 0 length, which means no valid data is in its buffer. One could verify this by:

\[
\text{len = net_pkt_get_len(pkt);}\]

Now, let’s write 8 bytes:

\[
\text{net_pkt_write(pkt, data, 8);}\]

The buffer length is now 8 bytes. There are various helpers to write a byte, or big endian uint16_t, uint32_t.

\[
\text{net_pkt_write_u8(pkt, &foo);}\]
\[
\text{net_pkt_write_be16(pkt, &ba);}\]
\[
\text{net_pkt_write_be32(pkt, &bar);}\]
Logically, net_pkt's length is now 15. But if we try to read at this point, it will fail because there is nothing to read at the cursor where we are at in the net_pkt. It is possible, while in write mode, to read what has been already written by resetting the cursor of the net_pkt. For instance:

```c
net_pkt_cursor_init(pkt);
net_pkt_read(pkt, data, 15);
```

This will reset the cursor of the pkt to the beginning of the buffer and then let you read the actual 15 bytes present. The cursor is then again pointing at the end of the buffer.

To set a large area with the same byte, a memset function is provided:

```c
net_pkt_memset(pkt, 0, 5);
```

Our net_pkt has now a length of 20 bytes.

Switching between modes can be achieved via `net_pkt_set_overwrite()` function. It is possible to switch mode back and forth at any time. The net_pkt will be set to overwrite and its cursor reset:

```c
net_pkt_set_overwrite(pkt, true);
net_pkt_cursor_init(pkt);
```

Now the same operators can be used, but it will be limited to the existing data in the buffer, i.e. 20 bytes. If it is necessary to know how much space is available in the net_pkt call:

```c
net_pkt_available_buffer(pkt);
```

Or, if headers space needs to be accounted for, call:

```c
net_pkt_available_payload_buffer(pkt, proto);
```

If you want to place the cursor at a known position use the function `net_pkt_skip()`. For example, to go after the IP header, use:

```c
net_pkt_cursor_init(pkt);
net_pkt_skip(pkt, net_pkt_ip_header_len(pkt));
```

**Data access** Though the API shown previously is rather simple, it involves always copying things to and from the net_pkt buffer. In many occasions, it is more relevant to access the information stored in the buffer contiguously, especially with network packets which embed headers.

These headers are, most of the time, a known fixed set of bytes. It is then more natural to have a structure representing a certain type of header. In addition to this, if it is known the header size appears in a contiguous area of the buffer, it will be way more efficient to cast the actual position in the buffer to the type of header. Either for reading or writing the fields of such header, accessing it directly will save memory.

Net pkt comes with a dedicated API for this, built on top of the previously described API. It is able to handle both contiguous and non-contiguous access transparently.

There are two macros used to define a data access descriptor: `NET_PKT_DATA_ACCESS_DEFINE` when it is not possible to tell if the data will be in a contiguous area, and `NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE` when it is guaranteed the data is in a contiguous area.

Let's take the example of IP and UDP. Both IPv4 and IPv6 headers are always found at the beginning of the packet and are small enough to fit in a net_buf of 128 bytes (for instance, though 64 bytes could be chosen).
It would be the same for struct net_ipv4_hdr. For a UDP header it is likely not to be in a contiguous area in IPv6 for instance so:

```c
NET_PKT_DATA_ACCESS_DEFINE(udp_access, struct net_ipv4_hdr);
struct net_ipv4_hdr *udp_hdr;
udp_hdr = (struct net_ipv4_hdr *)net_pkt_get_data(pkt, &udp_access);
```

At this point, the cursor of the net_pkt points at the beginning of the requested data. On the RX path, these headers will be read but not modified so to proceed further the cursor needs to advance past the data. There is a function dedicated for this:

```c
net_pkt_acknowledge_data(pkt, &ipv4_access);
```

On the TX path, however, the header fields have been modified. In such a case:

```c
net_pkt_set_data(pkt, &ipv4_access);
```

If the data are in a contiguous area, it will advance the cursor relevantly. If not, it will write the data and the cursor will be updated. Note that `net_pkt_set_data()` could be used in the RX path as well, but it is slightly faster to use `net_pkt_acknowledge_data()` as this one does not care about contiguity at all, it just advances the cursor via `net_pkt_skip()` directly.

### API Reference

**group net_pkt**

Network packet management library.

**Defines**

```c
NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE(ipv4_access, struct net_ipv4_hdr);
struct net_ipv4_hdr *ipv4_hdr;
ipv4_hdr = (struct net_ipv4_hdr *)net_pkt_get_data(pkt, &ipv4_access);
```

6.2. Networking
• name – Name of the pool.
• count – Number of net_buf in this pool.

net_pkt_print_frags(pkt)
    Print fragment list and the fragment sizes.
    Only available if debugging is activated.

Parameters
• pkt – Network pkt.

NET_PKT_DATA_ACCESS_DEFINE(_name, _type)
NET_PKT_DATA_ACCESS_CONTIGUOUS_DEFINE(_name, _type)

Functions

struct net_buf *net_pkt_get_reserve_rx_data(size_t min_len, k_timeout_t timeout)
    Get RX DATA buffer from pool. Normally you should use net_pkt_get_frag() instead.
    Normally this version is not useful for applications but is mainly used by network fragmentation code.

Parameters
• min_len – Minimum length of the requested fragment.
• timeout – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns
    Network buffer if successful, NULL otherwise.

struct net_buf *net_pkt_get_reserve_tx_data(size_t min_len, k_timeout_t timeout)
    Get TX DATA buffer from pool. Normally you should use net_pkt_get_frag() instead.
    Normally this version is not useful for applications but is mainly used by network fragmentation code.

Parameters
• min_len – Minimum length of the requested fragment.
• timeout – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns
    Network buffer if successful, NULL otherwise.

struct net_buf *net_pkt_get_frag(struct net_pkt *pkt, size_t min_len, k_timeout_t timeout)
    Get a data fragment that might be from user specific buffer pool or from global DATA pool.

Parameters
• pkt – Network packet.
• min_len – Minimum length of the requested fragment.
• timeout – Affects the action taken should the net buf pool be empty. If K_NO_WAIT, then return immediately. If K_FOREVER, then wait as long as necessary. Otherwise, wait up to the specified time.

Returns
    Network buffer if successful, NULL otherwise.
void net_pkt_unref(struct net_pkt *pkt)
    Place packet back into the available packets slab.
    Releases the packet to other use. This needs to be called by application after it has finished
    with the packet.

    Parameters
    • pkt – Network packet to release.

struct net_pkt *net_pkt_ref(struct net_pkt *pkt)
    Increase the packet ref count.
    Mark the packet to be used still.

    Parameters
    • pkt – Network packet to ref.

    Returns
    Network packet if successful, NULL otherwise.

struct net_buf *net_pkt_frag_ref(struct net_buf *frag)
    Increase the packet fragment ref count.
    Mark the fragment to be used still.

    Parameters
    • frag – Network fragment to ref.

    Returns
    a pointer on the referenced Network fragment.

void net_pkt_frag_unref(struct net_buf *frag)
    Decrease the packet fragment ref count.

    Parameters
    • frag – Network fragment to unref.

struct net_buf *net_pkt_frag_del(struct net_pkt *pkt, struct net_buf *parent, struct net_buf *frag)
    Delete existing fragment from a packet.

    Parameters
    • pkt – Network packet from which frag belongs to.
    • parent – parent fragment of frag, or NULL if none.
    • frag – Fragment to delete.

    Returns
    Pointer to the following fragment, or NULL if it had no further fragments.

void net_pkt_frag_add(struct net_pkt *pkt, struct net_buf *frag)
    Add a fragment to a packet at the end of its fragment list.

    Parameters
    • pkt – pkt Network packet where to add the fragment
    • frag – Fragment to add

void net_pkt_frag_insert(struct net_pkt *pkt, struct net_buf *frag)
    Insert a fragment to a packet at the beginning of its fragment list.

    Parameters
    • pkt – pkt Network packet where to insert the fragment
• **frag** – Fragment to insert

```c
void net_pkt_compact(struct net_pkt *pkt)
```

Compact the fragment list of a packet.

After this there is no more any free space in individual fragments.

**Parameters**

• *pkt* – Network packet.

```c
void net_pkt_get_info(struct k_mem_slab **rx, struct k_mem_slab **tx, struct net_buf_pool **rx_data, struct net_buf_pool **tx_data)
```

Get information about predefined RX, TX and DATA pools.

**Parameters**

• *rx* – Pointer to RX pool is returned.
• *tx* – Pointer to TX pool is returned.
• *rx_data* – Pointer to RX DATA pool is returned.
• *tx_data* – Pointer to TX DATA pool is returned.

```c
struct net_pkt *net_pkt_alloc(k_timeout_t timeout)
```

Allocate an initialized `net_pkt`.

for the time being, 2 pools are used. One for TX and one for RX. This allocator has to be used for TX.

**Parameters**

• *timeout* – Maximum time to wait for an allocation.

**Returns**

a pointer to a newly allocated `net_pkt` on success, NULL otherwise.

```c
struct net_pkt *net_pkt_alloc_from_slab(struct k_mem_slab *slab, k_timeout_t timeout)
```

Allocate an initialized `net_pkt` from a specific slab.

unlike `net_pkt_alloc()` which uses core slabs, this one will use an external slab (see `NET_PKT_SLAB_DEFINE()`). Do not use it unless you know what you are doing. Basically, only net_context should be using this, in order to allocate packet and then buffer on its local slab/pool (if any).

**Parameters**

• *slab* – The slab to use for allocating the packet
• *timeout* – Maximum time to wait for an allocation.

**Returns**

a pointer to a newly allocated `net_pkt` on success, NULL otherwise.

```c
struct net_pkt *net_pkt_rx_alloc(k_timeout_t timeout)
```

Allocate an initialized `net_pkt` for RX.

for the time being, 2 pools are used. One for TX and one for RX. This allocator has to be used for RX.

**Parameters**

• *timeout* – Maximum time to wait for an allocation.

**Returns**

a pointer to a newly allocated `net_pkt` on success, NULL otherwise.
struct net_pkt *
net_pkt_alloc_on_iface(struct net_if *iface, k_timeout_t timeout)

Allocate a network packet for a specific network interface.

Parameters
• iface – The network interface the packet is supposed to go through.
• timeout – Maximum time to wait for an allocation.

Returns
a pointer to a newly allocated net_pkt on success, NULL otherwise.

struct net_pkt *
net_pkt_rx_alloc_on_iface(struct net_if *iface, k_timeout_t timeout)

Allocate buffer for a net_pkt.
: such allocator will take into account space necessary for headers, MTU, and existing buffer
(if any). Beware that, due to all these criteria, the allocated size might be smaller/bigger than
requested one.

Parameters
• pkt – The network packet requiring buffer to be allocated.
• size – The size of buffer being requested.
• proto – The IP protocol type (can be 0 for none).
• timeout – Maximum time to wait for an allocation.

Returns
0 on success, negative errno code otherwise.

struct net_pkt *
net_pkt_alloc_with_buffer(struct net_if *iface, size_t size,
sa_family_t family, enum net_ip_protocol proto,
k_timeout_t timeout)

Allocate a network packet and buffer at once.

Parameters
• iface – The network interface the packet is supposed to go through.
• size – The size of buffer.
• family – The family to which the packet belongs.
• proto – The IP protocol type (can be 0 for none).
• timeout – Maximum time to wait for an allocation.

Returns
a pointer to a newly allocated net_pkt on success, NULL otherwise.

void net_pkt_append_buffer(struct net_pkt *pkt, struct net_buf *buffer)

Append a buffer in packet.

Parameters
• pkt – Network packet where to append the buffer
• buffer – Buffer to append
size_t net_pkt_available_buffer(struct net_pkt *pkt)
Get available buffer space from a pkt.

**Note:** Reserved bytes (headroom) in any of the fragments are not considered to be available.

**Parameters**
- pkt – The net_pkt which buffer availability should be evaluated

**Returns**
the amount of buffer available

size_t net_pkt_available_payload_buffer(struct net_pkt *pkt, enum net_ip_protocol proto)
Get available buffer space for payload from a pkt.

Unlike net_pkt_available_buffer(), this will take into account the headers space.

**Note:** Reserved bytes (headroom) in any of the fragments are not considered to be available.

**Parameters**
- pkt – The net_pkt which payload buffer availability should be evaluated
- proto – The IP protocol type (can be 0 for none).

**Returns**
the amount of buffer available for payload

void net_pkt_trim_buffer(struct net_pkt *pkt)
Trim net_pkt buffer.
This will basically check for unused buffers and deallocate them relevantly

**Parameters**
- pkt – The net_pkt which buffer will be trimmed

int net_pkt_remove_tail(struct net_pkt *pkt, size_t length)
Remove length bytes from tail of packet.
This function does not take packet cursor into account. It is a helper to remove unneeded bytes from tail of packet (like appended CRC). It takes care of buffer deallocation if removed bytes span whole buffer(s).

**Parameters**
- pkt – Network packet
- length – Number of bytes to be removed

**Return values**
- 0 – On success.
- -EINVAL – If packet length is shorter than length.

void net_pkt_cursor_init(struct net_pkt *pkt)
Initialize net_pkt cursor.
This will initialize the net_pkt cursor from its buffer.

**Parameters**
• pkt – The net_pkt whose cursor is going to be initialized

static inline void net_pkt_cursor_backup(struct net_pkt *pkt, struct net_pkt_cursor *backup)
Backup net_pkt cursor.

Parameters
• pkt – The net_pkt whose cursor is going to be backed up
• backup – The cursor where to backup net_pkt cursor

static inline void net_pkt_cursor_restore(struct net_pkt *pkt, struct net_pkt_cursor *backup)
Restore net_pkt cursor from a backup.

Parameters
• pkt – The net_pkt whose cursor is going to be restored
• backup – The cursor from where to restore net_pkt cursor

static inline void *net_pkt_cursor_get_pos(struct net_pkt *pkt)
Returns current position of the cursor.

Parameters
• pkt – The net_pkt whose cursor position is going to be returned

Returns
cursor’s position

int net_pkt_skip(struct net_pkt *pkt, size_t length)
Skip some data from a net_pkt.

net_pkt’s cursor should be properly initialized. Cursor position will be updated after the operation. Depending on the value of pkt->overwrite bit, this function will affect the buffer length or not. If it’s true, it will advance the cursor to the requested length. If it’s false, it will do the same but if the cursor was already also at the end of existing data, it will increment the buffer length. So in this case, its behavior is just like net_pkt_write or net_pkt_memset, difference being that it will not affect the buffer content itself (which may be just garbage then).

Parameters
• pkt – The net_pkt whose cursor will be updated to skip given amount of data from the buffer.
• length – Amount of data to skip in the buffer

Returns
0 in success, negative errno code otherwise.

int net_pkt_memset(struct net_pkt *pkt, int byte, size_t length)
Memset some data in a net_pkt.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The net_pkt whose buffer to fill starting at the current cursor position.
• byte – The byte to write in memory
• length – Amount of data to memset with given byte

Returns
0 in success, negative errno code otherwise.
int net_pkt_copy(struct net_pkt *pkt_dst, struct net_pkt *pkt_src, size_t length)
    Copy data from a packet into another one.
    Both net_pkt cursors should be properly initialized and, if needed, positioned using net_pkt_skip. The cursors will be updated after the operation.

    Parameters
    • pkt_dst – Destination network packet.
    • pkt_src – Source network packet.
    • length – Length of data to be copied.

    Returns
    0 on success, negative errno code otherwise.

struct net_pkt *net_pkt_clone(struct net_pkt *pkt, k_timeout_t timeout)
    Clone pkt and its buffer. The cloned packet will be allocated on the same pool as the original one.

    Parameters
    • pkt – Original pkt to be cloned
    • timeout – Timeout to wait for free buffer

    Returns
    NULL if error, cloned packet otherwise.

struct net_pkt *net_pkt_rx_clone(struct net_pkt *pkt, k_timeout_t timeout)
    Clone pkt and its buffer. The cloned packet will be allocated on the RX packet poll.

    Parameters
    • pkt – Original pkt to be cloned
    • timeout – Timeout to wait for free buffer

    Returns
    NULL if error, cloned packet otherwise.

struct net_pkt *net_pkt_shallow_clone(struct net_pkt *pkt, k_timeout_t timeout)
    Clone pkt and increase the refcount of its buffer.

    Parameters
    • pkt – Original pkt to be shallow cloned
    • timeout – Timeout to wait for free packet

    Returns
    NULL if error, cloned packet otherwise.

int net_pkt_read(struct net_pkt *pkt, void *data, size_t length)
    Read some data from a net_pkt.
    net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

    Parameters
    • pkt – The network packet from where to read some data
    • data – The destination buffer where to copy the data
    • length – The amount of data to copy

    Returns
    0 on success, negative errno code otherwise.
static inline int net_pkt_read_u8(struct net_pkt *pkt, uint8_t *data)

int net_pkt_read_be16(struct net_pkt *pkt, uint16_t *data)

Read uint16_t big endian data from a net_pkt.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to read
• data – The destination uint16_t where to copy the data

Returns
0 on success, negative errno code otherwise.

int net_pkt_read_le16(struct net_pkt *pkt, uint16_t *data)

Read uint16_t little endian data from a net_pkt.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to read
• data – The destination uint16_t where to copy the data

Returns
0 on success, negative errno code otherwise.

int net_pkt_read_be32(struct net_pkt *pkt, uint32_t *data)

Read uint32_t big endian data from a net_pkt.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to read
• data – The destination uint32_t where to copy the data

Returns
0 on success, negative errno code otherwise.

int net_pkt_write(struct net_pkt *pkt, const void *data, size_t length)

Write data into a net_pkt.

net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet where to write
• data – Data to be written
• length – Length of the data to be written

Returns
0 on success, negative errno code otherwise.

static inline int net_pkt_write_u8(struct net_pkt *pkt, uint8_t data)

static inline int net_pkt_write_be16(struct net_pkt *pkt, uint16_t data)

static inline int net_pkt_write_be32(struct net_pkt *pkt, uint32_t data)
static inline int net_pkt_write_le32(struct net_pkt *pkt, uint32_t data)
static inline int net_pkt_write_le16(struct net_pkt *pkt, uint16_t data)
size_t net_pkt_remaining_data(struct net_pkt *pkt)
   Get the amount of data which can be read from current cursor position.

   Parameters
   • pkt – Network packet

   Returns
   Amount of data which can be read from current pkt cursor

int net_pkt_update_length(struct net_pkt *pkt, size_t length)
   Update the overall length of a packet.
   Unlike net_pkt_pull() below, this does not take packet cursor into account. It's mainly a helper
dedicated for ipv4 and ipv6 input functions. It shrinks the overall length by given parameter.

   Parameters
   • pkt – Network packet
   • length – The new length of the packet

   Returns
   0 on success, negative errno code otherwise.

int net_pkt_pull(struct net_pkt *pkt, size_t length)
   Remove data from the packet at current location.
   net_pkt's cursor should be properly initialized and, eventually, properly positioned using
net_pkt_skip/read/write. Note that net_pkt's cursor is reset by this function.

   Parameters
   • pkt – Network packet
   • length – Number of bytes to be removed

   Returns
   0 on success, negative errno code otherwise.

uint16_t net_pkt_get_current_offset(struct net_pkt *pkt)
   Get the actual offset in the packet from its cursor.

   Parameters
   • pkt – Network packet.

   Returns
   a valid offset on success, 0 otherwise as there is nothing that can be done to
evaluate the offset.

bool net_pkt_is_contiguous(struct net_pkt *pkt, size_t size)
   Check if a data size could fit contiguously.
   net_pkt's cursor should be properly initialized and, if needed, positioned using net_pkt_skip.

   Parameters
   • pkt – Network packet.
   • size – The size to check for contiguity

   Returns
   true if that is the case, false otherwise.
size_t net_pkt_get_contiguous_len(struct net_pkt *pkt)
Get the contiguous buffer space.

Parameters
• pkt – Network packet

Returns
The available contiguous buffer space in bytes starting from the current cursor position. 0 in case of an error.

void *net_pkt_get_data(struct net_pkt *pkt, struct net_pkt_data_access *access)
Get data from a network packet in a contiguous way.
net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet from where to get the data.
• access – A pointer to a valid net_pkt_data_access describing the data to get in a contiguous way.

Returns
a pointer to the requested contiguous data, NULL otherwise.

int net_pkt_set_data(struct net_pkt *pkt, struct net_pkt_data_access *access)
Set contiguous data into a network packet.
net_pkt’s cursor should be properly initialized and, if needed, positioned using net_pkt_skip. Cursor position will be updated after the operation.

Parameters
• pkt – The network packet to where the data should be set.
• access – A pointer to a valid net_pkt_data_access describing the data to set.

Returns
0 on success, a negative errno otherwise.

static inline int net_pkt_acknowledge_data(struct net_pkt *pkt, struct net_pkt_data_access *access)
Acknowledged previously contiguous data taken from a network packet Packet needs to be set to overwrite mode.

struct net_pkt_cursor
#include <net_pkt.h>

Public Members

struct netbuf *buf
Current netbuf pointer by the cursor

uint8_t *pos
Current position in the data buffer of the netbuf

struct net_pkt
#include <net_pkt.h> Network packet.
Note that if you add new fields into net_pkt, remember to update net_pkt_clone() function.
Public Members

intptr_t fifo

The fifo is used by RX/TX threads and by socket layer. The net_pkt is queued via fifo to the processing thread.

struct k_mem_slab *slab

Slab pointer from where it belongs to

union net_pkt.[anonymous] [anonymous]
buffer holding the packet

struct net_pkt_cursor cursor

Internal buffer iterator used for reading/writing

struct net_context *context

Network connection context

struct net_if *iface

Network interface

struct net_pkt_data_access

#include <net_pkt.h>

Networking Technologies

Ethernet

- Overview
- API Reference

Virtual LAN (VLAN) Support

- Overview
- API Reference

Overview  Virtual LAN (VLAN) is a partitioned and isolated computer network at the data link layer (OSI layer 2). For ethernet network this refers to IEEE 802.1Q

In Zephyr, each individual VLAN is modeled as a virtual network interface. This means that there is an ethernet network interface that corresponds to a real physical ethernet port in the system. A virtual network interface is created for each VLAN, and this virtual network interface connects to the real network interface. This is similar to how Linux implements VLANs. The eth0 is the real network interface and vlan0 is a virtual network interface that is run on top of eth0.

VLAN support must be enabled at compile time by setting option CONFIG_NET_VLAN and CONFIG_NET_VLAN_COUNT to reflect how many network interfaces there will be in the system. For example, if there is one network interface without VLAN support, and two with VLAN support, the CONFIG_NET_VLAN_COUNT option should be set to 3.
Even if VLAN is enabled in a `prj.conf` file, the VLAN needs to be activated at runtime by the application. The VLAN API provides a `net_eth_vlan_enable()` function to do that. The application needs to give the network interface and desired VLAN tag as a parameter to that function. The VLAN tagging for a given network interface can be disabled by a `net_eth_vlan_disable()` function. The application needs to configure the VLAN network interface itself, such as setting the IP address, etc.

See also the VLAN sample application for API usage example. The source code for that sample application can be found at `samples/net/vlan`.

The net-shell module contains `net vlan add` and `net vlan del` commands that can be used to enable or disable VLAN tags for a given network interface.

See the IEEE 802.1Q spec for more information about ethernet VLANs.

### API Reference

**group** vlan_api

VLAN definitions and helpers.

**Defines**

`NET_VLAN_TAG_UNSPEC`

Unspecified VLAN tag value

**Functions**

```c
static inline uint16_t net_eth_vlan_get_vid(uint16_t tci)

Get VLAN identifier from TCI.

**Parameters**

- `tci` – VLAN tag control information.

**Returns**

VLAN identifier.
```

```c
static inline uint8_t net_eth_vlan_get_dei(uint16_t tci)

Get Drop Eligible Indicator from TCI.

**Parameters**

- `tci` – VLAN tag control information.

**Returns**

Drop eligible indicator.
```

```c
static inline uint8_t net_eth_vlan_get_pcp(uint16_t tci)

Get Priority Code Point from TCI.

**Parameters**

- `tci` – VLAN tag control information.

**Returns**

Priority code point.
```

```c
static inline uint16_t net_eth_vlan_set_vid(uint16_t tci, uint16_t vid)

Set VLAN identifier to TCI.

**Parameters**

- `tci` – VLAN tag control information.
- `vid` – VLAN tag value.

**Returns**

VLAN identifier.
```
• vid – VLAN identifier.

Returns
New TCI value.

static inline uint16_t net_eth_vlan_set_dei(uint16_t tci, bool dei)
Set Drop Eligible Indicator to TCI.

Parameters
• tci – VLAN tag control information.
• dei – Drop eligible indicator.

Returns
New TCI value.

static inline uint16_t net_eth_vlan_set_pcp(uint16_t tci, uint8_t pcp)
Set Priority Code Point to TCI.

Parameters
• tci – VLAN tag control information.
• pcp – Priority code point.

Returns
New TCI value.

Link Layer Discovery Protocol

Overview
The Link Layer Discovery Protocol (LLDP) is a vendor-neutral link layer protocol used by network devices for advertising their identity, capabilities, and neighbors on a wired Ethernet network. For more information, see this LLDP Wikipedia article.

API Reference

group lldp
LLDP definitions and helpers.

Defines

net_lldp_set_lldpdu(iface)
Set LLDP protocol data unit (LLDPDU) for the network interface.

Parameters
• iface – Network interface

Returns
<0 if error, index in lldp array if iface is found there
net_lldp_unset_lldpdu(iface)

Unset LLDP protocol data unit (LLDPDU) for the network interface.

**Parameters**

- **iface** – Network interface

**Typedefs**

typedef enum net_verdict (*net_lldp_recv_cb_t)(struct net_if *iface, struct net_pkt *pkt)

LLDP Receive packet callback.

Callback gets called upon receiving packet. It is responsible for freeing packet or indicating to the stack that it needs to free packet by returning correct net_verdict.

Returns:

- **NET_DROP**, if packet was invalid, rejected or we want the stack to free it. In this case the core stack will free the packet.
- **NET_OK**, if the packet was accepted, in this case the ownership of the *net_pkt* goes to callback and core network stack will forget it.

**Enums**

eenum net_lldp_tlv_type

TLV Types. Please refer to table 8.1 from IEEE 802.1AB standard.

Values:

- **enumerator LLDP_TLV_END_LLDPDU** = 0
  
  End Of LLDPDU (optional)

- **enumerator LLDP_TLV_CHASSIS_ID** = 1
  
  Chassis ID (mandatory)

- **enumerator LLDP_TLV_PORT_ID** = 2
  
  Port ID (mandatory)

- **enumerator LLDP_TLV_TTL** = 3
  
  Time To Live (mandatory)

- **enumerator LLDP_TLV_PORT_DESC** = 4
  
  Port Description (optional)

- **enumerator LLDP_TLV_SYSTEM_NAME** = 5
  
  System Name (optional)

- **enumerator LLDP_TLV_SYSTEM_DESC** = 6
  
  System Description (optional)

- **enumerator LLDP_TLV_SYSTEM_CAPABILITIES** = 7
  
  System Capability (optional)
enumerator LLDP_TLV_MANAGEMENT_ADDR = 8
Management Address (optional)

enumerator LLDP_TLV_ORG_SPECIFIC = 127
Org specific TLVs (optional)

Functions

int net_lldp_config(struct net_if *iface, const struct net_lldpdu *lldpdu)
Set the LLDP data unit for a network interface.

Parameters
• iface – Network interface
• lldpdu – LLDP data unit struct

Returns
0 if ok, <0 if error

int net_lldp_config_optional(struct net_if *iface, const uint8_t *tlv, size_t len)
Set the Optional LLDP TLVs for a network interface.

Parameters
• iface – Network interface
• tlv – LLDP optional TLVs following mandatory part
• len – Length of the optional TLVs

Returns
0 if ok, <0 if error

void net_lldp_init(void)
Initialize LLDP engine.

int net_lldp_register_callback(struct net_if *iface, net_lldp_recv_cb_t cb)
Register LLDP Rx callback function.

Parameters
• iface – Network interface
• cb – Callback function

Returns
0 if ok, < 0 if error

enum net_verdict net_lldp_recv(struct net_if *iface, struct net_pkt *pkt)
Parse LLDP packet.

Parameters
• iface – Network interface
• pkt – Network packet

Returns
Return the policy for network buffer

struct net_lldp_chassis_tlv
#include <lldp.h> Chassis ID TLV, see chapter 8.5.2 in IEEE 802.1AB
Public Members

`uint16_t type_length`
7 bits for type, 9 bits for length

`uint8_t subtype`
ID subtype

`uint8_t value[NET_LLDP_CHASSIS_ID_VALUE_LEN]`
Chassis ID value

```
#include <lldp.h>
```
Port ID TLV, see chapter 8.5.3 in IEEE 802.1AB

Public Members

`uint16_t type_length`
7 bits for type, 9 bits for length

`uint8_t subtype`
ID subtype

`uint8_t value[NET_LLDP_PORT_ID_VALUE_LEN]`
Port ID value

```
#include <lldp.h>
```
Time To Live TLV, see chapter 8.5.4 in IEEE 802.1AB

Public Members

`uint16_t type_length`
7 bits for type, 9 bits for length

`uint16_t ttl`
Time To Live (TTL) value

```
#include <lldp.h>
```
LLDP Data Unit (LLDPDU) shall contain the following ordered TLVs as stated in “8.2 LLDPDU format” from the IEEE 802.1AB

Public Members

```
struct net_lldp_chassis_tlv chassis_id
```
Mandatory Chassis TLV
struct net_lldp_port_tlv port_id
Mandatory Port TLV

struct net_lldp_time_to_live_tlv ttl
Mandatory TTL TLV

IEEE 802.1Qav

Overview Credit-based shaping is an alternative scheduling algorithm used in network schedulers to achieve fairness when sharing a limited network resource. Zephyr has support for configuring a credit-based shaper described in the IEEE 802.1Qav-2009 standard. Zephyr does not implement the actual shaper; it only provides a way to configure the shaper implemented by the Ethernet device driver.

Enabling 802.1Qav To enable 802.1Qav shaper, the Ethernet device driver must declare that it supports credit-based shaping. The Ethernet driver’s capability function must return ETHERNET_QAV value for this purpose. Typically also priority queues ETHERNET_PRIORITY_QUEUES need to be supported.

```c
static enum ethernet_hw_caps eth_get_capabilities(const struct device *dev)
{
    ARG_UNUSED(dev);

    return ETHERNET_QAV | ETHERNET_PRIORITY_QUEUES |
          ETHERNET_HW_VLAN | ETHERNET_LINK_10BASE_T |
          ETHERNET_LINK_100BASE_T;
}
```

See sam-e70-xplained board Ethernet driver drivers/ethernet/eth_sam_gmac.c for an example.

Configuring 802.1Qav The application can configure the credit-based shaper like this:

```c
#include <zephyr/net/net_if.h>
#include <zephyr/net/ethernet.h>
#include <zephyr/net/ethernet_mgmt.h>

static void qav_set_status(struct net_if *iface,
                            int queue_id, bool enable)
{
    struct ethernet_req_params params;
    int ret;

    memset(&params, 0, sizeof(params));

    params.qav_param.queue_id = queue_id;
    params.qav_param.enabled = enable;
    params.qav_param.type = ETHERNET_QAV_PARAM_TYPE_STATUS;

    /* Disable or enable Qav for a queue */
    ret = net_mgmt(NET_REQUEST_ETHERNET_SET_QAV_PARAM,
                   iface, &params,
                   sizeof(struct ethernet_req_params));

    if (ret) {
        LOG_ERR("Cannot %s Qav for queue %d for interface %p",
                 enable ? "enable" : "disable",
                 (continues on next page)
Overview

Ethernet is a networking technology commonly used in local area networks (LAN). For more information, see this Ethernet Wikipedia article.

Zephyr supports following Ethernet features:

- 10, 100 and 1000 Mbit/sec links
- Auto negotiation
- Half/full duplex
- Promiscuous mode
- TX and RX checksum offloading
- MAC address filtering
- Virtual LANs
- Priority queues
Not all Ethernet device drivers support all of these features. You can see what is supported by net iface net-shell command. It will print currently supported Ethernet features.

API Reference

group ethernet

Ethernet support functions.

Defines

ETH_NET_DEVICE_INIT(dev_id, name, init_fn, pm, data, config, prio, api, mtu)
Create an Ethernet network interface and bind it to network device.

Parameters

• dev_id – Network device id.
• name – The name this instance of the driver exposes to the system.
• init_fn – Address to the init function of the driver.
• pm – Reference to struct pm_device associated with the device. (optional).
• data – Pointer to the device's private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• prio – The initialization level at which configuration occurs.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• mtu – Maximum transfer unit in bytes for this network interface.

ETH_NET_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, prio, api, mtu)
Like ETH_NET_DEVICE_INIT but taking metadata from a devicetree. Create an Ethernet network interface and bind it to network device.

Parameters

• node_id – The devicetree node identifier.
• init_fn – Address to the init function of the driver.
• pm – Reference to struct pm_device associated with the device. (optional).
• data – Pointer to the device's private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• prio – The initialization level at which configuration occurs.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• mtu – Maximum transfer unit in bytes for this network interface.
ETH_NET_DEVICE_DT_INST_DEFINE(inst, ...
Like ETH_NET_DEVICE_DT_DEFINE for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

- `inst` – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to ETH_NET_DEVICE_DT_DEFINE.
- `...` – other parameters as expected by ETH_NET_DEVICE_DT_DEFINE.

**Enums**

**enum ethernet_hw_caps**

Ethernet hardware capabilities

*Values:*

- `enumerator ETHERNET_HW_TX_CHKSUM_OFFLOAD = BIT(0)`
  TX Checksum offloading supported for all of IPv4, UDP, TCP

- `enumerator ETHERNET_HW_RX_CHKSUM_OFFLOAD = BIT(1)`
  RX Checksum offloading supported for all of IPv4, UDP, TCP

- `enumerator ETHERNET_HW_VLAN = BIT(2)`
  VLAN supported

- `enumerator ETHERNET_AUTO_NEGOTIATION_SET = BIT(3)`
  Enabling/disabling auto negotiation supported

- `enumerator ETHERNET_LINK_10BASE_T = BIT(4)`
  10 Mbits link supported

- `enumerator ETHERNET_LINK_100BASE_T = BIT(5)`
  100 Mbits link supported

- `enumerator ETHERNET_LINK_1000BASE_T = BIT(6)`
  1 Gbits link supported

- `enumerator ETHERNET_DUPLEX_SET = BIT(7)`
  Changing duplex (half/full) supported

- `enumerator ETHERNET_PTP = BIT(8)`
  IEEE 802.1AS (gPTP) clock supported

- `enumerator ETHERNET_QAV = BIT(9)`
  IEEE 802.1Qav (credit-based shaping) supported

- `enumerator ETHERNET_PROMISC_Mode = BIT(10)`
  Promiscuous mode supported

- `enumerator ETHERNET_PRIORITY_QUEUES = BIT(11)`
  Priority queues available
enumerator ETHERNET_HW_FILTERING = BIT(12)
    MAC address filtering supported

enumerator ETHERNET_LLDP = BIT(13)
    Link Layer Discovery Protocol supported

enumerator ETHERNET_HW_VLAN_TAG_STRIP = BIT(14)
    VLAN Tag stripping

enumerator ETHERNET_DSA_SLAVE_PORT = BIT(15)
    DSA switch

enumerator ETHERNET_DSA_MASTER_PORT = BIT(16)

enumerator ETHERNET_QBV = BIT(17)
    IEEE 802.1Qbv (scheduled traffic) supported

enumerator ETHERNET_QBU = BIT(18)
    IEEE 802.1Qbu (frame preemption) supported

enumerator ETHERNET_TXTIME = BIT(19)
    TXTIME supported

enum ethernet_flags
    Values:

    enumerator ETH_CARRIER_UP

Functions

void ethernet_init(struct net_if *iface)
    Initialize Ethernet L2 stack for a given interface.

    Parameters
    • iface – A valid pointer to a network interface

void net_eth_ipv4_mcast_to_mac_addr(const struct in_addr *ipv4_addr, struct net_eth_addr *
    mac_addr)
    Convert IPv4 multicast address to Ethernet address.

    Parameters
    • ipv4_addr – IPv4 multicast address
    • mac_addr – Output buffer for Ethernet address

void net_eth_ipv6_mcast_to_mac_addr(const struct in6_addr *ipv6_addr, struct net_eth_addr *
    mac_addr)
    Convert IPv6 multicast address to Ethernet address.

    Parameters
    • ipv6_addr – IPv6 multicast address
    • mac_addr – Output buffer for Ethernet address
static inline enum ethernet_hw_caps net_eth_get_hw_capabilities(struct net_if *iface)
    Return ethernet device hardware capability information.

    Parameters
    • iface – Network interface

    Returns
    Hardware capabilities

static inline int net_eth_vlan_enable(struct net_if *iface, uint16_t tag)
    Add VLAN tag to the interface.

    Parameters
    • iface – Interface to use.
    • tag – VLAN tag to add

    Returns
    0 if ok, <0 if error

static inline int net_eth_vlan_disable(struct net_if *iface, uint16_t tag)
    Remove VLAN tag from the interface.

    Parameters
    • iface – Interface to use.
    • tag – VLAN tag to remove

    Returns
    0 if ok, <0 if error

static inline uint16_t net_eth_get_vlan_tag(struct net_if *iface)
    Return VLAN tag specified to network interface.

    Parameters
    • iface – Network interface.

    Returns
    VLAN tag for this interface or NET_VLAN_TAG_UNSPEC if VLAN is not configured
    for that interface.

static inline struct net_if *net_eth_get_vlan_iface(struct net_if *iface, uint16_t tag)
    Return network interface related to this VLAN tag.

    Parameters
    • iface – Master network interface. This is used to get the pointer to ethernet
      L2 context
    • tag – VLAN tag

    Returns
    Network interface related to this tag or NULL if no such interface exists.

static inline bool net_eth_is_vlan_enabled(struct ethernet_context *ctx, struct net_if *iface)
    Check if VLAN is enabled for a specific network interface.

    Parameters
    • ctx – Ethernet context
    • iface – Network interface

    Returns
    True if VLAN is enabled for this network interface, false if not.
static inline bool net_eth_get_vlan_status(struct net_if *iface)
Get VLAN status for a given network interface (enabled or not).

Parameters
• iface – Network interface

Returns
True if VLAN is enabled for this network interface, false if not.

void net_eth_carrier_on(struct net_if *iface)
Inform ethernet L2 driver that ethernet carrier is detected. This happens when cable is connected.

Parameters
• iface – Network interface

void net_eth_carrier_off(struct net_if *iface)
Inform ethernet L2 driver that ethernet carrier was lost. This happens when cable is disconnected.

Parameters
• iface – Network interface

int net_eth_promisc_mode(struct net_if *iface, bool enable)
Set promiscuous mode either ON or OFF.

Parameters
• iface – Network interface
• enable – on (true) or off (false)

Returns
0 if mode set or unset was successful, <0 otherwise.

static inline const struct device *net_eth_get_ptp_clock(struct net_if *iface)
Return PTP clock that is tied to this ethernet network interface.

Parameters
• iface – Network interface

Returns
Pointer to PTP clock if found, NULL if not found or if this ethernet interface does not support PTP.

const struct device *net_eth_get_ptp_clock_by_index(int index)
Return PTP clock that is tied to this ethernet network interface index.

Parameters
• index – Network interface index

Returns
Pointer to PTP clock if found, NULL if not found or if this ethernet interface index does not support PTP.

static inline int net_eth_get_ptp_port(struct net_if *iface)
Return PTP port number attached to this interface.

Parameters
• iface – Network interface

Returns
Port number, no such port if < 0
struct ethernet_qav_param
#include <ethernet.h>

Public Members

int queue_id
ID of the priority queue to use

enum ethernet_qav_param_type type
Type of Qav parameter

bool enabled
True if Qav is enabled for queue

unsigned int delta_bandwidth
Delta Bandwidth (percentage of bandwidth)

unsigned int idle_slope
Idle Slope (bits per second)

unsigned int oper_idle_slope
Oper Idle Slope (bits per second)

unsigned int traffic_class
Traffic class the queue is bound to

struct ethernet_qbv_param
#include <ethernet.h>

Public Members

int port_id
Port id

enum ethernet_qbv_param_type type
Type of Qbv parameter

enum ethernet_qbv_state_type state
What state (Admin/Oper) parameters are these

bool enabled
True if Qbv is enabled or not

bool gate_status[NET_TC_TX_COUNT]
True = open, False = closed
enum ethernet_gate_state_operation
    GateState operation

uint32_t time_interval
    Time interval ticks (nanoseconds)

uint16_t row
    Gate control list row

uint32_t gate_control_list_len
    Number of entries in gate control list

struct net_ptp_extended_time base_time
    Base time

struct net_ptp_time cycle_time
    Cycle time

uint32_t extension_time
    Extension time (nanoseconds)

struct ethernet_qbu_param
    #include <ethernet.h>

   **Public Members**

int port_id
    Port id

enum ethernet_qbu_param_type type
    Type of Qbu parameter

uint32_t hold_advance
    Hold advance (nanoseconds)

uint32_t release_advance
    Release advance (nanoseconds)

enum ethernet_qbu_preempt_status frame_preempt_statuses[NET_TC_TX_COUNT]
    sequence of framePreemptionAdminStatus values.

bool enabled
    True if Qbu is enabled or not

bool link_partner_status
    Link partner status (from Qbr)
# Additional fragment size

Additional fragment size (from Qbr). The minimum non-final fragment size is \((\text{additional\_fragment\_size} + 1) \times 64\) octets.

```c
struct ethernet_filter
    #include <ethernet.h>

Public Members

enum ethernet_filter_type type
    Type of filter

struct net_eth_addr mac_address
    MAC address to filter

bool set
    Set (true) or unset (false) the filter
```

```c
struct ethernet_txtime_param
    #include <ethernet.h>

Public Members

enum ethernet_txtime_param_type type
    Type of TXTIME parameter

int queue_id
    Queue number for configuring TXTIME

bool enable_txtime
    Enable or disable TXTIME per queue
```

```c
struct ethernet_api
    #include <ethernet.h>

Public Members

struct net_if_api iface_api
    The net_if_api must be placed in first position in this struct so that we are compatible with network interface API.

int (*start)(const struct device *dev)
    Start the device

int (*stop)(const struct device *dev)
    Stop the device
```
enum ethernet_hw_caps (*get_capabilities)(const struct device *dev)
    Get the device capabilities

int (*set_config)(const struct device *dev, enum ethernet_config_type type, const struct ethernet_config *config)
    Set specific hardware configuration

int (*get_config)(const struct device *dev, enum ethernet_config_type type, struct ethernet_config *config)
    Get hardware specific configuration

int (*send)(const struct device *dev, struct net_pkt *pkt)
    Send a network packet

struct ethernet_context
    #include <ethernet.h> Ethernet L2 context that is needed for VLAN

Public Members

atomic_t flags
    Flags representing ethernet state, which are accessed from multiple threads.

struct k_work carrier_work
    Carrier ON/OFF handler worker. This is used to create network interface UP/DOWN event when ethernet L2 driver notices carrier ON/OFF situation. We must not create another network management event from inside management handler thus we use worker thread to trigger the UP/DOWN event.

struct net_if *iface
    Network interface.

denum net_l2_flags ethernet_l2_flags
    This tells what L2 features does ethernet support.

bool is_net_carrier_up
    Is network carrier up

bool is_init
    Is this context already initialized

group ethernet_mii
    Ethernet MII (media independent interface) functions.

Defines

MII_BMCR
    Basic Mode Control Register
MII_BMSR
   Basic Mode Status Register

MII_PHYID1R
   PHY ID 1 Register

MII_PHYID2R
   PHY ID 2 Register

MII_ANAR
   Auto-Negotiation Advertisement Register

MII_ANLPAR
   Auto-Negotiation Link Partner Ability Reg

MII_ANER
   Auto-Negotiation Expansion Register

MII_ANNPTR
   Auto-Negotiation Next Page Transmit Register

MII_ANLPNPR
   Auto-Negotiation Link Partner Received Next Page Reg

MII_MMD_ACR
   MMD Access Control Register

MII_MMD_AADR
   MMD Access Address Data Register

MII_ESTAT
   Extended Status Register

MII_BMCR_RESET
   PHY reset

MII_BMCR_LOOPBACK
   enable loopback mode

MII_BMCR_SPEED_LSB
   10=1000Mbps 01=100Mbps; 00=10Mbps

MII_BMCR_AUTONEG_ENABLE
   Auto-Negotiation enable

MII_BMCR_POWER_DOWN
   power down mode
MII_BMCR_ISOLATE
isolate electrically PHY from MII

MII_BMCR_AUTONEG_RESTART
restart auto-negotiation

MII_BMCR_DUPLEx_MODE
full duplex mode

MII_BMCR_SPEED_MSB
10=1000Mbps 01=100Mbps; 00=10Mbps

MII_BMCR_SPEED_MASK
Link Speed Field

MII_BMCR_SPEED_10
select speed 10 Mb/s

MII_BMCR_SPEED_100
select speed 100 Mb/s

MII_BMCR_SPEED_1000
select speed 1000 Mb/s

MII_BMSR_100BASE_T4
100BASE-T4 capable

MII_BMSR_100BASE_X_FULL
100BASE-X full duplex capable

MII_BMSR_100BASE_X_HALF
100BASE-X half duplex capable

MII_BMSR_10_FULL
10 Mb/s full duplex capable

MII_BMSR_10_HALF
10 Mb/s half duplex capable

MII_BMSR_100BASE_T2_FULL
100BASE-T2 full duplex capable

MII_BMSR_100BASE_T2_HALF
100BASE-T2 half duplex capable

MII_BMSR_EXTEND_STATUS
extend status information in reg 15
MII_BMSR_MF_PREAMB_SUPPR
   PHY accepts management frames with preamble suppressed

MII_BMSR_AUTONEG_COMPLETE
   Auto-negotiation process completed

MII_BMSR_REMOTE_FAULT
   remote fault detected

MII_BMSR_AUTONEG_ABILITY
   PHY is able to perform Auto-Negotiation

MII_BMSR_LINK_STATUS
   link is up

MII_BMSR_JABBER_DETECT
   jabber condition detected

MII_BMSR_EXTEND_CAPAB
   extended register capabilities

MII_ADVERTISE_NEXT_PAGE
   next page

MII_ADVERTISE_LPACK
   link partner acknowledge response

MII_ADVERTISE_REMOTE_FAULT
   remote fault

MII_ADVERTISEASYM_PAUSE
   try for asymmetric pause

MII_ADVERTISE_PAUSE
   try for pause

MII_ADVERTISE_100BASE_T4
   try for 100BASE-T4 support

MII_ADVERTISE_100_FULL
   try for 100BASE-X full duplex support

MII_ADVERTISE_100_HALF
   try for 100BASE-X support

MII_ADVERTISE_10_FULL
   try for 10 Mb/s full duplex support
MII_ADVERTISE_10_HALF
try for 10 Mb/s half duplex support

MII_ADVERTISE_SEL_MASK
Selector Field

MII_ADVERTISE_SEL_IEEE_802_3

MII_ADVERTISE_ALL

IEEE 802.15.4

- Overview
- API Reference
  - IEEE 802.15.4
  - IEEE 802.15.4 Management

Overview
IEEE 802.15.4 is a technical standard which defines the operation of low-rate wireless personal area networks (LR-WPANs). For more detailed overview of this standard, see this IEEE 802.15.4 Wikipedia article. Also, see IEEE GET Program for creating an IEEE account and downloading the specification.

Zephyr supports IEEE 802.15.4 with Thread and 6LoWPAN. The Thread implementation is based on OpenThread. The IPv6 header compression in 6LoWPAN is shared with the Bluetooth IPSP (IP support profile).

API Reference

IEEE 802.15.4
group ieee802154
IEEE 802.15.4 library.

Defines

IEEE802154_MAX_PHY_PACKET_SIZE

IEEE802154_FCS_LENGTH

IEEE802154_MTU

IEEE802154_SHORT_ADDR_LENGTH

IEEE802154_EXT_ADDR_LENGTH
IEEE802154_MAX_ADDR_LENGTH

IEEE802154_NO_CHANNEL

IEEE802154_BROADCAST_ADDRESS

IEEE802154_NO_SHORT_ADDRESS_ASSIGNED

IEEE802154_SHORT_ADDRESS_NOT_ASSOCIATED

IEEE802154_BROADCAST_PAN_ID

IEEE802154_L2_CTX_TYPE

IEEE802154_AR_FLAG_SET

**Typedefs**

typedef void (*energy_scan_done_cb_t)(const struct device *dev, int16_t max_ed)

typedef void (*ieee802154_event_cb_t)(const struct device *dev, enum ieee802154_event evt, void *event_params)

** Enums**

enum ieee802154_channel

IEEE 802.15.4 Channel assignments.

Channel numbering for 868 MHz, 915 MHz, and 2450 MHz bands.

- Channel 0 is for 868.3 MHz.
- Channels 1-10 are for 906 to 924 MHz with 2 MHz channel spacing.
- Channels 11-26 are for 2405 to 2530 MHz with 5 MHz channel spacing.

For more information, please refer to 802.15.4-2015 Section 10.1.2.2.

*Values:*

enumerator IEEE802154_SUB_GHZ_CHANNEL_MIN = 0

everenumerator IEEE802154_SUB_GHZ_CHANNEL_MAX = 10

everenumerator IEEE802154_2_4_GHZ_CHANNEL_MIN = 11

everenumerator IEEE802154_2_4_GHZ_CHANNEL_MAX = 26
enum ieee802154_hw_caps
  Values:

  enumerator IEEE802154_HW_FCS = BIT(0)
  enumerator IEEE802154_HW_PROMISC = BIT(1)
  enumerator IEEE802154_HW_FILTER = BIT(2)
  enumerator IEEE802154_HW_CSMA = BIT(3)
  enumerator IEEE802154_HW_2_4_GHZ = BIT(4)
  enumerator IEEE802154_HW_TX_RX_ACK = BIT(5)
  enumerator IEEE802154_HW_SUB_GHZ = BIT(6)
  enumerator IEEE802154_HW_ENERGY_SCAN = BIT(7)
  enumerator IEEE802154_HW_TXTIME = BIT(8)
  enumerator IEEE802154_HW_SLEEP_TO_TX = BIT(9)
  enumerator IEEE802154_HW_TX_SEC = BIT(10)
  enumerator IEEE802154_HW_RXTIME = BIT(11)

enum ieee802154_filter_type
  Values:

  enumerator IEEE802154_FILTER_TYPE_IEEE_ADDR
  enumerator IEEE802154_FILTER_TYPE_SHORT_ADDR
  enumerator IEEE802154_FILTER_TYPE_PAN_ID
  enumerator IEEE802154_FILTER_TYPE_SRC_IEEE_ADDR
  enumerator IEEE802154_FILTER_TYPE_SRC_SHORT_ADDR

enum ieee802154_event
  Values:

  enumerator IEEE802154_EVENT_TX_STARTED
  enumerator IEEE802154_EVENT_RX_FAILED
enumerator IEEE802154_EVENT_SLEEP

enum ieee802154_rx_fail_reason
Values:

enumerator IEEE802154_RX_FAIL_NOT_RECEIVED
enumerator IEEE802154_RX_FAIL_INVALID_FCS
enumerator IEEE802154_RX_FAIL_ADDR_FILTERED
enumerator IEEE802154_RX_FAIL_OTHER

enum ieee802154_tx_mode
IEEE802.15.4 Transmission mode.
Values:

enumerator IEEE802154_TX_MODE_DIRECT
Transmit packet immediately, no CCA.
enumerator IEEE802154_TX_MODE_CCA
Perform CCA before packet transmission.
enumerator IEEE802154_TX_MODE_CSMA_CA
Perform full CSMA CA procedure before packet transmission.
enumerator IEEE802154_TX_MODE_TXTIME
Transmit packet in the future, at specified time, no CCA.
enumerator IEEE802154_TX_MODE_TXTIME_CCA
Transmit packet in the future, perform CCA before transmission.

enum ieee802154_fpb_mode
IEEE802.15.4 Frame Pending Bit table address matching mode.
Values:

enumerator IEEE802154_FPB_ADDR_MATCH_THREAD
The pending bit shall be set only for addresses found in the list.
enumerator IEEE802154_FPB_ADDR_MATCH_ZIGBEE
The pending bit shall be cleared for short addresses found in the list.

enum ieee802154_config_type
IEEE802.15.4 driver configuration types.
Values:
enumerator IEEE802154_CONFIG_AUTO_ACK_FPB
Indicates how radio driver should set Frame Pending bit in ACK responses for Data Requests. If enabled, radio driver should determine whether to set the bit or not based on the information provided with IEEE802154_CONFIG_ACK_FPB config and FPB address matching mode specified. Otherwise, Frame Pending bit should be set to 1 (see IEEE Std 802.15.4-2006, 7.2.2.3.1).

enumerator IEEE802154_CONFIG_ACK_FPB
Indicates whether to set ACK Frame Pending bit for specific address or not. Disabling the Frame Pending bit with no address provided (NULL pointer) should disable it for all enabled addresses.

enumerator IEEE802154_CONFIG_PAN_COORDINATOR
Indicates whether the device is a PAN coordinator.

enumerator IEEE802154_CONFIG_PROMISCUOUS
Enable/disable promiscuous mode.

enumerator IEEE802154_CONFIG_EVENT_HANDLER
Specifies new radio event handler. Specifying NULL as a handler will disable radio events notification.

enumerator IEEE802154_CONFIG_MAC_KEYS
Updates MAC keys and key index for radios supporting transmit security.

enumerator IEEE802154_CONFIG_FRAME_COUNTER
Sets the current MAC frame counter value for radios supporting transmit security.

enumerator IEEE802154_CONFIG_RX_SLOT
Configure a radio reception slot. This can be used for any scheduler reception, e.g.: Zigbee GP device, CSL, TSCH, etc.

In order to configure a CSL receiver the upper layer should combine several configuration options in the following way:

i. Use IEEE802154_CONFIG_ENH_ACK_HEADER_IE once to inform the radio driver of the short and extended addresses of the peer to which it should inject CSL IEs.

ii. Use IEEE802154_CONFIG_CSL_RX_TIME periodically, before each use of IEEE802154_CONFIG_CSL_PERIOD setting parameters of the nearest CSL RX window, and before each use of IEEE_CONFIG_RX_SLOT setting parameters of the following (not the nearest one) CSL RX window, to allow the radio driver to calculate the proper CSL Phase to the nearest CSL window to inject in the CSL IEs for both transmitted data and ack frames.

iii. Use IEEE802154_CONFIG_CSL_PERIOD on each value change to update the current CSL period value which will be injected in the CSL IEs together with the CSL Phase based on IEEE802154_CONFIG_CSL_RX_TIME.

iv. Use IEEE802154_CONFIG_RX_SLOT periodically to schedule the immediate receive window earlier enough before the expected window start time, taking into account possible clock drifts and scheduling uncertainties.

This diagram shows the usage of the four options over time: Start CSL Schedule CSL window

```
1882 Chapter 6. Connectivity
```
enumerator IEEE802154_CONFIG_CSL_PERIOD
  Configure CSL receiver (Endpoint) period

enumerator IEEE802154_CONFIG_CSL_RX_TIME
  Configure the next CSL receive window center, in units of microseconds, based on the
  radio time.

enumerator IEEE802154_CONFIG_ENH_ACK_HEADER_IE
  Indicates whether to inject IE into ENH ACK Frame for specific address or not. Disabling
  the ENH ACK with no address provided (NULL pointer) should disable it for all enabled
  addresses.

Functions

static inline bool ieee802154_is_ar_flag_set(struct net_buf *frag)
  Check if AR flag is set on the frame inside given net_pkt.

  Parameters
  • frag – A valid pointer on a net_buf structure, must not be NULL, and its length
    should be at least made of 1 byte (ACK frames are the smallest frames on 15.4
    and made of 3 bytes, not not counting the FCS part).

  Returns
  True if AR flag is set, False otherwise

enum net_verdict ieee802154_radio_handle_ack(struct net_if *iface, struct net_pkt *pkt)
  Radio driver ACK handling function that hw drivers should use.
  ACK handling requires fast handling and thus such function helps to hook directly the hw
  drivers to the radio driver.

  Parameters
  • iface – A valid pointer on a network interface that received the packet
  • pkt – A valid pointer on a packet to check

  Returns
  NET_OK if it was handled, NET_CONTINUE otherwise

void ieee802154_init(struct net_if *iface)
  Initialize L2 stack for a given interface.

  Parameters
  • iface – A valid pointer on a network interface

struct ieee802154_security_ctx
  #include <ieee802154.h>

struct ieee802154_context
  #include <ieee802154.h>

struct ieee802154_filter
  #include <ieee802154_radio.h>
struct ieee802154_key
   #include <ieee802154_radio.h>

struct ieee802154_config
   #include <ieee802154_radio.h> IEEE802.15.4 driver configuration data.

Public Members

struct ieee802154_config.[anonymous].[anonymous] auto_ack_fpb
   IEEE802154_CONFIG_AUTO_ACK_FPB

struct ieee802154_config.[anonymous].[anonymous] ack_fpb
   IEEE802154_CONFIG_ACK_FPB

bool pan_coordinator
   IEEE802154_CONFIG_PAN_COORDINATOR

bool promiscuous
   IEEE802154_CONFIG_PROMISCUOUS

ieee802154_event_cb_t event_handler
   IEEE802154_CONFIG_EVENT_HANDLER

struct ieee802154_key *mac_keys
   IEEE802154_CONFIG_MAC_KEYS Pointer to an array containing a list of keys used for MAC encryption. Refer to secKeyIdLookupDescriptor and secKeyDescriptor in IEEE 802.15.4
   key_value field points to a buffer containing the 16 byte key. The buffer is copied by the callee.
   The variable length array is terminated by key_value field set to NULL.

uint32_t frame_counter
   IEEE802154_CONFIG_FRAME_COUNTER

struct ieee802154_config.[anonymous].[anonymous] rx_slot
   IEEE802154_CONFIG_RX_SLOT

uint32_t csl_period
   IEEE802154_CONFIG_CSL_PERIOD

uint32_t csl_rx_time
   IEEE802154_CONFIG_CSL_RX_TIME

const uint8_t *ext_addr
   The extended address is expected to be passed starting with the most significant octet and ending with the least significant octet. A device with an extended address 01:23:45:67:89:ab:cd:ef as written in the usual big-endian hex notation should provide a pointer to an array containing values in the exact same order.
struct ieee802154_config.[anonymous].[anonymous] ack_ie
    IEEE802154_CONFIG_ENH_ACK_HEADER_IE

union ieee802154_config.[anonymous] [anonymous]
    Configuration data.

struct ieee802154_radio_api
    #include <ieee802154_radio.h> IEEE 802.15.4 radio interface API.

Public Members

struct net_if_api iface_api
    Mandatory to get in first position. A network device should indeed provide a pointer on such net_if_api structure. So we make current structure pointer that can be casted to a net_if_api structure pointer.

genius ieee802154_hw_caps (*get_capabilities)(const struct device *dev)
    Get the device capabilities

int (*cca)(const struct device *dev)
    Clear Channel Assessment - Check channel's activity

int (*set_channel)(const struct device *dev, uint16_t channel)
    Set current channel, channel is in CPU byte order.

int (*filter)(const struct device *dev, bool set, enum ieee802154_filter_type type, const struct ieee802154_filter *filter)
    Set/Unset filters (for IEEE802154_HW_FILTER )

int (*set_txpower)(const struct device *dev, int16_t dbm)
    Set TX power level in dbm

int (*tx)(const struct device *dev, enum ieee802154_tx_mode mode, struct net_pkt *pkt, struct net_buf *frag)
    Transmit a packet fragment

int (*start)(const struct device *dev)
    Start the device

int (*stop)(const struct device *dev)
    Stop the device

int (*configure)(const struct device *dev, enum ieee802154_config_type type, const struct ieee802154_config *config)
    Set specific radio driver configuration.

uint16_t (*get_subg_channel_count)(const struct device *dev)
    Get the available amount of Sub-GHz channels
int (*ed_scan)(const struct device *dev, uint16_t duration, energy_scan_done_cb_t done_cb)
Run an energy detection scan. Note: channel must be set prior to request this function.
duration parameter is in ms.

uint64_t (*get_time)(const struct device *dev)
Get the current radio time in microseconds

uint8_t (*get_sch_acc)(const struct device *dev)
Get the current accuracy, in units of ± ppm, of the clock used for scheduling delayed
receive or transmit radio operations. Note: Implementations may optimize this value
based on operational conditions (i.e.: temperature).

IEEE 802.15.4 Management

group ieee802154_mgmt
IEEE 802.15.4 net management library.

Defines

NET_REQUEST_IEEE802154_SET_ACK
NET_REQUEST_IEEE802154_UNSET_ACK
NET_REQUEST_IEEE802154_PASSIVE_SCAN
NET_REQUEST_IEEE802154_ACTIVE_SCAN
NET_REQUEST_IEEE802154_CANCEL_SCAN
NET_REQUEST_IEEE802154_ASSOCIATE
NET_REQUEST_IEEE802154_DISASSOCIATE
NET_REQUEST_IEEE802154_SET_CHANNEL
NET_REQUEST_IEEE802154_GET_CHANNEL
NET_REQUEST_IEEE802154_SET_PAN_ID
NET_REQUEST_IEEE802154_GET_PAN_ID
NET_REQUEST_IEEE802154_SET_EXT_ADDR
NET_REQUEST_IEEE802154_GET_EXT_ADDR
NET_REQUEST_IEEE802154_SET_SHORT_ADDR
NET_REQUEST_IEEE802154_GET_SHORT_ADDR

NET_REQUEST_IEEE802154_GET_TX_POWER

NET_REQUEST_IEEE802154_SET_TX_POWER

NET_EVENT_IEEE802154_SCAN_RESULT

IEEE802154_IS_CHAN_SCANNED(_channel_set, _chan)
IEEE802154_IS_CHAN_UNSCANNED(_channel_set, _chan)

IEEE802154_ALL_CHANNELS

Enums

enum net_request_ieee802154_cmd

Values:

enumerator NET_REQUEST_IEEE802154_CMD_SET_ACK = 1
enumerator NET_REQUEST_IEEE802154_CMD_UNSET_ACK
enumerator NET_REQUEST_IEEE802154_CMD_PASSIVE_SCAN
enumerator NET_REQUEST_IEEE802154_CMD_ACTIVE_SCAN
enumerator NET_REQUEST_IEEE802154_CMD_CANCEL_SCAN
enumerator NET_REQUEST_IEEE802154_CMD_ASSOCIATE
enumerator NET_REQUEST_IEEE802154_CMD_DISASSOCIATE
enumerator NET_REQUEST_IEEE802154_CMD_SET_CHANNEL
enumerator NET_REQUEST_IEEE802154_CMD_GET_CHANNEL
enumerator NET_REQUEST_IEEE802154_CMD_SET_PAN_ID
enumerator NET_REQUEST_IEEE802154_CMD_GET_PAN_ID
enumerator NET_REQUEST_IEEE802154_CMD_SET_EXT_ADDR
enumerator NET_REQUEST_IEEE802154_CMD_GET_EXT_ADDR
enumerator NET_REQUEST_IEEE802154_CMD_SET_SHORT_ADDR
enumerator NET_REQUEST_IEEE802154_CMD_GET_SHORT_ADDR

enumerator NET_REQUEST_IEEE802154_CMD_GET_TX_POWER

enumerator NET_REQUEST_IEEE802154_CMD_SET_TX_POWER

enumerator NET_REQUEST_IEEE802154_CMD_SET_SECURITY_SETTINGS

enumerator NET_REQUEST_IEEE802154_CMD_GET_SECURITY_SETTINGS

enum net_event_ieee802154_cmd

   Values:

enumerator NET_EVENT_IEEE802154_CMD_SCAN_RESULT = 1

struct ieee802154_req_params
   
#include <ieee802154_mgmt.h> Scanning parameters.

   Used to request a scan and get results as well

   Public Members

   uint32_t channel_set
      The set of channels to scan, use above macros to manage it

   uint32_t duration
      Duration of scan, per-channel, in milliseconds

   uint16_t channel
      Current channel in use as a result

   uint16_t pan_id
      Current pan_id in use as a result

   union ieee802154_req_params.[anonymous] [anonymous]
      Result address

   uint8_t len
      length of address

   uint8_t lqi
      Link quality information, between 0 and 255

struct ieee802154_security_params
   
#include <ieee802154_mgmt.h> Security parameters.

   Used to setup the link-layer security settings
Thread protocol

- **Overview**
- **Internet connectivity**
- **Sample usage**

**Overview**  Thread is a low-power mesh networking technology, designed specifically for home automation applications. It is an IPv6-based standard, which uses 6LoWPAN technology over IEEE 802.15.4 protocol. IP connectivity lets you easily connect a Thread mesh network to the internet with a Thread Border Router.

The Thread specification provides a high level of network security. Mesh networks built with Thread are secure - only authenticated devices can join the network and all communications within the mesh are encrypted. More information about Thread protocol can be found at [Thread Group website](#).

Zephyr integrates an open source Thread protocol implementation called OpenThread, documented on the [OpenThread website](#).

**Internet connectivity**  A Thread Border Router is required to connect mesh network to the internet. An open source implementation of Thread Border Router is provided by the OpenThread community. See [OpenThread Border Router guide](#) for instructions on how to set up a Border Router.

**Sample usage**  You can try using OpenThread with the Zephyr Echo server and Echo client samples, which provide out-of-the-box configuration for OpenThread. To enable OpenThread support in these samples, build them with `overlay-ot.conf` overlay config file. See [sockets-echo-server-sample](#) and [sockets-echo-client-sample](#) for details.

Point-to-Point Protocol (PPP) Support

- **Overview**
- **Testing**

**Overview**  Point-to-Point Protocol (PPP) is a data link layer (layer 2) communications protocol used to establish a direct connection between two nodes. PPP is used over many types of serial links since IP packets cannot be transmitted over a modem line on their own, without some data link protocol.

In Zephyr, each individual PPP link is modelled as a network interface. This is similar to how Linux implements PPP.

PPP support must be enabled at compile time by setting option `CONFIG_NET_PPP` and `CONFIG_NET_L2_PPP`. The PPP support in Zephyr 2.0 is still experimental and the implementation supports only these protocols:

- LCP (Link Control Protocol, RFC1661)
- HDLC (High-level data link control, RFC1662)
- IPCP (IP Control Protocol, RFC1332)
- IPV6CP (IPv6 Control Protocol, RFC5072)

See also the `samples/net/sockets/echo_server/overlay-ppp.conf` file for configuration option examples. For using PPP with GSM modem, see [Generic GSM Modem](#) for additional information.
Testing  See the net-tools README file for more details on how to test the Zephyr PPP against pppd running in Linux.

Protocols

CoAP

- **Overview**
- **Sample Usage**
  - CoAP Server
  - CoAP Client
- **Testing**
  - libcoap
  - TTCN3
- **API Reference**

Overview  The Constrained Application Protocol (CoAP) is a specialized web transfer protocol for use with constrained nodes and constrained (e.g., low-power, lossy) networks. It provides a convenient API for RESTful Web services that support CoAP's features. For more information about the protocol itself, see IETF RFC7252 The Constrained Application Protocol.

Zephyr provides a CoAP library which supports client and server roles. The library is configurable as per user needs. The Zephyr CoAP library is implemented using plain buffers. Users of the API create sockets for communication and pass the buffer to the library for parsing and other purposes. The library itself doesn't create any sockets for users.

On top of CoAP, Zephyr has support for LWM2M “Lightweight Machine 2 Machine” protocol, a simple, low-cost remote management and service enablement mechanism. See Lightweight M2M (LWM2M) for more information.

Supported RFCs:

Supported RFCs:

- RFC7252: The Constrained Application Protocol (CoAP)
- RFC6690: Constrained RESTful Environments (CoRE) Link Format
- RFC7959: Block-Wise Transfers in the Constrained Application Protocol (CoAP)
- RFC7641: Observing Resources in the Constrained Application Protocol (CoAP)

Note:  Not all parts of these RFCs are supported. Features are supported based on Zephyr requirements.

Sample Usage

CoAP Server  To create a CoAP server, resources for the server need to be defined. The `.well-known/core` resource should be added before all other resources that should be included in the responses of the `.well-known/core` resource.
```c
static struct coap_resource resources[] = {
    { .get = well_known_core_get,
      .path = COAP_WELL_KNOWN_CORE_PATH,
    },
    { .get = sample_get,
      .post = sample_post,
      .del = sample_del,
      .put = sample_put,
      .path = sample_path
    },
};
```

An application reads data from the socket and passes the buffer to the CoAP library to parse the message. If the CoAP message is proper, the library uses the buffer along with resources defined above to call the correct callback function to handle the CoAP request from the client. It's the callback function's responsibility to either reply or act according to CoAP request.

```c
coap_packet_parse(&request, data, data_len, options, opt_num);
...
coap_handle_request(&request, resources, options, opt_num,
    client_addr, client_addr_len);
```

If CONFIG_COAP_URI_WILDCARD enabled, server may accept multiple resources using MQTT-like wildcard style:

- the plus symbol represents a single-level wild card in the path;
- the hash symbol represents the multi-level wild card in the path.

```c
static const char * const led_set[] = { "led","+", "set", NULL };
static const char * const btn_get[] = { "button","#", NULL };
static const char * const no_wc[] = { "test","+1", NULL };
```

It accepts /led/0/set, led/1234/set, led/any/set, /button/door/1, /test/+1, but returns -ENOENT for /led/1, /test/21, /test/1.

This option is enabled by default, disable it to avoid unexpected behaviour with resource path like '/some_resource/+/#'.

**CoAP Client** If the CoAP client knows about resources in the CoAP server, the client can start prepare CoAP requests and wait for responses. If the client doesn’t know about resources in the CoAP server, it can request resources through the .well-known/core CoAP message.

```c
/* Initialize the CoAP message */
char *path = "test";
struct coap_packet request;
uint8_t data[100];
uint8_t payload[20];

coap_packet_init(&request, data, sizeof(data),
    1, COAP_TYPE_CON, 8, coap_next_token(),
    COAP_METHOD_GET, coap_next_id());

/* Append options */
coap_packet_append_option(&request, COAP_OPTION_URI_PATH,
    path, strlen(path));
```

(continues on next page)
Testing  There are various ways to test Zephyr CoAP library.

libcoap  libcoap implements a lightweight application-protocol for devices that are resource constrained, such as by computing power, RF range, memory, bandwidth, or network packet sizes. Sources can be found here libcoap. libcoap has a script (examples/etsi_coaptest.sh) to test coap-server functionality in Zephyr.

See the net-tools project for more details.

The coap-server-sample sample can be built and executed on QEMU as described in Networking with QEMU.

Use this command on the host to run the libcoap implementation of the ETSI test cases:

```bash
sudo ./libcoap/examples/etsi_coaptest.sh -i tap0 2001:db8::1
```

TTCN3  Eclipse has TTCN3 based tests to run against CoAP implementations.

Install eclipse-titan and set symbolic links for titan tools

```bash
sudo apt-get install eclipse-titan
cd /usr/share/titan
sudo ln -s /usr/bin bin
sudo ln /usr/bin/titanver bin
sudo ln -s /usr/bin/mctr_cli bin
sudo ln -s /usr/include/titan include
sudo ln -s /usr/lib/titan lib
export TTCN3_DIR=/usr/share/titan
git clone https://github.com/eclipse/titan.misc.git
cd titan.misc
```

Follow the instruction to setup CoAP test suite from here:

- https://github.com/eclipse/titan.misc
- https://github.com/eclipse/titan.misc/tree/master/CoAP_Conf

After the build is complete, the coap-server-sample sample can be built and executed on QEMU as described in Networking with QEMU.

Change the client (test suite) and server (Zephyr coap-server sample) addresses in coap.cfg file as per your setup.

Execute the test cases with following command.
ttcn3_start coaptests coap.cfg

Sample output of ttcn3 tests looks like this.

Verdict statistics: 0 none (0.00 %), 10 pass (100.00 %), 0 inconc (0.00 %), 0 fail (0.00 %), 0 error (0.00 %).
Test execution summary: 10 test cases were executed. Overall verdict: pass

API Reference

group coap
    COAP library.

Defines

    COAP_REQUEST_MASK

    COAP_VERSION_1
    coap_make_response_code(class, det)

    COAP_CODE_EMPTY

    COAP_TOKEN_MAX_LEN

    GET_BLOCK_NUM(v)

    GET_BLOCK_SIZE(v)

    GET_MORE(v)

    COAP_WELL_KNOWN_CORE_PATH
    This resource should be added before all other resources that should be included in the responses of the .well-known/core resource.

Typedefs

typedef int (*coap_method_t)(struct coap_resource *resource, struct coap_packet *request, struct sockaddr *addr, socklen_t addr_len)
    Type of the callback being called when a resource's method is invoked by the remote entity.

typedef void (*coap_notify_t)(struct coap_resource *resource, struct coap_observer *observer)
    Type of the callback being called when a resource's has observers to be informed when an update happens.

typedef int (*coap_reply_t)(const struct coap_packet *response, struct coap_reply *reply, const struct sockaddr *from)
    Helper function to be called when a response matches the a pending request.
Enums

enum coap_option_num
  Set of CoAP packet options we are aware of.

  Users may add options other than these to their packets, provided they know how to format them correctly. The only restriction is that all options must be added to a packet in numeric order.

  Refer to RFC 7252, section 12.2 for more information.

Values:

enumerator COAP_OPTION_IF_MATCH = 1
enumerator COAP_OPTION_URI_HOST = 3
enumerator COAP_OPTION_ETAG = 4
enumerator COAP_OPTION_IF_NONE_MATCH = 5
enumerator COAP_OPTION_OBSERVE = 6
enumerator COAP_OPTION_URI_PORT = 7
enumerator COAP_OPTION_LOCATION_PATH = 8
enumerator COAP_OPTION_URI_PATH = 11
enumerator COAP_OPTION_CONTENT_FORMAT = 12
enumerator COAP_OPTION_MAX_AGE = 14
enumerator COAP_OPTION_URI_QUERY = 15
enumerator COAP_OPTION_ACCEPT = 17
enumerator COAP_OPTION_LOCATION_QUERY = 20
enumerator COAP_OPTION_BLOCK2 = 23
enumerator COAP_OPTION_BLOCK1 = 27
enumerator COAP_OPTION_SIZE2 = 28
enumerator COAP_OPTION_PROXY_URI = 35
enumerator COAP_OPTION_PROXY_SCHEME = 39
enumerator COAP_OPTION_SIZE1 = 60

enum coap_method
    Available request methods.
    To be used when creating a request or a response.
    Values:

    enumerator COAP_METHOD_GET = 1
    enumerator COAP_METHOD_POST = 2
    enumerator COAP_METHOD_PUT = 3
    enumerator COAP_METHOD_DELETE = 4
    enumerator COAP_METHOD_FETCH = 5
    enumerator COAP_METHOD_PATCH = 6
    enumerator COAP_METHOD_IPATCH = 7

enum coap_msgtype
    CoAP packets may be of one of these types.
    Values:

    enumerator COAP_TYPE_CON = 0
        Confirmable message.
        The packet is a request or response the destination end-point must acknowledge.

    enumerator COAP_TYPE_NON_CON = 1
        Non-confirmable message.
        The packet is a request or response that doesn’t require acknowledgements.

    enumerator COAP_TYPE_ACK = 2
        Acknowledge.
        Response to a confirmable message.

    enumerator COAP_TYPE_RESET = 3
        Reset.
        Rejecting a packet for any reason is done by sending a message of this type.

enum coap_response_code
    Set of response codes available for a response packet.
    To be used when creating a response.
    Values:
<table>
<thead>
<tr>
<th>Enumerator</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>COAP_RESPONSE_CODE_OK</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_CREATED</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_DELETED</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_VALID</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_CHANGED</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_CONTENT</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_CONTINUE</td>
<td>(((2 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_BAD_REQUEST</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_UNAUTHORIZED</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_BAD_OPTION</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_FORBIDDEN</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_NOT_FOUND</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_NOT_ALLOWED</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_NOT_ACCEPTABLE</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_INCOMPLETE</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_CONFLICT</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_PRECONDITION_FAILED</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_REQUEST_TOO_LARGE</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_UNSUPPORTED_CONTENT_FORMAT</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_UNPROCESSABLE_ENTITY</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_TOO_MANY_REQUESTS</td>
<td>(((4 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_INTERNAL_ERROR</td>
<td>(((5 &lt;&lt; 5)</td>
</tr>
<tr>
<td>COAP_RESPONSE_CODE_NOT_IMPLEMENTED</td>
<td>(((5 &lt;&lt; 5)</td>
</tr>
</tbody>
</table>
enumerator COAP_RESPONSE_CODE_BAD_GATEWAY = ((5 << 5) | (2))

enumerator COAP_RESPONSE_CODE_SERVICE_UNAVAILABLE = ((5 << 5) | (3))

enumerator COAP_RESPONSE_CODE_GATEWAY_TIMEOUT = ((5 << 5) | (4))

enumerator COAP_RESPONSE_CODE_PROXYING_NOT_SUPPORTED = ((5 << 5) | (5))

definition coap_content_format
Set of Content-Format option values for CoAP.
To be used when encoding or decoding a Content-Format option.

Values:

enumerator COAP_CONTENT_FORMAT_TEXT_PLAIN = 0

enumerator COAP_CONTENT_FORMAT_APP_LINK_FORMAT = 40

enumerator COAP_CONTENT_FORMAT_APP_XML = 41

enumerator COAP_CONTENT_FORMAT_APP_OCTET_STREAM = 42

enumerator COAP_CONTENT_FORMAT_APP_EXI = 47

enumerator COAP_CONTENT_FORMAT_APP_JSON = 50

enumerator COAP_CONTENT_FORMAT_APP_JSON_PATCH_JSON = 51

enumerator COAP_CONTENT_FORMAT_APP_MERGE_PATCH_JSON = 52

enumerator COAP_CONTENT_FORMAT_APP_CBOR = 60

definition coap_block_size
Represents the size of each block that will be transferred using block-wise transfers [RFC7959]:
Each entry maps directly to the value that is used in the wire.

Values:

enumerator COAP_BLOCK_16

enumerator COAP_BLOCK_32

enumerator COAP_BLOCK_64

enumerator COAP_BLOCK_128
enumerator COAP_BLOCK_256
enumerator COAP_BLOCK_512
enumerator COAP_BLOCK_1024

Functions

uint8_t coap_header_get_version(const struct coap_packet *cpkt)
Returns the version present in a CoAP packet.

Parameters
• cpkt – CoAP packet representation

Returns
the CoAP version in packet

uint8_t coap_header_get_type(const struct coap_packet *cpkt)
Returns the type of the CoAP packet.

Parameters
• cpkt – CoAP packet representation

Returns
the type of the packet

uint8_t coap_header_get_token(const struct coap_packet *cpkt, uint8_t *token)
Returns the token (if any) in the CoAP packet.

Parameters
• cpkt – CoAP packet representation

Returns
Token length in the CoAP packet (0 - COAP_TOKEN_MAX_LEN).

uint8_t coap_header_get_code(const struct coap_packet *cpkt)
Returns the code of the CoAP packet.

Parameters
• cpkt – CoAP packet representation

Returns
the code present in the packet

uint16_t coap_header_get_id(const struct coap_packet *cpkt)
Returns the message id associated with the CoAP packet.

Parameters
• cpkt – CoAP packet representation

Returns
the message id present in the packet
const uint8_t *coap_packet_get_payload(const struct coap_packet *cpkt, uint16_t *len)

Returns the data pointer and length of the CoAP packet.

Parameters
• cpkt – CoAP packet representation
• len – Total length of CoAP payload

Returns
data pointer and length if payload exists NULL pointer and length set to 0 in case there is no payload

int coap_packet_parse(struct coap_packet *cpkt, uint8_t *data, uint16_t len, struct coap_option *options, uint8_t opt_num)

Parses the CoAP packet in data, validating it and initializing cpkt. data must remain valid while cpkt is used.

Parameters
• cpkt – Packet to be initialized from received data.
• data – Data containing a CoAP packet, its data pointer is positioned on the start of the CoAP packet.
• len – Length of the data
• options – Parse options and cache its details.
• opt_num – Number of options

Return values
• 0 – in case of success.
• -EINVAL – in case of invalid input args.
• -EBADMSG – in case of malformed coap packet header.
• -EINVAL – in case of malformed coap options.

int coap_packet_init(struct coap_packet *cpkt, uint8_t *data, uint16_t max_len, uint8_t ver, uint8_t type, uint8_t token_len, const uint8_t *token, uint8_t code, uint16_t id)

Creates a new CoAP Packet from input data.

Parameters
• cpkt – New packet to be initialized using the storage from data.
• data – Data that will contain a CoAP packet information
• max_len – Maximum allowable length of data
• ver – CoAP header version
• type – CoAP header type
• token_len – CoAP header token length
• token – CoAP header token
• code – CoAP header code
• id – CoAP header message id

Returns
0 in case of success or negative in case of error.
int coap_ack_init(struct coap_packet *cpkt, const struct coap_packet *req, uint8_t *data, uint16_t max_len, uint8_t code)

Create a new CoAP Acknowledgment message for given request.

This function works like coap_packet_init, filling CoAP header type, CoAP header token, and CoAP header message id fields according to acknowledgment rules.

Parameters
• cpkt – New packet to be initialized using the storage from data.
• req – CoAP request packet that is being acknowledged
• data – Data that will contain a CoAP packet information
• max_len – Maximum allowable length of data
• code – CoAP header code

Returns
0 in case of success or negative in case of error.

uint8_t *coap_next_token(void)

Returns a randomly generated array of 8 bytes, that can be used as a message's token.

Returns
a 8-byte pseudo-random token.

uint16_t coap_next_id(void)

Helper to generate message ids.

Returns
a new message id

int coap_find_options(const struct coap_packet *cpkt, uint16_t code, struct coap_option *options, uint16_t veclen)

Return the values associated with the option of value code.

Parameters
• cpkt – CoAP packet representation
• code – Option number to look for
• options – Array of coap_option where to store the value of the options found
• veclen – Number of elements in the options array

Returns
The number of options found in packet matching code, negative on error.

int coap_packet_append_option(struct coap_packet *cpkt, uint16_t code, const uint8_t *value, uint16_t len)

Appends an option to the packet.

Note: options must be added in numeric order of their codes. Otherwise error will be returned. TODO: Add support for placing options according to its delta value.

Parameters
• cpkt – Packet to be updated
• code – Option code to add to the packet, see coap_option_num
• value – Pointer to the value of the option, will be copied to the packet
• len – Size of the data to be added

Returns
0 in case of success or negative in case of error.
unsigned int coap_option_value_to_int(const struct coap_option *option)

Converts an option to its integer representation.

Assumes that the number is encoded in the network byte order in the option.

**Parameters**

- option – Pointer to the option value, retrieved by coap_find_options()

**Returns**

The integer representation of the option

int coap_append_option_int(struct coap_packet *cpkt, uint16_t code, unsigned int val)

Appends an integer value option to the packet.

The option must be added in numeric order of their codes, and the least amount of bytes will be used to encode the value.

**Parameters**

- cpkt – Packet to be updated
- code – Option code to add to the packet, see coap_option_num
- val – Integer value to be added

**Returns**

0 in case of success or negative in case of error.

int coap_packet_append_payload_marker(struct coap_packet *cpkt)

Append payload marker to CoAP packet.

**Parameters**

- cpkt – Packet to append the payload marker (0xFF)

**Returns**

0 in case of success or negative in case of error.

int coap_packet_append_payload(struct coap_packet *cpkt, const uint8_t *payload, uint16_t payload_len)

Append payload to CoAP packet.

**Parameters**

- cpkt – Packet to append the payload
- payload – CoAP packet payload
- payload_len – CoAP packet payload len

**Returns**

0 in case of success or negative in case of error.

int coap_handle_request(struct coap_packet *cpkt, struct coap_resource *resources, struct coap_option *options, uint8_t opt_num, struct sockaddr *addr, socklen_t addr_len)

When a request is received, call the appropriate methods of the matching resources.

**Parameters**

- cpkt – Packet received
- resources – Array of known resources
- options – Parsed options from coap_packet_parse()
- opt_num – Number of options
- addr – Peer address
• addr_len – Peer address length

Return values
• 0 – in case of success.
• -ENOTSUP – in case of invalid request code.
• -EPERM – in case resource handler is not implemented.
• -ENOENT – in case the resource is not found.

static inline uint16_t coap_block_size_to_bytes(enum coap_block_size block_size)
Helper for converting the enumeration to the size expressed in bytes.

Parameters
• block_size – The block size to be converted

Returns
The size in bytes that the block_size represents

int coap_block_transfer_init(struct coap_block_context *ctx, enum coap_block_size block_size, size_t total_size)
Initializes the context of a block-wise transfer.

Parameters
• ctx – The context to be initialized
• block_size – The size of the block
• total_size – The total size of the transfer, if known

Returns
0 in case of success or negative in case of error.

int coap_append_block1_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append BLOCK1 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Block1 option

Returns
0 in case of success or negative in case of error.

int coap_append_block2_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append BLOCK2 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Block2 option

Returns
0 in case of success or negative in case of error.

int coap_append_size1_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append SIZE1 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Size1 option
Returns
0 in case of success or negative in case of error.

int coap_append_size2_option(struct coap_packet *cpkt, struct coap_block_context *ctx)
Append SIZE2 option to the packet.

Parameters
• cpkt – Packet to be updated
• ctx – Block context from which to retrieve the information for the Size2 option

Returns
0 in case of success or negative in case of error.

int coap_get_option_int(const struct coap_packet *cpkt, uint16_t code)
Get the integer representation of a CoAP option.

Parameters
• cpkt – Packet to be inspected
• code – CoAP option code

Returns
Integer value >= 0 in case of success or negative in case of error.

int coap_update_from_block(const struct coap_packet *cpkt, struct coap_block_context *ctx)
Retrieves BLOCK{1,2} and SIZE{1,2} from cpkt and updates ctx accordingly.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated

Returns
0 in case of success or negative in case of error.

int coap_next_block_for_option(const struct coap_packet *cpkt, struct coap_block_context *ctx,
                             enum coap_option_num option)
Updates ctx according to option set in cpkt so after this is called the current entry indicates the correct offset in the body of data being transferred.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated
• option – Either COAP_OPTION_BLOCK1 or COAP_OPTION_BLOCK2

Returns
The offset in the block-wise transfer, 0 if the transfer has finished or a negative value in case of an error.

size_t coap_next_block(const struct coap_packet *cpkt, struct coap_block_context *ctx)
Updates ctx so after this is called the current entry indicates the correct offset in the body of data being transferred.

Parameters
• cpkt – Packet in which to look for block-wise transfers options
• ctx – Block context to be updated

Returns
The offset in the block-wise transfer, 0 if the transfer has finished.
void coap_observer_init(struct coap_observer *observer, const struct coap_packet *request, const struct sockaddr *addr)

Indicates that the remote device referenced by `addr`, with `request`, wants to observe a resource.

**Parameters**

- `observer` – Observer to be initialized
- `request` – Request on which the observer will be based
- `addr` – Address of the remote device

bool coap_register_observer(struct coap_resource *resource, struct coap_observer *observer)

After the observer is initialized, associate the observer with an resource.

**Parameters**

- `resource` – Resource to add an observer
- `observer` – Observer to be added

**Returns**

true if this is the first observer added to this resource.

void coap_remove_observer(struct coap_resource *resource, struct coap_observer *observer)

Remove this observer from the list of registered observers of that resource.

**Parameters**

- `resource` – Resource in which to remove the observer
- `observer` – Observer to be removed

struct coap_observer *coap_find_observer_by_addr(struct coap_observer *observers, size_t len, const struct sockaddr *addr)

Returns the observer that matches address `addr`.

**Parameters**

- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers
- `addr` – Address of the endpoint observing a resource

**Returns**

A pointer to a observer if a match is found, NULL otherwise.

struct coap_observer *coap_observer_next_unused(struct coap_observer *observers, size_t len)

Returns the next available observer representation.

**Parameters**

- `observers` – Pointer to the array of observers
- `len` – Size of the array of observers

**Returns**

A pointer to a observer if there's an available observer, NULL otherwise.

void coap_reply_init(struct coap_reply *reply, const struct coap_packet *request)

Indicates that a reply is expected for `request`.

**Parameters**

- `reply` – Reply structure to be initialized
- `request` – Request from which `reply` will be based
int coap_pending_init(struct coap_pending *pending, const struct coap_packet *request, const struct sockaddr *addr, uint8_t retries)

Initialize a pending request with a request.

The request’s fields are copied into the pending struct, so request doesn’t have to live for as long as the pending struct lives, but “data” that needs to live for at least that long.

**Parameters**

- `pending` – Structure representing the waiting for a confirmation message, initialized with data from `request`
- `request` – Message waiting for confirmation
- `addr` – Address to send the retransmission
- `retries` – Maximum number of retransmissions of the message.

**Returns**

0 in case of success or negative in case of error.

struct coap_pending *coap_pending_next_unused(struct coap_pending *pendings, size_t len)

Returns the next available pending struct, that can be used to track the retransmission status of a request.

**Parameters**

- `pendings` – Pointer to the array of `coap_pending` structures
- `len` – Size of the array of `coap_pending` structures

**Returns**

pointer to a free `coap_pending` structure, NULL in case none could be found.

struct coap_reply *coap_reply_next_unused(struct coap_reply *replies, size_t len)

Returns the next available reply struct, so it can be used to track replies and notifications received.

**Parameters**

- `replies` – Pointer to the array of `coap_reply` structures
- `len` – Size of the array of `coap_reply` structures

**Returns**

pointer to a free `coap_reply` structure, NULL in case none could be found.

struct coap_pending *coap_pending_received(const struct coap_packet *response, struct coap_pending *pendings, size_t len)

After a response is received, returns if there is any matching pending request exits. User has to clear all pending retransmissions related to that response by calling `coap_pending_clear()`.

**Parameters**

- `response` – The received response
- `pendings` – Pointer to the array of `coap_reply` structures
- `len` – Size of the array of `coap_reply` structures

**Returns**

pointer to the associated `coap_pending` structure, NULL in case none could be found.

struct coap_reply *coap_response_received(const struct coap_packet *response, const struct sockaddr *from, struct coap_reply *replies, size_t len)

After a response is received, call coap_reply_t handler registered in `coap_reply` structure.
Parameters

- response – A response received
- from – Address from which the response was received
- replies – Pointer to the array of \texttt{coap\_reply} structures
- len – Size of the array of \texttt{coap\_reply} structures

Returns

Pointer to the reply matching the packet received, NULL if none could be found.

\begin{verbatim}
struct coap\_pending *coap\_pending\_next\_to\_expire(struct coap\_pending *pendings, size\_t len)
\end{verbatim}

Returns the next pending about to expire, pending->timeout informs how many ms to next expiration.

Parameters

- pendings – Pointer to the array of \texttt{coap\_pending} structures
- len – Size of the array of \texttt{coap\_pending} structures

Returns

The next \texttt{coap\_pending} to expire, NULL if none is about to expire.

\begin{verbatim}
bool coap\_pending\_cycle(struct coap\_pending *pending)
\end{verbatim}

After a request is sent, user may want to cycle the pending retransmission so the timeout is updated.

Parameters

- pending – Pending representation to have its timeout updated

Returns

false if this is the last retransmission.

\begin{verbatim}
void coap\_pending\_clear(struct coap\_pending *pending)
\end{verbatim}

Cancels the pending retransmission, so it again becomes available.

Parameters

- pending – Pending representation to be canceled

\begin{verbatim}
void coap\_pendings\_clear(struct coap\_pending *pendings, size\_t len)
\end{verbatim}

Cancels all pending retransmissions, so they become available again.

Parameters

- pendings – Pointer to the array of \texttt{coap\_pending} structures
- len – Size of the array of \texttt{coap\_pending} structures

\begin{verbatim}
void coap\_reply\_clear(struct coap\_reply *reply)
\end{verbatim}

Cancels awaiting for this reply, so it becomes available again. User responsibility to free the memory associated with data.

Parameters

- reply – The reply to be canceled

\begin{verbatim}
void coap\_replies\_clear(struct coap\_reply *replies, size\_t len)
\end{verbatim}

Cancels all replies, so they become available again.

Parameters

- replies – Pointer to the array of \texttt{coap\_reply} structures
- len – Size of the array of \texttt{coap\_reply} structures
int coap_resource_notify(struct coap_resource *resource)
Indicates that this resource was updated and that the notify callback should be called for every registered observer.

**Parameters**
- resource – Resource that was updated

**Returns**
0 in case of success or negative in case of error.

bool coap_request_is_observe(const struct coap_packet *request)
Returns if this request is enabling observing a resource.

**Parameters**
- request – Request to be checked

**Returns**
True if the request is enabling observing a resource, False otherwise

int coap_well_known_core_get(struct coap_resource *resource, struct coap_packet *request,
struct coap_packet *response, uint8_t *data, uint16_t len)

struct coap_resource
#include <coap.h> Description of CoAP resource.
CoAP servers often want to register resources, so that clients can act on them, by fetching their state or requesting updates to them.

**Public Members**

**coap_method_t get**
Which function to be called for each CoAP method

struct coap_observer
#include <coap.h> Represents a remote device that is observing a local resource.

struct coap_packet
#include <coap.h> Representation of a CoAP Packet.

struct coap_option
#include <coap.h>

struct coap_pending
#include <coap.h> Represents a request awaiting for an acknowledgment (ACK).

struct coap_reply
#include <coap.h> Represents the handler for the reply of a request, it is also used when observing resources.

struct coap_block_context
#include <coap.h> Represents the current state of a block-wise transaction.
In case you want to add attributes to the resources included in the 'well-known/core' "virtual" resource, the 'user_data' field should point to a valid `coap_core_metadata` structure.

**Overview**  
The HTTP client library allows you to send HTTP requests and parse HTTP responses. The library communicates over the sockets API but it does not create sockets on its own. The application must be responsible for creating a socket and passing it to the library. Therefore, depending on the application's needs, the library can communicate over either a plain TCP socket (HTTP) or a TLS socket (HTTPS).

**Sample Usage**  
The API of the HTTP client library has a single function.

The following is an example of a request structure created correctly:

```c
struct http_request req = { 0 };  
static uint8_t recv_buf[512];

req.method = HTTP_GET;
req.url = "/";
req.host = "localhost";
req.protocol = "HTTP/1.1";
req.response = response_cb;
req.recv_buf = recv_buf;
req.recv_buf_len = sizeof(recv_buf);

/* sock is a file descriptor referencing a socket that has been connected * to the HTTP server. */
ret = http_client_req(sock, &req, 5000, NULL);
```

If the server responds to the request, the library provides the response to the application through the response callback registered in the request structure. As the library can provide the response in chunks, the application must be able to process these.

Together with the structure containing the response data, the callback function also provides information about whether the library expects to receive more data.

The following is an example of a very simple response handling function:

```c
static void response_cb(struct http_response *rsp,
                        enum http_final_call final_data,
                        void *user_data)
{
    if (final_data == HTTP_DATA_MORE) {
        LOG_INF("Partial data received (%zd bytes)", rsp->data_len);
    } else if (final_data == HTTP_DATA_FINAL) {
           
```
LOG_INF("All the data received (%zd bytes)", rsp->data_len);
}

LOG_INF("Response status %s", rsp->http_status);
}

See HTTP client sample application for more information about the library usage.

API Reference

**group** http_client

HTTP client API.

**Defines**

HTTP_CRLF

HTTP_STATUS_STR_SIZE

**Typedefs**

typedef int (*http_payload_cb_t)(int sock, struct http_request *req, void *user_data)

Callback used when data needs to be sent to the server.

**Param sock**
Socket id of the connection

**Param req**
HTTP request information

**Param user_data**
User specified data specified in *http_client_req()

**Return**

>=0 amount of data sent, in this case *http_client_req() should continue sending data, <0 if *http_client_req() should return the error code to the caller.

typedef int (*http_header_cb_t)(int sock, struct http_request *req, void *user_data)

Callback can be used if application wants to construct additional HTTP headers when the HTTP request is sent. Usage of this is optional.

**Param sock**
Socket id of the connection

**Param req**
HTTP request information

**Param user_data**
User specified data specified in *http_client_req()

**Return**

>=0 amount of data sent, in this case *http_client_req() should continue sending data, <0 if *http_client_req() should return the error code to the caller.
typedef void (*http_response_cb_t)(struct http_response *rsp, enum http_final_call final_data, void *user_data)

Callback used when data is received from the server.

**Param rsp**
HTTP response information

**Param final_data**
Does this data buffer contain all the data or is there still more data to come.

**Param user_data**
User specified data specified in `http_client_req()`

**Enums**

```c
enum http_final_call

Values:

enumerator HTTP_DATA_MORE = 0
enumerator HTTP_DATA_FINAL = 1
```

**Functions**

```c
int http_client_req(int sock, struct http_request *req, int32_t timeout, void *user_data)
```

Do a HTTP request. The callback is called when data is received from the HTTP server. The caller must have created a connection to the server before calling this function so `connect()` call must have be done successfully for the socket.

**Parameters**

- **sock** – Socket id of the connection.
- **req** – HTTP request information
- **timeout** – Max timeout to wait for the data. The timeout value cannot be 0 as there would be no time to receive the data. The timeout value is in milliseconds.
- **user_data** – User specified data that is passed to the callback.

**Returns**

<0 if error, >=0 amount of data sent to the server

```c
struct http_response
```

#include `<client.h>` HTTP response from the server.

**Public Members**

```c
const struct http_parser_settings *http_cb
```

HTTP parser settings for the application usage
User provided HTTP response callback which is called when a response is received to a sent HTTP request.

<table>
<thead>
<tr>
<th>recv_buffer that contains header + body</th>
</tr>
</thead>
<tbody>
<tr>
<td>+-- body_frag_len -&gt;</td>
</tr>
<tr>
<td>+-------------------+ +-------------------</td>
</tr>
<tr>
<td>...header</td>
</tr>
<tr>
<td>+-------------------+ +-------------------</td>
</tr>
<tr>
<td>↑ recv_buf ↑ body_frag_start</td>
</tr>
</tbody>
</table>

recv_buffer that contains body only

| +-- body_frag_len -> |
| +-- data_len -> |
| +-------------------|

size_t body_frag_len
Length of the body fragment contained in the recv_buf

uint8_t *recv_buf
Where the response is stored, this is to be provided by the user.

size_t recv_buf_len
Response buffer maximum length

size_t data_len
Length of the data in the result buf. If the value is larger than recv_buf_len, then it means that the data is truncated and could not be fully copied into recv_buf. This can only happen if the user did not set the response callback. If the callback is set, then the HTTP client API will call response callback many times so that all the data is delivered to the user. Will be zero in the event of a null response.

size_t content_length
HTTP Content-Length field value. Will be set to zero in the event of a null response.

size_t processed
Amount of data given to the response callback so far, including the current data given to the callback. This should be equal to the content_length field once the entire body has been received. Will be zero if a null response is given.

uint16_t http_status_code
Numeric HTTP status code which corresponds to the textual description. Set to zero if
null response is given. Otherwise, will be a 3-digit integer code if valid HTTP response is
given.

```c
struct http_client_internal_data
#include <client.h> HTTP client internal data that the application should not touch

Public Members

struct k_work_delayable work
Work for handling timeout

struct http_parser parser
HTTP parser context

struct http_parser_settings parser_settings
HTTP parser settings

struct http_response response
HTTP response specific data (filled by http_client_req() when data is received)

void *user_data
User data

int sock
HTTP socket

k_timeout_t timeout
Request timeout

```

```c
struct http_request
#include <client.h> HTTP client request. This contains all the data that is needed when doing
a HTTP request.

Public Members

struct http_client_internal_data internal
HTTP client request internal data

enum http_method method
The HTTP method: GET, HEAD, OPTIONS, POST, ...

http_response_cb_t response
User supplied callback function to call when response is received.

const struct http_parser_settings *http_cb
User supplied list of HTTP callback functions if the calling application wants to know the
parsing status or the HTTP fields. This is optional and normally not needed.
```
uint8_t *recv_buf
    User supplied buffer where received data is stored

size_t recv_buf_len
    Length of the user supplied receive buffer

const char *url
    The URL for this request, for example: /index.html

const char *protocol
    The HTTP protocol, for example “HTTP/1.1”

const char **header_fields
    The HTTP header fields (application specific) The Content-Type may be specified here or in the next field. Depending on your application, the Content-Type may vary, however some header fields may remain constant through the application’s life cycle. This is a NULL terminated list of header fields.

const char *content_type_value
    The value of the Content-Type header field, may be NULL

const char *host
    Hostname to be used in the request

const char *port
    Port number to be used in the request

http_payload_cb_t payload_cb
    User supplied callback function to call when payload needs to be sent. This can be NULL in which case the payload field in http_request is used. The idea of this payload callback is to allow user to send more data that is practical to store in allocated memory.

const char *payload
    Payload, may be NULL

size_t payload_len
    Payload length is used to calculate Content-Length. Set to 0 for chunked transfers.

http_header_cb_t optional_headers_cb
    User supplied callback function to call when optional headers need to be sent. This can be NULL, in which case the optional_headers field in http_request is used. The idea of this optional_headers callback is to allow user to send more HTTP header data that is practical to store in allocated memory.

const char **optional_headers
    A NULL terminated list of any optional headers that should be added to the HTTP request. May be NULL. If the optional_headers_cb is specified, then this field is ignored. Note that there are two similar fields that contain headers, the header_fields above and this optional_headers. This is done like this to support Websocket use case where Websocket will use header_fields variable and any optional application specific headers will be placed into this field.

6.2. Networking
Lightweight M2M (LwM2M)

- Overview
- Example LwM2M object and resources: Device
- Sample usage
- Using LwM2M library with DTLS
- Multi-thread usage
- Support for time series data
  - Enabling and configuring
  - Read and Write operations
  - Limitations
- LwM2M engine and application events
- LwM2M shell
- API Reference

Overview  Lightweight Machine to Machine (LwM2M) is an application layer protocol designed with device management, data reporting and device actuation in mind. Based on CoAP/UDP, LwM2M is a standard defined by the Open Mobile Alliance and suitable for constrained devices by its use of CoAP packet-size optimization and a simple, stateless flow that supports a REST API.

One of the key differences between LwM2M and CoAP is that an LwM2M client initiates the connection to an LwM2M server. The server can then use the REST API to manage various interfaces with the client.

LwM2M uses a simple resource model with the core set of objects and resources defined in the specification.

Example LwM2M object and resources: Device  Object definition

<table>
<thead>
<tr>
<th>Object ID</th>
<th>Name</th>
<th>Instance</th>
<th>Mandatory</th>
</tr>
</thead>
<tbody>
<tr>
<td>3</td>
<td>Device</td>
<td>Single</td>
<td>Mandatory</td>
</tr>
</tbody>
</table>

Resource definitions

* R=Read, W=Write, E=Execute
### Table of Resource IDs

<table>
<thead>
<tr>
<th>ID</th>
<th>Name</th>
<th>OP*</th>
<th>Instance</th>
<th>Mandatory</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Manufacturer</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>1</td>
<td>Model</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>2</td>
<td>Serial number</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>3</td>
<td>Firmware version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>4</td>
<td>Reboot</td>
<td>E</td>
<td>Single</td>
<td>Mandatory</td>
<td></td>
</tr>
<tr>
<td>5</td>
<td>Factory Reset</td>
<td>E</td>
<td>Single</td>
<td>Optional</td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>Available Power Sources</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer 0-7</td>
</tr>
<tr>
<td>7</td>
<td>Power Source Voltage (mV)</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>8</td>
<td>Power Source Current (mA)</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>9</td>
<td>Battery Level %</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>10</td>
<td>Memory Free (Kb)</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>11</td>
<td>Error Code</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>Integer 0-8</td>
</tr>
<tr>
<td>12</td>
<td>Reset Error</td>
<td>E</td>
<td>Single</td>
<td>Optional</td>
<td></td>
</tr>
<tr>
<td>13</td>
<td>Current Time</td>
<td>RW</td>
<td>Single</td>
<td>Optional</td>
<td>Time</td>
</tr>
<tr>
<td>14</td>
<td>UTC Offset</td>
<td>RW</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>15</td>
<td>Timezone</td>
<td>RW</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>16</td>
<td>Supported Binding</td>
<td>R</td>
<td>Single</td>
<td>Mandatory</td>
<td>String</td>
</tr>
<tr>
<td>17</td>
<td>Device Type</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>18</td>
<td>Hardware Version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>19</td>
<td>Software Version</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>String</td>
</tr>
<tr>
<td>20</td>
<td>Battery Status</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer 0-6</td>
</tr>
<tr>
<td>21</td>
<td>Memory Total (Kb)</td>
<td>R</td>
<td>Single</td>
<td>Optional</td>
<td>Integer</td>
</tr>
<tr>
<td>22</td>
<td>ExtDevInfo</td>
<td>R</td>
<td>Multiple</td>
<td>Optional</td>
<td>ObjLnk</td>
</tr>
</tbody>
</table>

The server could query the `Manufacturer` resource for `Device` object instance 0 (the default and only instance) by sending a `READ 3/0/0` operation to the client.

The full list of registered objects and resource IDs can be found in the LwM2M registry.

Zephyr's LwM2M library lives in the `subsys/net/lib/lwm2m`, with a client sample in `samples/net/lwm2m_client`. For more information about the provided sample see: `lwm2m-client-sample`.

The sample can be configured to use normal unsecure network sockets or sockets secured via DTLS.

The Zephyr LwM2M library implements the following items:

- engine to process networking events and core functions
- RD client which performs BOOTSTRAP and REGISTRATION functions
- SenML CBOR, SenML JSON, CBOR, TLV, JSON, and plain text formatting functions
- LwM2M Technical Specification Enabler objects such as Security, Server, Device, Firmware Update, etc.
- Extended IPSO objects such as Light Control, Temperature Sensor, and Timer

By default, the library implements LwM2M specification 1.0.2 and can be set to LwM2M specification 1.1.1 with a Kconfig option.

For more information about LwM2M visit OMA Specworks LwM2M.

#### Sample usage

To use the LwM2M library, start by creating an LwM2M client context `lwm2m_ctx` structure:

```c
/* LwM2M client context */
static struct lwm2m_ctx client;
```

Create callback functions for LwM2M resource executions:
static int device_reboot_cb(uint16_t obj_inst_id, uint8_t *args,  
uint16_t args_len)
{
    LOG_INF("Device rebooting.");
    LOG_PANIC();
    sys_reboot(0);  
    return 0; /* won't reach this */
}

The LwM2M RD client can send events back to the sample. To receive those events, setup a callback function:

static void rd_client_event(struct lwm2m_ctx *client,  
enum lwm2m_rd_client_event client_event)
{
    switch (client_event) {
    case LWM2M_RD_CLIENT_EVENT_NONE:
        /* do nothing */
        break;
    case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_FAILURE:
        LOG_DBG("Bootstrap registration failure!");
        break;
    case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_COMPLETE:
        LOG_DBG("Bootstrap registration complete");
        break;
    case LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_TRANSFER_COMPLETE:
        LOG_DBG("Bootstrap transfer complete");
        break;
    case LWM2M_RD_CLIENT_EVENT_REGISTRATION_FAILURE:
        LOG_DBG("Registration failure!");
        break;
    case LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE:
        LOG_DBG("Registration complete");
        break;
    case LWM2M_RD_CLIENT_EVENT_REG_TIMEOUT:
        LOG_DBG("Registration timeout!");
        break;
    case LWM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE:
        LOG_DBG("Registration update complete");
        break;
    case LWM2M_RD_CLIENT_EVENT_DEREGISTER_FAILURE:
        LOG_DBG("Deregister failure!");
        break;
    case LWM2M_RD_CLIENT_EVENT_DISCONNECT:
        LOG_DBG("Disconnected");
        break;
    (continues on next page)
Next we assign Security resource values to let the client know where and how to connect as well as set the Manufacturer and Reboot resources in the Device object with some data and the callback we defined above:

```c
/*
 * Server URL of default Security object = 0/0/0
 * Use leshan.eclipse.org server IP (5.39.83.206) for connection
 */
lwm2m_engine_set_string("0/0/0", "coap://5.39.83.206");

/*
 * Security Mode of default Security object = 0/0/2
 * 3 = NoSec mode (no security beware!)
 */
lwm2m_engine_set_u8("0/0/2", 3);

#define CLIENT_MANUFACTURER "Zephyr Manufacturer"

/*
 * Manufacturer resource of Device object = 3/0/0
 * We use lwm2m_engine_set_res_data() function to set a pointer to the
 * CLIENT_MANUFACTURER string.
 * Note the LWM2M_RES_DATA_FLAG_RO flag which stops the engine from
 * trying to assign a new value to the buffer.
 */
lwm2m_engine_set_res_data("3/0/0", CLIENT_MANUFACTURER,
                         sizeof(CLIENT_MANUFACTURER),
                         LWM2M_RES_DATA_FLAG_RO);

/* Reboot resource of Device object = 3/0/4 */
lwm2m_engine_register_exec_callback("3/0/4", device_reboot_cb);
```

Lastly, we start the LwM2M RD client (which in turn starts the LwM2M engine). The second parameter of `lwm2m_rd_client_start()` is the client endpoint name. This is important as it needs to be unique per LwM2M server:

```c
(void)memset(&client, 0x0, sizeof(client));
lwm2m_rd_client_start(&client, "unique-endpoint-name", 0, rd_client_event);
```

### Using LwM2M library with DTLS

The Zephyr LwM2M library can be used with DTLS transport for secure communication by selecting `CONFIG_LWM2M_DTLS_SUPPORT`. In the client initialization we need to create a PSK and identity. These need to match the security information loaded onto the LwM2M server. Normally, the endpoint name is used to lookup the related security information:

```c
/* "000102030405060708090a0b0c0d0e0f" */
static unsigned char client_psk[] = {
    0x00, 0x01, 0x02, 0x03, 0x04, 0x05, 0x06, 0x07,
    0x08, 0x09, 0x0a, 0x0b, 0x0c, 0x0d, 0x0e, 0x0f
};

static const char client_identity[] = "Client_identity";
```

Next we alter the Security object resources to include DTLS security information. The server URL
should begin with `coaps://` to indicate security is required. Assign a 0 value (Pre-shared Key mode) to the `Security Mode` resource. Lastly, set the client identity and PSK resources.

```c
/* Use coaps:// for server URL protocol */
lwm2m_engine_set_string("0/0/0", "coaps://5.39.83.206");
/* 0 = Pre-Shared Key mode */
lwm2m_engine_set_u8("0/0/2", 0);
/* Set the client identity */
lwm2m_engine_set_string("0/0/3", (char *)client_identity);
/* Set the client pre-shared key (PSK) */
lwm2m_engine_setOpaque("0/0/5", (void *)client_psk, sizeof(client_psk));
```

Before calling `lwm2m_rd_client_start()` assign the `tls_tag #` where the LwM2M library should store the DTLS information prior to connection (normally a value of 1 is ok here).

```c
(void)memset(&client, 0x0, sizeof(client));
client.tls_tag = 1; /* <---- */
lwm2m_rd_client_start(&client, "endpoint-name", 0, rd_client_event);
```

For a more detailed LwM2M client sample see: lwm2m-client-sample.

**Multi-thread usage** Writing a value to a resource can be done using functions like `lwm2m_engine_set_u8`. When writing to multiple resources, the function `lwm2m_registry_lock` will ensure that the client halts until all writing operations are finished:

```c
lwm2m_registry_lock();
lwm2m_engine_set_u32("1/0/1", 60);
lwm2m_engine_set_u8("5/0/3", 0);
lwm2m_engine_set_float("3303/0/5700", &value);
lwm2m_registry_unlock();
```

This is especially useful if the server is composite-observing the resources being written to. Locking will then ensure that the client only updates and sends notifications to the server after all operations are done, resulting in fewer messages in general.

**Support for time series data** LwM2M version 1.1 adds support for SenML CBOR and SenML JSON data formats. These data formats add support for time series data. Time series formats can be used for READ, NOTIFY and SEND operations. When data cache is enabled for a resource, each write will create a timestamped entry in a cache, and its content is then returned as a content in in READ, NOTIFY or SEND operation for a given resource.

Data cache is only supported for resources with a fixed data size.

Supported resource types:

- Signed and unsigned 8-64-bit integers
- Float
- Boolean

**Enabling and configuring** Enable data cache by selecting `CONFIG_LWM2M_RESOURCE_DATA_CACHE_SUPPORT`. Application needs to allocate an array of `lwm2m_time_series_elem` structures and then enable the cache by calling `lwm2m_engine_enable_cache()` for a given resource. Each resource must be enabled separately and each resource needs their own storage.

```c
/* Allocate data cache storage */
static struct lwm2m_time_series_elem temperature_cache[10];
```
LwM2M engine have room for four resources that have cache enabled. Limit can be increased by changing `CONFIG_LWM2M_MAX_CACHED_RESOURCES`. This affects a static memory usage of engine.

Data caches depends on one of the SenML data formats `CONFIG_LWM2M_RW_SENML_CBOR_SUPPORT` or `CONFIG_LWM2M_RW_SENML_JSON_SUPPORT` and needs `CONFIG_POSIX_CLOCK` so it can request a timestamp from the system and `CONFIG_RING_BUFFER` for ring buffer.

Read and Write operations Full content of data cache is written into a payload when any READ, SEND or NOTIFY operation internally reads the content of a given resource. This has a side effect that any read callbacks registered for a that resource are ignored when cache is enabled. Data is written into a cache when any of the `lwm2m_engine_set_*` functions are called. To filter the data entering the cache, application may register a validation callback using `lwm2m_engine_register_validate_callback()`.

Limitations Cache size should be manually set so small that the content can fit normal packets sizes. When cache is full, new values are dropped.

LwM2M engine and application events The Zephyr LwM2M engine defines events that can be sent back to the application through callback functions. The engine state machine shows when the events are spawned. Events depicted in the diagram are listed in the table. The events are prefixed with `LWM2M_RD_CLIENT_EVENT_`.

![State machine for the LwM2M engine](image)

Fig. 6.10: State machine for the LwM2M engine

6.2. Networking
Table 6.20: LwM2M RD Client events

<table>
<thead>
<tr>
<th>Event ID</th>
<th>Event Name</th>
<th>Description</th>
<th>Actions</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>NONE</td>
<td>No event</td>
<td>Do nothing</td>
</tr>
<tr>
<td>1</td>
<td>BOOT-STRAP_REG_FAIL</td>
<td>Bootstrap registration failed. Occurs if there is a timeout or failure in bootstrap registration.</td>
<td>Retry bootstrap</td>
</tr>
<tr>
<td>2</td>
<td>BOOT-STRAP_REG</td>
<td>Bootstrap registration complete. Occurs after successful bootstrap registration.</td>
<td>No actions needed</td>
</tr>
<tr>
<td>3</td>
<td>BOOT-STRAP_TRNSFER_COMPLETE</td>
<td>Bootstrap finish command received from the server.</td>
<td>No actions needed, client proceeds to registration.</td>
</tr>
<tr>
<td>4</td>
<td>REGISTRATION.FAILURE</td>
<td>Registration to LwM2M server failed. Occurs if there is a failure in the registration.</td>
<td>Retry registration</td>
</tr>
<tr>
<td>5</td>
<td>REGISTRATION_COMPLETE</td>
<td>Registration to LwM2M server successful. Occurs after a successful registration reply from the LwM2M server or when session resumption is used.</td>
<td>No actions needed</td>
</tr>
<tr>
<td>6</td>
<td>REG_TIMEOUT</td>
<td>Registration or registration update timeout. Occurs if there is a timeout during registration. NOTE: If registration fails without a timeout, a full registration is triggered automatically and no registration update failure event is generated.</td>
<td>No actions needed, client proceeds to re-registration automatically.</td>
</tr>
<tr>
<td>7</td>
<td>REG_UPDATE_COMPLETE</td>
<td>Registration update completed. Occurs after successful registration update reply from the LwM2M server.</td>
<td>No actions needed</td>
</tr>
<tr>
<td>8</td>
<td>DEREGISTER_FAILURE</td>
<td>Deregistration to LwM2M server failed. Occurs if there is a timeout or failure in the deregistration.</td>
<td>No actions needed, client proceeds to idle state automatically.</td>
</tr>
<tr>
<td>9</td>
<td>DISCONNECT</td>
<td>Disconnected from LwM2M server. Occurs if there is a timeout during communication with server. Also triggered after deregistration has been done.</td>
<td>If connection is required, the application should restart the client.</td>
</tr>
<tr>
<td>10</td>
<td>QUEUE_MODE_RX_OFF</td>
<td>In queue mode, not actively listening for incoming packets. In queue mode the client is not required to actively listen for the incoming packets after a configured time period.</td>
<td>No actions needed</td>
</tr>
<tr>
<td>11</td>
<td>NETWORK_ERR</td>
<td>Sending messages to the network failed too many times. If sending a message fails, it will be retried. If the retry counter reaches its limits, this event will be triggered.</td>
<td>No actions needed, client will do a re-registerate automatically.</td>
</tr>
</tbody>
</table>

**LwM2M shell** For testing the client it is possible to enable Zephyr's shell and LwM2M specific commands which support changing the state of the client. Operations supported are read, write and execute resources. Client start, stop, pause and resume are also available. The feature is enabled by selecting `CONFIG_LWM2M_SHELL`. The shell is meant for testing so productions systems should not enable it.

One imaginable scenario, where to use the shell, would be executing client side actions over UART when a server side tests would require those. It is assumed that not all tests are able to trigger required actions from the server side.

```bash
uart:~$ lwm2m
lwm2m - LwM2M commands
Subcommands:
exec :Execute a resource
(continues on next page)
```

1920 Chapter 6. Connectivity
exec PATH

read : Read value from LwM2M resource
read PATH [OPTIONS]
-s Read value as string (default)
-b Read value as bool (1/0)
-uX Read value as uintX_t
-sX Read value as intX_t
-f Read value as float

write : Write into LwM2M resource
write PATH [OPTIONS] VALUE
-s Value as string (default)
-b Value as bool
-uX Value as uintX_t
-sX Value as intX_t
-f Value as float

start : Start the LwM2M RD (Registration / Discovery) Client
start EP_NAME [BOOTSTRAP FLAG]
-b Set the bootstrap flag (default 0)

stop : Stop the LwM2M RD (De-register) Client
stop [OPTIONS]
-f Force close the connection

update : Trigger Registration Update of the LwM2M RD Client

pause : LwM2M engine thread pause
resume : LwM2M engine thread resume

API Reference

group lwm2m_api

LwM2M high-level API.

LwM2M high-level interface is defined in this header.

Note: The implementation assumes UDP module is enabled.

Note: For more information refer to Technical Specification OMA-TS-LightweightM2M_Core-V1_1_1-20190617-A

Defines

LWM2M_OBJECT_SECURITY_ID

LwM2M Objects managed by OMA for LwM2M tech specification. Objects in this range have IDs from 0 to 1023.

LWM2M_OBJECT_SERVER_ID
LWM2M_OBJECT_ACCESS_CONTROL_ID

LWM2M_OBJECT_DEVICE_ID

LWM2M_OBJECT_CONNECTIVITY_MONITORING_ID

LWM2M_OBJECT_FIRMWARE_ID

LWM2M_OBJECT_LOCATION_ID

LWM2M_OBJECT_CONNECTIVITY_STATISTICS_ID

LWM2M_OBJECT_SOFTWARE_MANAGEMENT_ID

LWM2M_OBJECT_PORTFOLIO_ID

LWM2M_OBJECT_EVENT_LOG_ID

LWM2M_OBJECT_GATEWAY_ID

IPSO_OBJECT_GENERIC_SENSOR_ID

LwM2M Objects produced by 3rd party Standards Development Organizations. Objects in this range have IDs from 2048 to 10240. Refer to the OMA LightweightM2M (LwM2M) Object and Resource Registry: http://www.openmobilealliance.org/wp/OMNA/LwM2M/LwM2MRegistry.html.

IPSO_OBJECT_TEMP_SENSOR_ID

IPSO_OBJECT_HUMIDITY_SENSOR_ID

IPSO_OBJECT_LIGHT_CONTROL_ID

IPSO_OBJECT_ACCELEROMETER_ID

IPSO_OBJECT_CURRENT_SENSOR_ID

IPSO_OBJECT_PRESSURE_ID

IPSO_OBJECT_BUZZER_ID

IPSO_OBJECT_TIMER_ID

IPSO_OBJECT_ONOFF_SWITCH_ID

IPSO_OBJECT_PUSH_BUTTON_ID
UCIFI_OBJECT_BATTERY_ID

IPSO_OBJECT_FILLING_LEVEL_SENSOR_ID

LWM2M_DEVICE_PWR_SRC_TYPE_DC_POWER
   Power source types used for the “Available Power Sources” resource of the LwM2M Device object.

LWM2M_DEVICE_PWR_SRC_TYPE_BAT_INT

LWM2M_DEVICE_PWR_SRC_TYPE_BAT_EXT

LWM2MDEVICE_PWR_SRC_TYPE_UNUSED

LWM2M_DEVICE_PWR_SRC_TYPE_PWR_OVER_ETH

LWM2M_DEVICE_PWR_SRC_TYPE_USB

LWM2M_DEVICE_PWR_SRC_TYPE_AC_POWER

LWM2M_DEVICE_PWR_SRC_TYPE_SOLAR

LWM2M_DEVICE_PWR_SRC_TYPE_MAX

LWM2M_DEVICE_ERROR_NONE
   Error codes used for the “Error Code” resource of the LwM2M Device object. An LwM2M client can register one of the following error codes via the lwm2m_device_add_err() function.

LWM2M_DEVICE_ERROR_LOW_POWER

LWM2M_DEVICE_ERROR_EXT_POWER_SUPPLY_OFF

LWM2M_DEVICE_ERROR_GPS_FAILURE

LWM2M_DEVICE_ERROR_LOW_SIGNAL_STRENGTH

LWM2M_DEVICE_ERROR_OUT_OF_MEMORY

LWM2M_DEVICE_ERROR_SMS_FAILURE

LWM2M_DEVICE_ERROR_NETWORK_FAILURE

LWM2M_DEVICE_ERROR_PERIPHERAL_FAILURE
Battery status codes used for the “Battery Status” resource (3/0/20) of the LwM2M Device object. As the battery status changes, an LwM2M client can set one of the following codes via:

```
lwm2m_engine_set_u8("3/0/20", [battery status])
```

LWM2M_DEVICE_BATTERY_STATUS_CHARGING

LWM2M_DEVICE_BATTERY_STATUS_CHARGE_COMP

LWM2M_DEVICE_BATTERY_STATUS_DAMAGED

LWM2M_DEVICE_BATTERY_STATUS_LOW

LWM2M_DEVICE_BATTERY_STATUS_NOT_INST

LWM2M_DEVICE_BATTERY_STATUSUNKNOWN

STATE_IDLE

LWM2M Firmware Update object states.

An LwM2M client or the LwM2M Firmware Update object use the following codes to represent the LwM2M Firmware Update state (5/0/3).

STATE_DOWNLOADING

STATE_DOWNLOADED

STATE_UPDATING

RESULT_DEFAULT

LWM2M Firmware Update object result codes.

After processing a firmware update, the client sets the result via one of the following codes via `lwm2m_engine_set_u8("5/0/5", [result code])`

RESULT_SUCCESS

RESULT_NO_STORAGE

RESULT_OUT_OF_MEM

RESULT_CONNECTION_LOST

RESULT_INTEGRITY_FAILED

RESULT_UNSUP_FW

RESULT_INVALID_URI
RESULT_UPDATE_FAILED
RESULT_UNSUP_PROTO

LWM2M_OBJJLNK_MAX_ID
   Maximum value for ObjLnk resource fields.

LWM2M_RES_DATA_READ_ONLY
   Resource read-only value bit.

LWM2M_RES_DATA_FLAG_RO
   Resource read-only flag.

LWM2M_HAS_RES_FLAG(res, f)
   Read resource flags helper macro.

LWM2M_RD_CLIENT_EVENT_REG_UPDATE_FAILURE
   Define for old event name keeping backward compatibility.

LWM2M_RD_CLIENT_FLAG_BOOTSTRAP
   Run bootstrap procedure in current session.

LWM2M_MAX_PATH_STR_LEN
   LwM2M path maximum length.

Typedefs

typedef void (*lwm2m_socket_fault_cb_t)(int error)

typedef void (*lwm2m_observe_cb_t)(enum lwm2m_observe_event event, struct lwm2m_obj_path *path, void *user_data)
   Observe callback indicating observer adds and deletes, and notification ACKs and timeouts.

   Param event
      [in] Observer add/delete or notification ack/timeout

   Param path
      [in] LwM2M path

   Param user_data
      [in] Pointer to user_data buffer, as provided in send_traceable_notification().
      Used to determine for which data the ACKed/timed out notification was.

   typedef void (*lwm2m_ctx_event_cb_t)(struct lwm2m_ctx *ctx, enum lwm2m_rd_client_event event)
   Asynchronous RD client event callback.

   Param ctx
      [in] LwM2M context generating the event

   Param event
      [in] LwM2M RD client event code

6.2. Networking
typedef void *(*lwm2m_engine_get_data_cb_t)(uint16_t obj_inst_id, uint16_t res_id, uint16_t res_inst_id, size_t *data_len)

Asynchronous callback to get a resource buffer and length.

Prior to accessing the data buffer of a resource, the engine can use this callback to get the buffer pointer and length instead of using the resource’s data buffer.

The client or LwM2M objects can register a function of this type via:
lwm2m_engine_register_read_callback() lwm2m_engine_register_pre_write_callback()

Param obj_inst_id  
[in] Object instance ID generating the callback.

Param res_id  
[in] Resource ID generating the callback.

Param res_inst_id  
[in] Resource instance ID generating the callback (typically 0 for non-multi instance resources).

Param data_len  
[out] Length of the data buffer.

Return  
Callback returns a pointer to the data buffer or NULL for failure.

typedef int (*lwm2m_engine_set_data_cb_t)(uint16_t obj_inst_id, uint16_t res_id, uint16_t res_inst_id, uint8_t *data, uint16_t data_len, bool last_block, size_t total_size)

Asynchronous callback when data has been set to a resource buffer.

After changing the data of a resource buffer, the LwM2M engine can make use of this callback to pass the data back to the client or LwM2M objects.

A function of this type can be registered via:  
lwm2m_engine_register_validate_callback() lwm2m_engine_register_post_write_callback()

Param obj_inst_id  
[in] Object instance ID generating the callback.

Param res_id  
[in] Resource ID generating the callback.

Param res_inst_id  
[in] Resource instance ID generating the callback (typically 0 for non-multi instance resources).

Param data  
[in] Pointer to data.

Param data_len  
[in] Length of the data.

Param last_block  
[in] Flag used during block transfer to indicate the last block of data. For non-block transfers this is always false.

Param total_size  
[in] Expected total size of data for a block transfer. For non-block transfers this is 0.

Return  
Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.
typedef int (*lwm2m_engine_user_cb_t)(uint16_t obj_inst_id)

Asynchronous event notification callback.

Various object instance and resource-based events in the LwM2M engine can trigger a callback of this function type: object instance create, and object instance delete.

Register a function of this type via: lwm2m_engine_register_create_callback()
  lwm2m_engine_register_delete_callback()

**Param obj_inst_id**
[in] Object instance ID generating the callback.

**Return**
Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.

typedef int (*lwm2m_engine_execute_cb_t)(uint16_t obj_inst_id, uint8_t *args, uint16_t args_len)

Asynchronous execute notification callback.

Resource executes trigger a callback of this type.

Register a function of this type via: lwm2m_engine_register_exec_callback()

**Param obj_inst_id**
[in] Object instance ID generating the callback.

**Param args**
[in] Pointer to execute arguments payload. (This can be NULL if no arguments are provided)

**Param args_len**
[in] Length of argument payload in bytes.

**Return**
Callback returns a negative error code (errno.h) indicating reason of failure or 0 for success.

** Enums **

enum lwm2m_observe_event

Observe callback events.

**Values:**

enumerator LWM2M_OBSERVE_EVENT_OBSERVER_ADDED

enumerator LWM2M_OBSERVE_EVENT_OBSERVER_REMOVED

enumerator LWM2M_OBSERVE_EVENT_NOTIFY_ACK

enumerator LWM2M_OBSERVE_EVENT_NOTIFY_TIMEOUT

enum lwm2m_rd_client_event

LwM2M RD client events.

LwM2M client events are passed back to the event_cb function in lwm2m_rd_client_start()

**Values:**
enumerator LWM2M_RD_CLIENT_EVENT_NONE
enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_FAILURE
enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_REG_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_BOOTSTRAP_TRANSFER_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_REGISTRATION_FAILURE
enumerator LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_REG_TIMEOUT
enumerator LWM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE
enumerator LWM2M_RD_CLIENT_EVENT_DEREGISTER_FAILURE
enumerator LWM2M_RD_CLIENT_EVENT_DISCONNECT
enumerator LWM2M_RD_CLIENT_EVENT_QUEUE_MODE_RX_OFF
enumerator LWM2M_RD_CLIENT_EVENT_ENGINE_SUSPENDED
enumerator LWM2M_RD_CLIENT_EVENT_NETWORK_ERROR

Functions

int lwm2m_device_add_err(uint8_t error_code)
Register a new error code with LwM2M Device object.

Parameters

Returns
  0 for success or negative in case of error.

int lwm2m_engine_update_observer_min_period(struct lwm2m_ctx *client_ctx, const char *pathstr, uint32_t period_s)
Change an observer's pmin value.

LwM2M clients use this function to modify the pmin attribute for an observation being made. Example to update the pmin of a temperature sensor value being observed:
lwm2m_engine_update_observer_min_period("client_ctx, 3303/0/5700", 5);

Parameters
  • client_ctx – [in] LwM2M context
  • pathstr – [in] LwM2M path string "obj/obj-inst/res"
  • period_s – [in] Value of pmin to be given (in seconds).
Returns
0 for success or negative in case of error.

```
int lwm2m_engine_update Observer_max_period(struct lwm2m_ctx *client_ctx, const char *pathstr, uint32_t period_s)
```

Change an observer's pmax value.

LwM2M clients use this function to modify the pmax attribute for an observation being made. Example to update the pmax of a temperature sensor value being observed:
lwm2m_engine_update_observer_max_period("client_ctx, 3303/0/5700", 5);

Parameters
- `client_ctx` - [in] LwM2M context
- `pathstr` - [in] LwM2M path string “obj/obj-inst/res”
- `period_s` - [in] Value of pmax to be given (in seconds).

Returns
0 for success or negative in case of error.

```
int lwm2m_engine_create_obj_inst(const char *pathstr)
```

Create an LwM2M object instance.

LwM2M clients use this function to create non-default LwM2M objects: Example to create first temperature sensor object: lwm2m_engine_create_obj_inst("3303/0");

Parameters
- `pathstr` - [in] LwM2M path string “obj/obj-inst”

Returns
0 for success or negative in case of error.

```
int lwm2m_engine_delete_obj_inst(const char *pathstr)
```

Delete an LwM2M object instance.

LwM2M clients use this function to delete LwM2M objects.

Parameters
- `pathstr` - [in] LwM2M path string “obj/obj-inst”

Returns
0 for success or negative in case of error.

```
void lwm2m_registry_lock(void)
```

Locks the registry for this thread.

Use this function before writing to multiple resources. This halts the lwm2m main thread until all the write-operations are finished.

```
void lwm2m_registry_unlock(void)
```

Unlocks the registry previously locked by `lwm2m_registry_lock()`.

```
int lwm2m_engine_set_opaque(const char *pathstr, const char *data_ptr, uint16_t data_len)
```

Set resource (instance) value (opaque buffer)

Parameters
- `pathstr` - [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- `data_ptr` - [in] Data buffer
- `data_len` - [in] Length of buffer

Returns
0 for success or negative in case of error.
int lwm2m_engine_set_string(const char *pathstr, const char *data_ptr)
   Set resource (instance) value (string)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • data_ptr – [in] NULL terminated char buffer

Returns
   0 for success or negative in case of error.

int lwm2m_engine_set_u8(const char *pathstr, uint8_t value)
   Set resource (instance) value (u8)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • value – [in] u8 value

Returns
   0 for success or negative in case of error.

int lwm2m_engine_set_u16(const char *pathstr, uint16_t value)
   Set resource (instance) value (u16)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • value – [in] u16 value

Returns
   0 for success or negative in case of error.

int lwm2m_engine_set_u32(const char *pathstr, uint32_t value)
   Set resource (instance) value (u32)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • value – [in] u32 value

Returns
   0 for success or negative in case of error.

int lwm2m_engine_set_u64(const char *pathstr, uint64_t value)
   Set resource (instance) value (u64)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • value – [in] u64 value

Returns
   0 for success or negative in case of error.

int lwm2m_engine_set_s8(const char *pathstr, int8_t value)
   Set resource (instance) value (s8)

Parameters
   • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
   • value – [in] s8 value

Returns
   0 for success or negative in case of error.
int lwm2m_engine_set_s16(const char *pathstr, int16_t value)
    Set resource (instance) value (s16)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] s16 value

Returns
    0 for success or negative in case of error.

int lwm2m_engine_set_s32(const char *pathstr, int32_t value)
    Set resource (instance) value (s32)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] s32 value

Returns
    0 for success or negative in case of error.

int lwm2m_engine_set_s64(const char *pathstr, int64_t value)
    Set resource (instance) value (s64)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] s64 value

Returns
    0 for success or negative in case of error.

int lwm2m_engine_set_bool(const char *pathstr, bool value)
    Set resource (instance) value (bool)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] bool value

Returns
    0 for success or negative in case of error.

int lwm2m_engine_set_float(const char *pathstr, const double *value)
    Set resource (instance) value (double)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] double value

Returns
    0 for success or negative in case of error.

int lwm2m_engine_set_objlnk(const char *pathstr, const struct lwm2m_objlnk *value)
    Set resource (instance) value (ObjLnk)

Parameters
    • pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
    • value – [in] pointer to the lwm2m_objlnk structure

Returns
    0 for success or negative in case of error.
int lwm2m_engine_set_time(const char *pathstr, time_t value)
Set resource (instance) value (Time)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [in] Epoch timestamp

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_opaque(const char *pathstr, void *buf, uint16_t buflen)
Get resource (instance) value (opaque buffer)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• buf – [out] Data buffer to copy data into
• buflen – [in] Length of buffer

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_string(const char *pathstr, void *str, uint16_t strlen)
Get resource (instance) value (string)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• str – [out] String buffer to copy data into
• strlen – [in] Length of buffer

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u8(const char *pathstr, uint8_t *value)
Get resource (instance) value (u8)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u8 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u16(const char *pathstr, uint16_t *value)
Get resource (instance) value (u16)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u16 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u32(const char *pathstr, uint32_t *value)
Get resource (instance) value (u32)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u32 buffer to copy data into
Returns
0 for success or negative in case of error.

int lwm2m_engine_get_u64(const char *pathstr, uint64_t *value)
Get resource (instance) value (u64)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] u64 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_s8(const char *pathstr, int8_t *value)
Get resource (instance) value (s8)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] s8 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_s16(const char *pathstr, int16_t *value)
Get resource (instance) value (s16)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] s16 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_s32(const char *pathstr, int32_t *value)
Get resource (instance) value (s32)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] s32 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_s64(const char *pathstr, int64_t *value)
Get resource (instance) value (s64)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] s64 buffer to copy data into

Returns
0 for success or negative in case of error.

int lwm2m_engine_get_bool(const char *pathstr, bool *value)
Get resource (instance) value (bool)

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• value – [out] bool buffer to copy data into


Returns
0 for success or negative in case of error.

`int lwm2m_engine_get_float(const char *pathstr, double *buf)`
Get resource (instance) value (double)

Parameters
- `buf` – [out] double buffer to copy data into

Returns
0 for success or negative in case of error.

`int lwm2m_engine_get_objlnk(const char *pathstr, struct lwm2m_objlnk *buf)`
Get resource (instance) value (ObjLnk)

Parameters
- `buf` – [out] `lwm2m_objlnk` buffer to copy data into

Returns
0 for success or negative in case of error.

`int lwm2m_engine_get_time(const char *pathstr, time_t *buf)`
Get resource (instance) value (Time)

Parameters
- `buf` – [out] `time_t` pointer to copy data

Returns
0 for success or negative in case of error.

`int lwm2m_engine_register_read_callback(const char *pathstr, lwm2m_engine_get_data_cb_t cb)`
Set resource (instance) read callback.

LwM2M clients can use this to set the callback function for resource reads when data handling in the LwM2M engine needs to be bypassed. For example reading back opaque binary data from external storage.

This callback should not generally be used for any data that might be observed as engine does not have any knowledge of data changes.

When separate buffer for data should be used, use `lwm2m_engine_set_res_buf()` instead to set the storage.

Parameters
- `cb` – [in] Read resource callback

Returns
0 for success or negative in case of error.

`int lwm2m_engine_register_pre_write_callback(const char *pathstr, lwm2m_engine_get_data_cb_t cb)`
Set resource (instance) pre-write callback.

This callback is triggered before setting the value of a resource. It can pass a special data buffer to the engine so that the actual resource value can be calculated later, etc.

Parameters
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• cb – [in] Pre-write resource callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_register_validate_callback(const char *pathstr,
                                           lwm2m_engine_set_data_cb_t cb)
```

Set resource (instance) validation callback.
This callback is triggered before setting the value of a resource to the resource data buffer.
The callback allows an LwM2M client or object to validate the data before writing and notify
an error if the data should be discarded for any reason (by returning a negative error code).

**Note:** All resources that have a validation callback registered are initially decoded into a tem-
porary validation buffer. Make sure that `CONFIG_LWM2M_ENGINE_VALIDATION_BUFFER_SIZE` is
large enough to store each of the validated resources (individually).

**Parameters**
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• cb – [in] Validate resource data callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_register_post_write_callback(const char *pathstr,
                                               lwm2m_engine_set_data_cb_t cb)
```

Set resource (instance) post-write callback.
This callback is triggered after setting the value of a resource to the resource data buffer.
It allows an LwM2M client or object to post-process the value of a resource or trigger other
related resource calculations.

**Parameters**
• pathstr – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
• cb – [in] Post-write resource callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_register_exec_callback(const char *pathstr,
                                         lwm2m_engine_execute_cb_t cb)
```

Set resource execute event callback.
This event is triggered when the execute method of a resource is enabled.

**Parameters**
• pathstr – [in] LwM2M path string “obj/obj-inst/res”
• cb – [in] Execute resource callback

**Returns**
0 for success or negative in case of error.

```c
int lwm2m_engine_register_create_callback(uint16_t obj_id,
                                          lwm2m_engine_user_cb_t cb)
```

Set object instance create event callback.
This event is triggered when an object instance is created.
Parameters
- **obj_id** – [in] LwM2M object id
- **cb** – [in] Create object instance callback

Returns
0 for success or negative in case of error.

```c
int lwm2m_engine_register_delete_callback(uint16_t obj_id, lwm2m_engine_user_cb_t cb)
```
Set object instance delete event callback.
This event is triggered when an object instance is deleted.

Parameters
- **obj_id** – [in] LwM2M object id
- **cb** – [in] Delete object instance callback

Returns
0 for success or negative in case of error.

```c
int lwm2m_engine_set_res_buf(const char *pathstr, void *buffer_ptr, uint16_t buffer_len,
                             uint16_t data_len, uint8_t data_flags)
```
Set data buffer for a resource.
Use this function to set the data buffer and flags for the specified LwM2M resource.

Parameters
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **buffer_ptr** – [in] Data buffer pointer
- **buffer_len** – [in] Length of buffer
- **data_len** – [in] Length of existing data in the buffer
- **data_flags** – [in] Data buffer flags (such as read-only, etc)

Returns
0 for success or negative in case of error.

```c
int lwm2m_engine_set_res_data(const char *pathstr, void *data_ptr, uint16_t data_len, uint8_t data_flags)
```
Set data buffer for a resource.
Use this function to set the data buffer and flags for the specified LwM2M resource.

*Deprecated:* Use `lwm2m_engine_set_res_buf()` instead, so you can define buffer size and data size separately.

Parameters
- **pathstr** – [in] LwM2M path string “obj/obj-inst/res(/res-inst)”
- **data_ptr** – [in] Data buffer pointer
- **data_len** – [in] Length of buffer
- **data_flags** – [in] Data buffer flags (such as read-only, etc)

Returns
0 for success or negative in case of error.
int lwm2m_engine_set_res_data_len(const char *pathstr, uint16_t data_len)
  Update data size for a resource.

  Use this function to set the new size of data in the buffer if you write to a buffer received by
  \textit{lwm2m_engine_get_res_buf()}.  

\textbf{Parameters}

- \textit{pathstr} – [\textit{in}] LwM2M path string \textquote{obj/obj-inst/res(/res-inst)}
- \textit{data_len} – [\textit{in}] Length of data

\textbf{Returns}

0 for success or negative in case of error.

\begin{verbatim}
int lwm2m_engine_get_res_buf(const char *pathstr, void **buffer_ptr, uint16_t *buffer_len, 
  uint16_t *data_len, uint8_t *data_flags)
\end{verbatim}

Get data buffer for a resource.

Use this function to get the data buffer information for the specified LwM2M resource.

If you directly write into the buffer, you must use \textit{lwm2m_engine_set_res_data_len()} function
to update the new size of the written data.

All parameters except \textit{pathstr} can NULL if you don\'t want to read those values.

\textbf{Parameters}

- \textit{pathstr} – [\textit{in}] LwM2M path string \textquote{obj/obj-inst/res(/res-inst)}
- \textit{buffer_ptr} – [\textit{out}] Data buffer pointer
- \textit{buffer_len} – [\textit{out}] Length of buffer
- \textit{data_len} – [\textit{out}] Length of existing data in the buffer
- \textit{data_flags} – [\textit{out}] Data buffer flags (such as read-only, etc)

\textbf{Returns}

0 for success or negative in case of error.

\begin{verbatim}
int lwm2m_engine_get_res_data(const char *pathstr, void **data_ptr, uint16_t *data_len, 
  uint8_t *data_flags)
\end{verbatim}

Get data buffer for a resource.

Use this function to get the data buffer information for the specified LwM2M resource.

\textit{Deprecated:}
Use \textit{lwm2m_engine_get_res_buf()} as it can tell you the size of the buffer as well.

\textbf{Parameters}

- \textit{pathstr} – [\textit{in}] LwM2M path string \textquote{obj/obj-inst/res(/res-inst)}
- \textit{data_ptr} – [\textit{out}] Data buffer pointer
- \textit{data_len} – [\textit{out}] Length of existing data in the buffer
- \textit{data_flags} – [\textit{out}] Data buffer flags (such as read-only, etc)

\textbf{Returns}

0 for success or negative in case of error.

\begin{verbatim}
int lwm2m_engine_create_res_inst(const char *pathstr)
\end{verbatim}

Create a resource instance.

LwM2M clients use this function to create multi-resource instances: Example to create 0
instance of device available power sources: \textit{lwm2m_engine_create_res_inst(\textquote{3/0/6/0})};
Parameters
  • pathstr – [in] LwM2M path string “obj/obj-inst/res/res-inst”

Returns
  0 for success or negative in case of error.

int lwm2m_engine_delete_res_inst(const char *pathstr)
    Delete a resource instance.
    Use this function to remove an existing resource instance

Parameters
  • pathstr – [in] LwM2M path string “obj/obj-inst/res/res-inst”

Returns
  0 for success or negative in case of error.

int lwm2m_engine_update_service_period(k_work_handler_t service, uint32_t period_ms)
    Update the period of a given service.
    Allow the period modification on an existing service created with
    lwm2m_engine_add_service(). Example to frequency at which a periodic_service changes its
    values : lwm2m_engine_update_service(device_periodic_service,5*MSEC_PER_SEC);

Parameters
  • service – [in] Handler of the periodic_service
  • period_ms – [in] New period for the periodic_service (in milliseconds)

Returns
  0 for success or negative in case of error.

int lwm2m_update_device_service_period(uint32_t period_ms)
    Update the period of the device service.
    Change the duration of the periodic device service that notifies the current time.

Parameters
  • period_ms – [in] New period for the device service (in milliseconds)

Returns
  0 for success or negative in case of error.

bool lwm2m_engine_path_is_observed(const char *pathstr)
    Check whether a path is observed.

Parameters
  • pathstr – [in] LwM2M path string to check, e.g. “3/0/1”

Returns
  true when there exists an observation of the same level or lower as the given
  path, false if it doesn’t or path is not a valid LwM2M-path. E.g. true if path refers
  to a resource and the parent object has an observation, false for the inverse.

int lwm2m_engine_stop(struct lwm2m_ctx *client_ctx)
    Stop the LwM2M engine.
    LwM2M clients normally do not need to call this function as it is called within
    lwm2m_rd_client. However, if the client does not use the RD client implementation, it will
    need to be called manually.

Parameters
  • client_ctx – [in] LwM2M context
Returns
0 for success or negative in case of error.

int lwm2m_engine_start(struct lwm2m_ctx *client_ctx)
Start the LwM2M engine.

LwM2M clients normally do not need to call this function as it is called by
lwm2m_rd_client_start(). However, if the client does not use the RD client implementation, it
will need to be called manually.

Parameters
• client_ctx – [in] LwM2M context

Returns
0 for success or negative in case of error.

void lwm2m_ acknowledge(struct lwm2m_ctx *client_ctx)
Acknowledge the currently processed request with an empty ACK.

LwM2M engine by default sends piggybacked responses for requests. This function allows to
send an empty ACK for a request earlier (from the application callback). The LwM2M engine
will then send the actual response as a separate CON message after all callbacks are executed.

Parameters
• client_ctx – [in] LwM2M context

6.2. Networking

int lwm2m_rd_client_start(struct lwm2m_ctx *client_ctx, const char *ep_name, uint32_t flags,
   lwm2m_ctx_event_cb_t event_cb, lwm2m_observe_cb_t observe_cb)
Start the LwM2M RD (Registration / Discovery) Client.

The RD client sits just above the LwM2M engine and performs the necessary actions to im-
plement the “Registration interface”. For more information see Section “Client Registration
Interface” of LwM2M Technical Specification.

NOTE: lwm2m_engine_start() is called automatically by this function.

Parameters
• client_ctx – [in] LwM2M context
• ep_name – [in] Registered endpoint name
• flags – [in] Flags used to configure current LwM2M session.
• event_cb – [in] Client event callback function
• observe_cb – [in] Observe callback function called when an observer was
   added or deleted, and when a notification was acked or has timed out

Returns
0 for success, -EINPROGRESS when client is already running or negative error
codes in case of failure.

int lwm2m_rd_client_stop(struct lwm2m_ctx *client_ctx, lwm2m_ctx_event_cb_t event_cb, bool
deregister)
Stop the LwM2M RD (De-register) Client.

The RD client sits just above the LwM2M engine and performs the necessary actions to im-
plement the “Registration interface”. For more information see Section “Client Registration
Interface” of the LwM2M Technical Specification.

Parameters
• client_ctx – [in] LwM2M context
• event_cb – [in] Client event callback function
• deregister – [in] True to deregister the client if registered. False to force close the connection.

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_pause(void)
```

Suspend the LwM2M engine Thread.

Suspend LwM2M engine. Use case could be when network connection is down. LwM2M Engine indicate before it suspend by LWM2M_RD_CLIENT_EVENT_ENGINE_SUSPENDED event.

**Returns**

0 for success or negative in case of error.

```c
int lwm2m_engine_resume(void)
```

Resume the LwM2M engine thread.

Resume suspended LwM2M engine. After successful resume call engine will do full registration or registration update based on suspended time. Event’s LWM2M_RD_CLIENT_EVENT_REGISTRATION_COMPLETE or WM2M_RD_CLIENT_EVENT_REG_UPDATE_COMPLETE indicate that client is connected to server.

**Returns**

0 for success or negative in case of error.

```c
void lwm2m_rd_client_update(void)
```

Trigger a Registration Update of the LwM2M RD Client.

```c
char * lwm2m_path_log_buf(char *buf, struct lwm2m_obj_path *path)
```

Helper function to print path objects’ contents to log.

**Parameters**

- **buf** – [in] The buffer to use for formatting the string
- **path** – [in] The path to stringify

**Returns**

Resulting formatted path string

```c
int lwm2m_engine_send(struct lwm2m_ctx *ctx, char const *path_list[], uint8_t path_list_size, bool confirmation_request)
```

LwM2M SEND operation to given path list

**Parameters**

- **ctx** – LwM2M context
- **path_list** – LwM2M Path string list
- **path_list_size** – Length of path list. Max size is CONFIG_LWM2M_COMPOSITE_PATH_LIST_SIZE
- **confirmation_request** – True request confirmation for operation.

**Returns**

0 for success or negative in case of error.

```c
struct lwm2m_ctx * lwm2m_rd_client_ctx(void)
```

Returns LwM2M client context

**Returns**

ctx LwM2M context
int lwm2m_engine_enable_cache(char const *resource_path, struct lwm2m_time_series_elem *data_cache, size_t cache_len)

Enable data cache for a resource.

Application may enable caching of resource data by allocating buffer for LwM2M engine to use. Buffer must be size of struct lwm2m_time_series_elem times cache_len.

**Parameters**

- `resource_path` – LwM2M ressourcepath string “obj/obj-inst/res(/res-inst)”
- `data_cache` – Pointer to Data cache array
- `cache_len` – number of cached entries

**Returns**

0 for success or negative in case of error.

```c
#include <lwm2m.h>
```

```c
struct lwm2m_obj_path
```

```c
#include <lwm2m.h>
```

```c
struct lwm2m_ctx
```

```c
LwM2M context structure to maintain information for a single LwM2M connection.
```

**Public Members**

```c
struct sockaddr remote_addr
```

Destination address storage

```c
struct coap_pending pendings[CONFIG_LWM2M_ENGINE_MAX_PENDING + 1]
```

Private CoAP and networking structures + 1 is for RD Client own message

```c
void *processed_req
```

A pointer to currently processed request, for internal LwM2M engine use. The underlying type is struct lwm2m_message, but since it's declared in a private header and not exposed to the application, it's stored as a void pointer.

```c
bool use_dtls
```

Flag to indicate if context should use DTLS. Enabled via the use of coaps:// protocol prefix in connection information. NOTE: requires CONFIG_LWM2M_DTLS_SUPPORT=y

```c
bool connection_suspended
```

Flag to indicate that the socket connection is suspended. With queue mode, this will tell if there is a need to reconnect.

```c
int sec_obj_inst
```

Current index of Security Object used for server credentials

```c
int srv_obj_inst
```

Current index of Server Object used in this context.

6.2. Networking
bool bootstrap_mode
Flag to enable BOOTSTRAP interface. See Section “Bootstrap Interface” of LwM2M Technical Specification for more information.

int sock_fd
Socket File Descriptor

lwm2m_socket_fault_cb_t fault_cb
Socket fault callback. LwM2M processing thread will call this callback in case of socket errors on receive.

lwm2m_observe_cb_t observe_cb
Callback for new or cancelled observations, and acknowledged or timed out notifications.

uint8_t validate_buf[CONFIG_LWM2M_ENGINE_VALIDATION_BUFFER_SIZE]
Validation buffer. Used as a temporary buffer to decode the resource value before validation. On successful validation, its content is copied into the actual resource buffer.

struct lwm2m_time_series_elem
#include <lwm2m.h> LwM2M Time series data structure

struct lwm2m_objlnk
#include <lwm2m.h> LWM2M ObjLnk resource type structure.

MQTT

• Overview
• Sample usage
• Using MQTT with TLS
• API Reference

Overview MQTT (Message Queuing Telemetry Transport) is an application layer protocol which works on top of the TCP/IP stack. It is a lightweight publish/subscribe messaging transport for machine-to-machine communication. For more information about the protocol itself, see http://mqtt.org/.

Zephyr provides an MQTT client library built on top of BSD sockets API. The library is configurable at a per-client basis, with support for MQTT versions 3.1.0 and 3.1.1. The Zephyr MQTT implementation can be used with either plain sockets communicating over TCP, or with secure sockets communicating over TLS. See BSD Sockets for more information about Zephyr sockets.

MQTT clients require an MQTT server to connect to. Such a server, called an MQTT Broker, is responsible for managing client subscriptions and distributing messages published by clients. There are many implementations of MQTT brokers, one of them being Eclipse Mosquitto. See https://mosquitto.org/ for more information about the Eclipse Mosquitto project.

Sample usage To create an MQTT client, a client context structure and buffers need to be defined:
Multiple MQTT client instances can be created in the application and managed independently. Additionally, a structure for MQTT Broker address information is needed. This structure must be accessible throughout the lifespan of the MQTT client and can be shared among MQTT clients:

```c
/* MQTT Broker address information. */
static struct sockaddr_storage broker;
```

An MQTT client library will notify MQTT events to the application through a callback function created to handle respective events:

```c
void mqtt_evt_handler(struct mqtt_client *client,
                      const struct mqtt_evt *evt)
{
    switch (evt->type) {
        /* Handle events here. */
    }
}
```

For a list of possible events, see [API Reference](#).

The client context structure needs to be initialized and set up before it can be used. An example configuration for TCP transport is shown below:

```c
mqtt_client_init(&client_ctx);
/* MQTT client configuration */
client_ctx.broker = &broker;
client_ctx.evt_cb = mqtt_evt_handler;
client_ctx.client_id.utf8 = (uint8_t *)"zephyr_mqtt_client";
client_ctx.client_id.size = sizeof("zephyr_mqtt_client") - 1;
client_ctx.password = NULL;
client_ctx.user_name = NULL;
client_ctx.protocol_version = MQTT_VERSION_3_1_1;
client_ctx.transport.type = MQTT_TRANSPORT_NON_SECURE;
/* MQTT buffers configuration */
client_ctx.rx_buf = rx_buffer;
client_ctx.rx_buf_size = sizeof(rx_buffer);
client_ctx.tx_buf = tx_buffer;
client_ctx.tx_buf_size = sizeof(tx_buffer);
```

After the configuration is set up, the MQTT client can connect to the MQTT broker. Call the `mqtt_connect` function, which will create the appropriate socket, establish a TCP/TLS connection, and send an MQTT CONNECT message. When notified, the application should call the `mqtt_input` function to process the response received. Note, that `mqtt_input` is a non-blocking function, therefore the application should use socket `poll` to wait for the response. If the connection was successful, `MQTT_EVT_CONNACK` will be notified to the application through the callback function.

```c
rc = mqtt_connect(&client_ctx);
if (rc != 0) {
    return rc;
}
```

(continues on next page)
In the above code snippet, the MQTT callback function should set the `connected` flag upon a successful connection. If the connection fails at the MQTT level or a timeout occurs, the connection will be aborted, and the underlying socket closed.

After the connection is established, an application needs to call `mqtt_input` and `mqtt_live` functions periodically to process incoming data and upkeep the connection. If an MQTT message is received, an MQTT callback function will be called and an appropriate event notified.

The connection can be closed by calling the `mqtt_disconnect` function.

Zephyr provides sample code utilizing the MQTT client API. See `mqtt-publisher-sample` for more information.

### Using MQTT with TLS

The Zephyr MQTT library can be used with TLS transport for secure communication by selecting a secure transport type (`MQTT_TRANSPORT_SECURE`) and some additional configuration information:

```c
client_ctx.transport.type = MQTT_TRANSPORT_SECURE;

struct mqtt_sec_config *tls_config = &client_ctx.transport.tls.config;

tls_config->peer_verify = TLS_PEER_VERIFY_REQUIRED;
tls_config->cipher_list = NULL;
tls_config->sec_tag_list = m_sec_tags;
tls_config->sec_tag_count = ARRAY_SIZE(m_sec_tags);
tls_config->hostname = MQTT_BROKER_HOSTNAME;
```

In this sample code, the `m_sec_tags` array holds a list of tags, referencing TLS credentials that the MQTT library should use for authentication. We do not specify `cipher_list`, to allow the use of all cipher suites available in the system. We set `hostname` field to broker hostname, which is required for server authentication. Finally, we enforce peer certificate verification by setting the `peer_verify` field.

Note, that TLS credentials referenced by the `m_sec_tags` array must be registered in the system first. For more information on how to do that, refer to `secure sockets documentation`.

An example of how to use TLS with MQTT is also present in `mqtt-publisher-sample`.

### API Reference

**group mqtt_socket**

MQTT Client Implementation.

MQTT Client’s Application interface is defined in this header.

---

**Note:** The implementation assumes TCP module is enabled.
**Note:** By default the implementation uses MQTT version 3.1.1.

**Defines**

MQTT_UTF8_LITERAL(literal)

Initialize UTF-8 encoded string from C literal string.

Use it as follows:

```c
struct mqtt_utf8 password = MQTT_UTF8_LITERAL("my_pass");
```

**Parameters**

- `literal` - **[in]** Literal string from which to generate `mqtt_utf8` object.

**Typedefs**

typedef void (*mqtt_evt_cb_t)(struct mqtt_client *client, const struct mqtt_evt *evt)

Asynchronous event notification callback registered by the application.

**Param client**

- **[in]** Identifies the client for which the event is notified.

**Param evt**

- **[in]** Event description along with result and associated parameters (if any).

** Enums**

```c
enum mqtt_evt_type
```

MQTT Asynchronous Events notified to the application from the module through the callback registered by the application.

**Values:**

- Enumerator `MQTT_EVT_CONNACK`

  Acknowledgment of connection request. Event result accompanying the event indicates whether the connection failed or succeeded.

- Enumerator `MQTT_EVT_DISCONNECT`

  Disconnection Event. MQTT Client Reference is no longer valid once this event is received for the client.

- Enumerator `MQTT_EVT_PUBLISH`

  Publish event received when message is published on a topic client is subscribed to.

  **Note:** PUBLISH event structure only contains payload size, the payload data parameter should be ignored. Payload content has to be read manually with `mqtt_read_publish_payload` function.

- Enumerator `MQTT_EVT_PUBACK`

  Acknowledgment for published message with QoS 1.
enumerator MQTT_EVT_PUBREC
    Reception confirmation for published message with QoS 2.

enumerator MQTT_EVT_PUBREL
    Release of published message with QoS 2.

enumerator MQTT_EVT_PUBCOMP
    Confirmation to a publish release message with QoS 2.

enumerator MQTT_EVT_SUBACK
    Acknowledgment to a subscribe request.

enumerator MQTT_EVT_UNSUBACK
    Acknowledgment to a unsubscribe request.

enumerator MQTT_EVT_PINGRESP
    Ping Response from server.

enum mqtt_version
    MQTT version protocol level.
    Values:

enumerator MQTT_VERSION_3_1_0 = 3
    Protocol level for 3.1.0.

enumerator MQTT_VERSION_3_1_1 = 4
    Protocol level for 3.1.1.

enum mqtt_qos
    MQTT Quality of Service types.
    Values:

enumerator MQTT_QOS_0_AT_MOST_ONCE = 0x00
    Lowest Quality of Service, no acknowledgment needed for published message.

enumerator MQTT_QOS_1_AT_LEAST_ONCE = 0x01
    Medium Quality of Service, if acknowledgment expected for published message, duplicate messages permitted.

enumerator MQTT_QOS_2_EXACTLY_ONCE = 0x02
    Highest Quality of Service, acknowledgment expected and message shall be published only once. Message not published to interested parties unless client issues a PUBREL.

enum mqtt_conn_return_code
    MQTT CONNACK return codes.
    Values:
enumerator MQTT_CONNECTION_ACCEPTED = 0x00
    Connection accepted.

enumerator MQTT_UNACCEPTABLE_PROTOCOL_VERSION = 0x01
    The Server does not support the level of the MQTT protocol requested by the Client.

enumerator MQTT_IDENTIFIER_REJECTED = 0x02
    The Client identifier is correct UTF-8 but not allowed by the Server.

enumerator MQTT_SERVER_UNAVAILABLE = 0x03
    The Network Connection has been made but the MQTT service is unavailable.

enumerator MQTT_BAD_USER_NAME_OR_PASSWORD = 0x04
    The data in the user name or password is malformed.

enumerator MQTT_NOT_AUTHORIZED = 0x05
    The Client is not authorized to connect.

enum mqtt_suback_return_code
    MQTT SUBACK return codes.
    Values:

enumerator MQTT_SUBACK_SUCCESS_QoS_0 = 0x00
    Subscription with QoS 0 succeeded.

enumerator MQTT_SUBACK_SUCCESS_QoS_1 = 0x01
    Subscription with QoS 1 succeeded.

enumerator MQTT_SUBACK_SUCCESS_QoS_2 = 0x02
    Subscription with QoS 2 succeeded.

enumerator MQTT_SUBACK_FAILURE = 0x80
    Subscription for a topic failed.

enum mqtt_transport_type
    MQTT transport type.
    Values:

enumerator MQTT_TRANSPORT_NON_SECURE
    Use non secure TCP transport for MQTT connection.

enumerator MQTT_TRANSPORT_NUM
    Shall not be used as a transport type. Indicator of maximum transport types possible.

Functions

6.2. Networking
void mqtt_client_init(struct mqtt_client *client)
    Initializes the client instance.

    **Note:** Shall be called to initialize client structure, before setting any client parameters and before connecting to broker.

**Parameters**

- `client` - [in] Client instance for which the procedure is requested. Shall not be NULL.

---

int mqtt_connect(struct mqtt_client *client)
    API to request new MQTT client connection.

    **Note:** This memory is assumed to be resident until mqtt_disconnect is called.

    **Note:** Any subsequent changes to parameters like broker address, user name, device id, etc. have no effect once MQTT connection is established.

    **Note:** Default protocol revision used for connection request is 3.1.1. Please set client.protocol_version = MQTT_VERSION_3_1_0 to use protocol 3.1.0.

    **Note:** Please modify_CONFIG_MQTT_KEEPALIVE time to override default of 1 minute.

**Parameters**

- `client` - [in] Client instance for which the procedure is requested. Shall not be NULL.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

---

int mqtt_publish(struct mqtt_client *client, const struct mqtt_publish_param *param)
    API to publish messages on topics.

**Parameters**

- `client` - [in] Client instance for which the procedure is requested. Shall not be NULL.
- `param` - [in] Parameters to be used for the publish message. Shall not be NULL.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

---

int mqtt_publish_qos1_ack(struct mqtt_client *client, const struct mqtt_puback_param *param)
    API used by client to send acknowledgment on receiving QoS1 publish message. Should be called on reception of MQTT_EVT_PUBLISH with QoS level MQTT_QOS_1_AT_LEAST_ONCE.

**Parameters**

- `client` - [in] Client instance for which the procedure is requested. Shall not be NULL.
- `param` - [in] Identifies message being acknowledged.
Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_receive(struct mqtt_client *client, const struct mqtt_pubrec_param *param)

API used by client to send acknowledgment on receiving QoS2 publish message. Should be called on reception of MQTT_EVT_PUBLISH with QoS level MQTT_QOS_2_EXACTLY_ONCE.

Parameters
• client – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being acknowledged.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_release(struct mqtt_client *client, const struct mqtt_pubrel_param *param)

API used by client to request release of QoS2 publish message. Should be called on reception of MQTT_EVT_PUBREC.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being released.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_publish_qos2_complete(struct mqtt_client *client, const struct mqtt_pubcomp_param *param)

API used by client to send acknowledgment on receiving QoS2 publish release message. Should be called on reception of MQTT_EVT_PUBREL.

Parameters
• client – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Identifies message being completed.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_subscribe(struct mqtt_client *client, const struct mqtt_subscription_list *param)

API to request subscription of one or more topics on the connection.

Parameters
• client – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
• param – [in] Subscription parameters. Shall not be NULL.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_unsubscribe(struct mqtt_client *client, const struct mqtt_subscription_list *param)

API to request unsubscription of one or more topics on the connection.

Note: QoS included in topic description is unused in this API.
Parameters

- client – [in] Identifies client instance for which the procedure is requested. Shall not be NULL.
- param – [in] Parameters describing topics being unsubscribed from. Shall not be NULL.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_ping(struct mqtt_client *client)

API to send MQTT ping. The use of this API is optional, as the library handles the connection keep-alive on its own, see mqtt_live.

Parameters

- client – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_disconnect(struct mqtt_client *client)

API to disconnect MQTT connection.

Parameters

- client – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_abort(struct mqtt_client *client)

API to abort MQTT connection. This will close the corresponding transport without closing the connection gracefully at the MQTT level (with disconnect message).

Parameters

- client – [in] Identifies client instance for which procedure is requested.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_keepalive_time_left(const struct mqtt_client *client)

This API should be called periodically for the client to be able to keep the connection alive by sending Ping Requests if need be.

Note: Application shall ensure that the periodicity of calling this function makes it possible to respect the Keep Alive time agreed with the broker on connection. mqtt_connect for details on Keep Alive time.

Parameters

- client – [in] Client instance for which the procedure is requested. Shall not be NULL.

Returns

0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_keepalive_time_left(const struct mqtt_client *client)

Helper function to determine when next keep alive message should be sent. Can be used for instance as a source for poll timeout.

Parameters
• client – [in] Client instance for which the procedure is requested.

Returns
Time in milliseconds until next keep alive message is expected to be sent. Function will return -1 if keep alive messages are not enabled.

int mqtt_input(struct mqtt_client *client)
Receive an incoming MQTT packet. The registered callback will be called with the packet content.

Note: In case of PUBLISH message, the payload has to be read separately with mqtt_read_publish_payload function. The size of the payload to read is provided in the publish event structure.

Note: This is a non-blocking call.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.

Returns
0 or a negative error code (errno.h) indicating reason of failure.

int mqtt_read_publish_payload(struct mqtt_client *client, void *buffer, size_t length)
Read the payload of the received PUBLISH message. This function should be called within the MQTT event handler, when MQTT PUBLISH message is notified.

Note: This is a non-blocking call.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.

• buffer – [out] Buffer where payload should be stored.

• length – [in] Length of the buffer, in bytes.

Returns
Number of bytes read or a negative error code (errno.h) indicating reason of failure.

int mqtt_read_publish_payload_blocking(struct mqtt_client *client, void *buffer, size_t length)
Blocking version of mqtt_read_publish_payload function.

Parameters
• client – [in] Client instance for which the procedure is requested. Shall not be NULL.

• buffer – [out] Buffer where payload should be stored.

• length – [in] Length of the buffer, in bytes.

Returns
Number of bytes read or a negative error code (errno.h) indicating reason of failure.
int mqtt_readall_publish_payload(struct mqtt_client *client, uint8_t *buffer, size_t length)

Blocking version of \texttt{mqtt_read_publish_payload} function which runs until the required number of bytes are read.

**Parameters**

- \texttt{client} – [in] Client instance for which the procedure is requested. Shall not be NULL.
- \texttt{buffer} – [out] Buffer where payload should be stored.
- \texttt{length} – [in] Number of bytes to read.

**Returns**

0 if success, otherwise a negative error code (\texttt{errno.h}) indicating reason of failure.

\[struct\] mqtt_utf8

\texttt{#include <mqtt.h>} Abstracts UTF-8 encoded strings.

**Public Members**

- \texttt{const uint8_t *utf8}
  Pointer to UTF-8 string.
- \texttt{uint32_t size}
  Size of UTF string, in bytes.

\[struct\] mqtt_binstr

\texttt{#include <mqtt.h>} Abstracts binary strings.

**Public Members**

- \texttt{uint8_t *data}
  Pointer to binary stream.
- \texttt{uint32_t len}
  Length of binary stream.

\[struct\] mqtt_topic

\texttt{#include <mqtt.h>} Abstracts MQTT UTF-8 encoded topic that can be subscribed to or published.

**Public Members**

- \texttt{struct mqtt_utf8 topic}
  Topic on to be published or subscribed to.
- \texttt{uint8_t qos}
  Quality of service requested for the subscription. \texttt{mqtt_qos} for details.

\[struct\] mqtt_publish_message

\texttt{#include <mqtt.h>} Parameters for a publish message.
Public Members

struct _mqtt_topic topic
  Topic on which data was published.

struct _mqtt_binstr payload
  Payload on the topic published.

struct _mqtt_connack_param
  #include <mqtt.h> Parameters for a connection acknowledgment (CONNACK).

Public Members

uint8_t _session_present_flag
  The Session Present flag enables a Client to establish whether the Client and Server have a consistent view about whether there is already stored Session state.

enum _mqtt_conn_return_code return_code
  The appropriate non-zero Connect return code indicates if the Server is unable to process a connection request for some reason.

struct _mqtt_puback_param
  #include <mqtt.h> Parameters for MQTT publish acknowledgment (PUBACK).

struct _mqtt_pubrec_param
  #include <mqtt.h> Parameters for MQTT publish receive (PUBREC).

struct _mqtt_pubrel_param
  #include <mqtt.h> Parameters for MQTT publish release (PUBREL).

struct _mqtt_pubcomp_param
  #include <mqtt.h> Parameters for MQTT publish complete (PUBCOMP).

struct _mqtt_suback_param
  #include <mqtt.h> Parameters for MQTT subscription acknowledgment (SUBACK).

struct _mqtt_unsuback_param
  #include <mqtt.h> Parameters for MQTT unsubscribe acknowledgment (UNSUBACK).

struct _mqtt_publish_param
  #include <mqtt.h> Parameters for a publish message.

Public Members

struct _mqtt_publish_message message
  Messages including topic, QoS and its payload (if any) to be published.
```c
uint16_t message_id
    Message id used for the publish message. Redundant for QoS 0.

uint8_t dup_flag
    Duplicate flag. If 1, it indicates the message is being retransmitted. Has no meaning with QoS 0.

uint8_t retain_flag
    Retain flag. If 1, the message shall be stored persistently by the broker.
```

```c
struct mqtt_subscription_list
    #include <mqtt.h> List of topics in a subscription request.
```

### Public Members

```c
struct mqtt_topic *list
    Array containing topics along with QoS for each.

uint16_t list_count
    Number of topics in the subscription list

uint16_t message_id
    Message id used to identify subscription request.
```

```c
union mqtt_evt_param
    #include <mqtt.h> Defines event parameters notified along with asynchronous events to the application.
```

### Public Members

```c
struct mqtt_connack_param connack
    Parameters accompanying MQTT_EVT_CONNACK event.

struct mqtt_publish_param publish
    Parameters accompanying MQTT_EVT_PUBLISH event.
```

**Note:** PUBLISH event structure only contains payload size, the payload data parameter should be ignored. Payload content has to be read manually with `mqtt_read_publish_payload` function.

```c
struct mqtt_puback_param puback
    Parameters accompanying MQTT_EVT_PUBACK event.

struct mqtt_pubrec_param pubrec
    Parameters accompanying MQTT_EVT_PUBREC event.
```
struct mqtt_pubrel_param pubrel
Parameters accompanying MQTT_EVT_PUBREL event.

struct mqtt_pubcomp_param pubcomp
Parameters accompanying MQTT_EVT_PUBCOMP event.

struct mqtt_suback_param suback
Parameters accompanying MQTT_EVT_SUBACK event.

struct mqtt_unsuback_param unsuback
Parameters accompanying MQTT_EVT_UNSUBACK event.

struct mqtt_evt
#include <mqtt.h> Defines MQTT asynchronous event notified to the application.

Public Members

to
enum mqtt_evt_type type
Identifies the event.

union mqtt_evt_param param
Contains parameters (if any) accompanying the event.

int result
Event result. 0 or a negative error code (errno.h) indicating reason of failure.

struct mqtt_sec_config
#include <mqtt.h> TLS configuration for secure MQTT transports.

Public Members

int peer_verify
Indicates the preference for peer verification.

uint32_t cipher_count
Indicates the number of entries in the cipher list.

int *cipher_list
Indicates the list of ciphers to be used for the session. May be NULL to use the default ciphers.

uint32_t sec_tag_count
Indicates the number of entries in the sec tag list.

sec_tag_t *sec_tag_list
Indicates the list of security tags to be used for the session.
const char *hostname
Peer hostname for certificate verification. May be NULL to skip hostname verification.

int cert_nocopy
Indicates the preference for copying certificates to the heap.

struct mqtt_transport
#include <mqtt.h> MQTT transport specific data.

Public Members

enum mqtt_transport_type type
Transport type selection for client instance. mqtt_transport_type for possible values. MQTT_TRANSPORT_MAX is not a valid type.

int sock
Socket descriptor.

struct mqtt_internal
#include <mqtt.h> MQTT internal state.

Public Members

struct sys_mutex mutex
Internal. Mutex to protect access to the client instance.

uint32_t last_activity
Internal. Wall clock value (in milliseconds) of the last activity that occurred. Needed for periodic PING.

uint32_t state
Internal. Client's state in the connection.

uint32_t trx_buf_datalen
Internal. Packet length read so far.

uint32_t remaining_payload
Internal. Remaining payload length to read.

struct mqtt_client
#include <mqtt.h> MQTT Client definition to maintain information relevant to the client.

Public Members

struct mqtt_internal internal
MQTT client internal state.
struct mqtt_transport transport
MQTT transport configuration and data.

struct mqtt_utf8 client_id
Unique client identification to be used for the connection.

const void *broker
Broker details, for example, address, port. Address type should be compatible with transport used.

struct mqtt_utf8 *user_name
User name (if any) to be used for the connection. NULL indicates no user name.

struct mqtt_utf8 *password
Password (if any) to be used for the connection. Note that if password is provided, user name shall also be provided. NULL indicates no password.

struct mqtt_topic *will_topic
Will topic and QoS. Can be NULL.

struct mqtt_utf8 *will_message
Will message. Can be NULL. Non NULL value valid only if will topic is not NULL.

mqtt_evt_cb_t evt_cb
Application callback registered with the module to get MQTT events.

uint8_t *rx_buf
Receive buffer used for MQTT packet reception in RX path.

uint32_t rx_buf_size
Size of receive buffer.

uint8_t *tx_buf
Transmit buffer used for creating MQTT packet in TX path.

uint32_t tx_buf_size
Size of transmit buffer.

uint16_t keepalive
Keepalive interval for this client in seconds. Default is CONFIG_MQTT_KEEPALIVE.

uint8_t protocol_version
MQTT protocol version.

int8_t unacked_ping
Unanswered PINGREQ count on this connection.

uint8_t will_retain
Will retain flag, 1 if will message shall be retained persistently.

6.2. Networking
uint8_t clean_session

Clean session flag indicating a fresh (1) or a retained session (0). Default is CONFIG_MQTT_CLEAN_SESSION.

MQTT-SN

• Overview
• Sample usage
• Deviations from the standard
• API Reference

Overview MQTT-SN is a variant of the well-known MQTT protocol - see MQTT.

In contrast to MQTT, MQTT-SN does not require a TCP transport, but is designed to be used over any message-based transport. Originally, it was mainly created with ZigBee in mind, but others like Bluetooth, UDP or even a UART can be used just as well.

Zephyr provides an MQTT-SN client library built on top of BSD sockets API. The library is configurable at a per-client basis, with support for MQTT-SN version 1.2. The Zephyr MQTT-SN implementation can be used with any message-based transport, but support for UDP is already built-in.

MQTT-SN clients require an MQTT-SN gateway to connect to. These gateways translate between MQTT-SN and MQTT. The Eclipse Paho project offers an implementation of a MQTT-SN gateway, but others are available too. https://www.eclipse.org/paho/index.php?page=components/mqtt-sn-transparent-gateway/index.php

The MQTT-SN spec v1.2 can be found here: https://www.oasis-open.org/committees/download.php/66091/MQTT-SN_spec_v1.2.pdf

Sample usage To create an MQTT-SN client, a client context structure and buffers need to be defined:

```c
/* Buffers for MQTT client. */
static uint8_t rx_buffer[256];
static uint8_t tx_buffer[256];

/* MQTT-SN client context */
static struct mqtt_sn_client client;
```

Multiple MQTT-SN client instances can be created in the application and managed independently. Additionally, a structure for the transport is needed as well. The library already comes with an example implementation for UDP.

```c
/* MQTT Broker address information. */
static struct mqtt_sn_transport tp;
```

The MQTT-SN library will inform clients about certain events using a callback.

```c
static void evt_cb(struct mqtt_sn_client *client,
                   const struct mqtt_sn_evt *evt)
{
    switch(evt->type) {
    {
        /* Handle events here. */
    }
```

(continues on next page)
For a list of possible events, see API Reference.

The client context structure needs to be initialized and set up before it can be used. An example configuration for UDP transport is shown below:

```c
struct mqtt_sn_data client_id = MQTT_SN_DATA_STRING_LITERAL(“ZEPHYR”);
struct sockaddr_in gateway = {0};

uint8_t tx_buf[256];
uint8_t rx_buf[256];

mqtt_sn_transport_udp_init(&tp, (struct sockaddr*)&gateway, sizeof((gateway)));
mqtt_sn_client_init(&client, &client_id, &tp.tp, evt_cb, tx_buf, sizeof(tx_buf), rx_buf, sizeof(rx_buf));
```

After the configuration is set up, the MQTT-SN client can connect to the gateway. While the MQTT-SN protocol offers functionality to discover gateways through an advertisement mechanism, this is not implemented yet in the library.

Call the `mqtt_sn_connect` function, which will send a `CONNECT` message. The application should periodically call the `mqtt_sn_input` function to process the response received. The application does not have to call `mqtt_sn_input` if it knows that no data has been received (e.g. when using Bluetooth). Note that `mqtt_sn_input` is a non-blocking function, if the transport struct contains a `poll` compatible function pointer. If the connection was successful, `MQTT_SN_EVT_CONNECTED` will be notified to the application through the callback function.

```c
err = mqtt_sn_connect(&client, false, true);
__ASSERT(err == 0, "mqtt_sn_connect() failed %d", err);
while (1) {
    mqtt_sn_input(&client);
    if (connected) {
        mqtt_sn_publish(&client, MQTT_SN_QOS_0, &topic_p, false, &pubdata);
    }
    k_sleep(K_MSEC(500));
}
```

In the above code snippet, the event handler function should set the `connected` flag upon a successful connection. If the connection fails at the MQTT level or a timeout occurs, the connection will be aborted.

After the connection is established, an application needs to call `mqtt_input` function periodically to process incoming data. Connection upkeep, on the other hand, is done automatically using a k_work item. If a MQTT message is received, an MQTT callback function will be called and an appropriate event notified.

The connection can be closed by calling the `mqtt_sn_disconnect` function. This has no effect on the transport, however. If you want to close the transport (e.g. the socket), call `mqtt_sn_client_deinit`, which will deinit the transport as well.

Zephyr provides sample code utilizing the MQTT-SN client API. See mqtt-sn-publisher-sample for more information.

**Deviations from the standard** Certain parts of the protocol are not yet supported in the library. * Pre-defined topic IDs * QoS -1 - it's most useful with predefined topics * Gateway discovery using ADVERTISE,
SEARCHGW and GWINFO messages. * Setting the will topic and message after the initial connect * Forwarder Encapsulation

API Reference

**group mqtt_sn_socket**

MQTT-SN Client Implementation.

MQTT-SN Client's Application interface is defined in this header. Targets protocol version 1.2.

**Defines**

`MQTT_SN_DATA_STRING_LITERAL(literal)`

Initialize memory buffer from C literal string.

Use it as follows:

```c
struct mqtt_sn_data topic = MQTT_SN_DATA_STRING_LITERAL("/zephyr");
```

**Parameters**

- **literal** - [in] Literal string from which to generate `mqtt_sn_data` object.

`MQTT_SN_DATA_BYTES(...)`

Initialize memory buffer from single bytes.

Use it as follows:

```c
struct mqtt_sn_data data = MQTT_SN_DATA_BYTES(0x13, 0x37);
```

**Typedefs**

typedef void (*mqtt_sn_evt_cb_t)(struct mqtt_sn_client *client, const struct mqtt_sn_evt *evt)

Asynchronous event notification callback registered by the application.

**Param client**

[in] Identifies the client for which the event is notified.

**Param evt**

[in] Event description along with result and associated parameters (if any).

**Enums**

`enum mqtt_sn_qos`

Quality of Service. QoS 0-2 work the same as basic MQTT, QoS -1 is an MQTT-SN addition. QOS -1 is not supported yet.

**Values:**

- **QOS 0**
  - enumerator `MQTT_SN_QOS_0`
- **QOS 1**
  - enumerator `MQTT_SN_QOS_1`
enumerator MQTT_SN_QOS_2
    QOS 2

enumerator MQTT_SN_QOS_M1
    QOS -1

enum mqtt_sn_topic_type
    MQTT-SN topic types.
    Values:

    enumerator MQTT_SN_TOPIC_TYPE_NORMAL

    enumerator MQTT_SN_TOPIC_TYPE_PREDEF

    enumerator MQTT_SN_TOPIC_TYPE_SHORT

enum mqtt_sn_return_code
    Values:

    enumerator MQTT_SN_CODE_ACCEPTED = 0x00
        Accepted

    enumerator MQTT_SN_CODE_REJECTED_CONGESTION = 0x01
        Rejected: congestion

    enumerator MQTT_SN_CODE_REJECTED_TOPIC_ID = 0x02
        Rejected: Invalid Topic ID

    enumerator MQTT_SN_CODE_REJECTED_NOTSUP = 0x03
        Rejected: Not Supported

enum mqtt_sn_evt_type
    Event types that can be emitted by the library.
    Values:

    enumerator MQTT_SN_EVT_CONNECTED
        Connected to a gateway

    enumerator MQTT_SN_EVT_DISCONNECTED
        Disconnected

    enumerator MQTT_SN_EVT_ASLEEP
        Entered ASLEEP state

    enumerator MQTT_SN_EVT_AWAKE
        Entered AWAKE state
enumerator MQTT_SN_EVT_PUBLISH
Received a PUBLISH message

enumerator MQTT_SN_EVT_PINGRESP
Received a PINGRESP

**Functions**

```c
def int mqtt_sn_client_init(struct mqtt_sn_client *client, const struct mqtt_sn_data *client_id,
                           struct mqtt_sn_transport *transport, mqtt_sn_evt_cb_t evt_cb, void *tx,
                           size_t txsz, void *rx, size_t rxsz)
```

Initialize a client.

```c
def void mqtt_sn_client_deinit(struct mqtt_sn_client *client)
```

Deinitialize the client.

This removes all topics and publishes, and also deinitializes the transport.

```c
def int mqtt_sn_connect(struct mqtt_sn_client *client, bool will, bool clean_session)
```

Connect the client.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
def int mqtt_sn_disconnect(struct mqtt_sn_client *client)
```

Disconnect the client.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
def int mqtt_sn_sleep(struct mqtt_sn_client *client, uint16_t duration)
```

Set the client into sleep state for the given duration (seconds).

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
def int mqtt_sn_subscribe(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name)
```

Subscribe to a given topic.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
def int mqtt_sn_unsubscribe(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name)
```

Unsubscribe from a topic.

```c
def int mqtt_sn_publish(struct mqtt_sn_client *client, enum mqtt_sn_qos qos, struct mqtt_sn_data *topic_name, bool retain, struct mqtt_sn_data *data)
```

Publish a value.

If the topic is not yet registered with the gateway, the library takes care of it.

**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
def int mqtt_sn_input(struct mqtt_sn_client *client)
```

Check the transport for new incoming data.

Call this function periodically, or if you have good reason to believe there is any data. If the client’s transport struct contains a poll-function, this function is non-blocking.
**Returns**

0 or a negative error code (errno.h) indicating reason of failure.

```c
struct mqtt_sn_data
#include <mqtt_sn.h> Abstracts memory buffers.
```

**Public Members**

`const uint8_t *data`
Pointer to data.

`uint16_t size`
Size of data, in bytes.

```c
union mqtt_sn_evt_param
#include <mqtt_sn.h> Event metadata.
```

**Public Members**

```c
struct mqtt_sn_data data
```

```c
enum mqtt_sn_topic_type topic_type
```

```c
uint16_t topic_id
```

```c
struct mqtt_sn_evt_param.[anonymous] publish
```

```c
struct mqtt_sn_evt
#include <mqtt_sn.h> MQTT-SN event structure to be handled by the event callback.
```

```c
struct mqtt_sn_transport
#include <mqtt_sn.h> Structure to describe an MQTT-SN transport.
```

MQTT-SN does not require transports to be reliable or to hold a connection. Transports just need to be frame-based, so you can use UDP, ZigBee, or even a simple UART, given some kind of framing protocol is used.

**Public Members**

```c
int (*init)(struct mqtt_sn_transport *transport)
```
Will be called once on client init to initialize the transport.
Use this to open sockets or similar. May be NULL.

```c
void (*deinit)(struct mqtt_sn_transport *transport)
```
Will be called on client deinit.
Use this to close sockets or similar. May be NULL.
int (*msg_send)(struct mqtt_sn_client *client, void *buf, size_t sz)
  Will be called by the library when it wants to send a message.

ssize_t (*recv)(struct mqtt_sn_client *client, void *buffer, size_t length)
  Will be called by the library when it wants to receive a message.
  Implementations should follow recv conventions.

int (*poll)(struct mqtt_sn_client *client)
  Check if incoming data is available.
  If poll() returns a positive number, recv must not block.
  May be NULL, but recv should not block then either.
  **Return**
  Positive number if data is available, or zero if there is none. Negative values
  signal errors.

struct mqtt_sn_client
  
  "include <mqtt_sn.h> Structure describing an MQTT-SN client.

Public Members

struct mqtt_sn_data client_id
  1-23 character unique client ID

struct mqtt_sn_data will_topic
  Must be initialized before connecting with will=true

struct mqtt_sn_data will_msg
  Must be initialized before connecting with will=true

Network System Management

Network Configuration Library

- **Overview**
  The network configuration library sets up networking devices in a semi-automatic way during the system boot, based on user-supplied Kconfig options.
  The following Kconfig options affect how configuration library will setup the system:
Table 6.21: Kconfig options for network configuration library

<table>
<thead>
<tr>
<th>Option name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CONFIG_NET_CONFIG_SETTINGS</td>
<td>This option controls whether the network system is configured or initialized at all. If not set, then the config library is not used for initialization and the application needs to do all the network related configuration itself. If this option is set, then the user can optionally configure static IP addresses to be set to the first network interface in the system. Typically setting static IP addresses is only usable in testing and should not be used in production code. See the config library Kconfig file subsys/net/lib/config/Kconfig for specific options to set the static IP addresses.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_AUTO_INIT</td>
<td>The networking system is automatically configured when the device is started.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_INIT_TIMEOUT</td>
<td>This tells how long to wait for the networking to be ready and available. If for example IPv4 address from DHCPv4 is not received within this limit, then a call to net_config_init() will return error during the device startup.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV4</td>
<td>The network application needs IPv4 support to function properly. This option makes sure the network application is initialized properly in order to use IPv4. If CONFIG_NET_IPV4 is not enabled, then setting this option will automatically enable IPv4.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV6</td>
<td>The network application needs IPv6 support to function properly. This option makes sure the network application is initialized properly in order to use IPv6. If CONFIG_NET_IPV6 is not enabled, then setting this option will automatically enable IPv6.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_NEED_IPV6_ROUTER</td>
<td>If IPv6 is enabled, then this option tells that the network application needs IPv6 router to exists before continuing. This means in practice that the application wants to wait until it receives IPv6 router advertisement message before continuing.</td>
</tr>
<tr>
<td>CONFIG_NET_CONFIG_BT_NODE</td>
<td>Enables application to operate in Bluetooth node mode which requires GATT service to be registered and start advertising as peripheral.</td>
</tr>
</tbody>
</table>

Sample usage  If CONFIG_NET_CONFIG_AUTO_INIT is set, then the configuration library is automatically enabled and run during the device boot. In this case, the library will call net_config_init() automatically and the application does not need to do any network configuration.

If you want to use the network configuration library but without automatic initialization, you can call net_config_init() manually. The flags parameter can be used to give hints to the library about what kind of functionality the application wishes to have before the actual application starts.

API Reference

*group net_config*

Network configuration library.

Define
NET_CONFIG_NEED_ROUTER

Application needs routers to be set so that connectivity to remote network is possible. For IPv6 networks, this means that the device should receive IPv6 router advertisement message before continuing.

NET_CONFIG_NEED_IPV6

Application needs IPv6 subsystem configured and initialized. Typically this means that the device has IPv6 address set.

NET_CONFIG_NEED_IPV4

Application needs IPv4 subsystem configured and initialized. Typically this means that the device has IPv4 address set.

Functions

int net_config_init(const char *app_info, uint32_t flags, int32_t timeout)

Initialize this network application.

This will call net_config_init_by_iface() with NULL network interface.

Parameters

• app_info – String describing this application.
• flags – Flags related to services needed by the client.
• timeout – How long to wait the network setup before continuing the startup.

Returns

0 if ok, <0 if error.

int net_config_init_by_iface(struct net_if *iface, const char *app_info, uint32_t flags, int32_t timeout)

Initialize this network application using a specific network interface.

If network interface is set to NULL, then the default one is used in the configuration.

Parameters

• iface – Initialize networking using this network interface.
• app_info – String describing this application.
• flags – Flags related to services needed by the client.
• timeout – How long to wait the network setup before continuing the startup.

Returns

0 if ok, <0 if error.

int net_config_init_app(const struct device *dev, const char *app_info)

Initialize this network application.

If CONFIG_NET_CONFIG_AUTO_INIT is set, then this function is called automatically when the device boots. If that is not desired, unset the config option and call the function manually when the application starts.

Parameters

• dev – Network device to use. The function will figure out what network interface to use based on the device. If the device is NULL, then default network interface is used by the function.
• app_info – String describing this application.
Returns
0 if ok, <0 if error.

DHCPv4

• Overview
• Sample usage
• API Reference

Overview  The Dynamic Host Configuration Protocol (DHCP) is a network management protocol used on IPv4 networks. A DHCPv4 server dynamically assigns an IPv4 address and other network configuration parameters to each device on a network so they can communicate with other IP networks. See this DHCP Wikipedia article for a detailed overview of how DHCP works.

Note that Zephyr only supports DHCP client functionality.

Sample usage  See dhcpv4-client-sample for details.

API Reference

group dhcpv4
DHCPv4.

Functions

void net_dhcpv4_start(struct net_if *iface)
Start DHCPv4 client on an iface.

Start DHCPv4 client on a given interface. DHCPv4 client will start negotiation for IPv4 address. Once the negotiation is success IPv4 address details will be added to interface.

Parameters
• iface – A valid pointer on an interface

void net_dhcpv4_stop(struct net_if *iface)
Stop DHCPv4 client on an iface.

Stop DHCPv4 client on a given interface. DHCPv4 client will remove all configuration obtained from a DHCP server from the interface and stop any further negotiation with the server.

Parameters
• iface – A valid pointer on an interface

void net_dhcpv4_restart(struct net_if *iface)
Restart DHCPv4 client on an iface.

Restart DHCPv4 client on a given interface. DHCPv4 client will restart the state machine without any of the initial delays used in start.

Parameters
• iface – A valid pointer on an interface
Hostname Configuration

- Overview
- API Reference

Overview
A networked device might need a hostname, for example, if the device is configured to be a
mDNS responder (see DNS Resolve for details) and needs to respond to <hostname>.local DNS queries.
The CONFIG_NET_HOSTNAME_ENABLE must be set in order to store the hostname and enable the relevant
APIs. If the option is enabled, then the default hostname is set to be zephyr by CONFIG_NET_HOSTNAME
option.

If the same firmware image is used to flash multiple boards, then it is not practical to use the same
hostname in all of the boards. In that case, one can enable CONFIG_NET_HOSTNAME_UNIQUE which will
add a unique postfix to the hostname. By default the link local address of the first network interface is
used as a postfix. In Ethernet networks, the link local address refers to MAC address. For example, if the
link local address is 01:02:03:04:05:06, then the unique hostname could be zephyr010203040506.
If you want to set the prefix yourself, then call net_hostname_set_postfix() before the network
interfaces are created. For example for the Ethernet networks, the initialization priority is set by
CONFIG_ETH_INIT_PRIORITY so you would need to set the postfix before that. The postfix can be set
only once.

API Reference

group net_hostname

Network hostname configuration library.

Defines

NET_HOSTNAME_MAX_LEN

Functions

static inline const char *net_hostname_get(void)
Get the device hostname.
Return pointer to device hostname.

Returns
Pointer to hostname or NULL if not set.

static inline void net_hostname_init(void)
Initialize and set the device hostname.

static inline int net_hostname_set_postfix(const uint8_t *hostname_postfix, int postfix_len)
Set the device hostname postfix.
Set the device hostname to some value. This is only used if CON-
FIG_NET_HOSTNAME_UNIQUE is set.

Parameters
- hostname_postfix – Usually link address. The function will convert this to a
  string.
- postfix_len – Length of the hostname_postfix array.
Returns
0 if ok, <0 if error

Network Core Helpers

Overview  The network subsystem contains two functions for sending and receiving data from the network. The `net_recv_data()` is typically used by network device driver when the received network data needs to be pushed up in the network stack for further processing. All the data is received via a network interface which is typically created by the device driver.

For sending, the `net_send_data()` can be used. Typically applications do not call this function directly as there is the BSD Sockets API for sending and receiving network data.

API Reference

group net_core
    Network core library.

Enums

enum net_verdict
    Net Verdict.
    Values:
    enumerator NET_OK
        Packet has been taken care of.
    enumerator NET_CONTINUE
        Packet has not been touched, other part should decide about its fate.
    enumerator NET_DROP
        Packet must be dropped.

Functions

int net_recv_data(struct net_if *iface, struct net_pkt *pkt)
    Called by lower network stack or network device driver when a network packet has been received. The function will push the packet up in the network stack for further processing.

    Parameters
    • iface – Network interface where the packet was received.
    • pkt – Network packet data.

    Returns
    0 if ok, <0 if error.
int net_send_data(struct net_pkt *pkt)
    Send data to network.

    Send data to network. This should not be used normally by applications as it requires that the
    network packet is properly constructed.

**Parameters**

- pkt – Network packet.

**Returns**

0 if ok, <0 if error. If <0 is returned, then the caller needs to unref the pkt in
order to avoid memory leak.

**Network Interface**

- **Overview**
- **Network interface state management**
- **API Reference**

**Overview**  The network interface is a nexus that ties the network device drivers and the upper part of
the network stack together. All the sent and received data is transferred via a network interface. The
network interfaces cannot be created at runtime. A special linker section will contain information about
them and that section is populated at linking time.

Network interfaces are created by NETDEVICE_INIT() macro. For Ethernet network, a macro called
ETH_NETDEVICE_INIT() should be used instead as it will create VLAN interfaces automatically if
CONFIG_NET_VLAN is enabled. These macros are typically used in network device driver source code.

The network interface can be turned ON by calling net_if_up() and OFF by calling net_if_down().
When the device is powered ON, the network interface is also turned ON by default.

The network interfaces can be referenced either by a struct net_if * pointer or by a network interface
index. The network interface can be resolved from its index by calling net_if_get_by_index() and from
interface pointer by calling net_if_get_by_iface().

The IP address for network devices must be set for them to be connectable. In a typical dynamic net-
work environment, IP addresses are set automatically by DHCPv4, for example. If needed though, the
application can set a device's IP address manually. See the API documentation below for functions such
as net_if_ipv4_addr_add() that do that.

The net_if_get_default() returns a default network interface. What this default interface means can
be configured via options like CONFIG_NET_DEFAULT_IP_FIRST and CONFIG_NET_DEFAULT_IP ETHERNET.
See Kconfig file subsys/net/ip/Kconfig what options are available for selecting the default network inter-
face.

The transmitted and received network packets can be classified via a network packet priority. This is
typically done in Ethernet networks when virtual LANs (VLANs) are used. Higher priority packets can
be sent or received earlier than lower priority packets. The traffic class setup can be configured by
CONFIG_NET_TC_TX_COUNT and CONFIG_NET_TC_RX_COUNT options.

If the CONFIG_NET_PROMISCUOUS_MODE is enabled and if the underlying network technology supports
promiscuous mode, then it is possible to receive all the network packets that the network device driver
is able to receive. See Promiscuous Mode API for more details.

**Network interface state management**  Zephyr distinguishes between two interface states: adminis-
trative state and operational state, as described in RFC 2863. The administrative state indicate whether
an interface is turned ON or OFF. This state is represented by NET_IF_UP flag and is controlled by the
application. It can be changed by calling `net_if_up()` or `net_if_down()` functions. Network drivers or L2 implementations should not change administrative state on their own.

Bringing an interface up however not always means that the interface is ready to transmit packets. Because of that, operational state, which represents the internal interface status, was implemented. The operational state is updated whenever one of the following conditions take place:

- The interface is brought up/down by the application (administrative state changes).
- The interface is notified by the driver/L2 that PHY status has changed.
- The interface is notified by the driver/L2 that it joined/left a network.

The PHY status is represented with `NET_IF_LOWER_UP` flag and can be changed with `net_if_carrier_on()` and `net_if_carrier_off()`. By default, the flag is set on a newly initialized interface. An example of an event that changes the carrier state is Ethernet cable being plugged in or out.

The network association status is represented with `NET_IF_DORMANT` flag and can be changed with `net_if_dormant_on()` and `net_if_dormant_off()`. By default, the flag is cleared on a newly initialized interface. An example of an event that changes the dormant state is a Wi-Fi driver successfully connecting to an access point. In this scenario, driver should set the dormant state to ON during initialization, and once it detects that it connected to a Wi-Fi network, the dormant state should be set to OFF.

The operational state of an interface is updated as follows:

- `!net_if_is_admin_up()` Interface is in `NET_IF_OPER_DOWN`.
- `net_if_is_admin_up() && !net_if_is_carrier_ok()` Interface is in `NET_IF_OPER_DOWN` or `NET_IF_OPER_LOWERLAYERDOWN` if the interface is stacked (virtual).
- `net_if_is_admin_up() && net_if_is_carrier_ok() && net_if_is_dormant()` Interface is in `NET_IF_OPER_DORMANT`.
- `net_if_is_admin_up() && net_if_is_carrier_ok() && !net_if_is_dormant()` Interface is in `NET_IF_OPER_UP`.

Only after an interface enters `NET_IF_OPER_UP` state the `NET_IF_RUNNING` flag is set on the interface indicating that the interface is ready to be used by the application.

API Reference

`group net_if`

Network Interface abstraction layer.

**Defines**

`NETDEVICE_INIT(dev_id, name, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)`

Create a network interface and bind it to network device.

**Parameters**

- `dev_id` – Network device id.
- `name` – The name this instance of the driver exposes to the system.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
- data – Pointer to the device’s private data.
- config – The address to the structure containing the configuration information for this instance of the driver.
- prio – The initialization level at which configuration occurs.
- api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- l2 – Network L2 layer for this network interface.
- l2_ctx_type – Type of L2 context data.
- mtu – Maximum transfer unit in bytes for this network interface.

```
NET_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)
```

Like `NET_DEVICE_INIT` but taking metadata from a devicetree node. Create a network interface and bind it to network device.

**Parameters**

- `node_id` – The devicetree node identifier.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
- `data` – Pointer to the device’s private data.
- `config` – The address to the structure containing the configuration information for this instance of the driver.
- `prio` – The initialization level at which configuration occurs.
- `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
- `l2` – Network L2 layer for this network interface.
- `l2_ctx_type` – Type of L2 context data.
- `mtu` – Maximum transfer unit in bytes for this network interface.

```
NET_DEVICE_DT_INST_DEFINE(inst, ...
```

Like `NET_DEVICE_DT_DEFINE` for an instance of a `DT_DRV_COMPAT` compatible.

**Parameters**

- `inst` – instance number. This is replaced by `DT_DRV_COMPAT(inst)` in the call to `NET_DEVICE_DT_DEFINE`.
- `...` – other parameters as expected by `NET_DEVICE_DT_DEFINE`.

```
NET_DEVICE_INIT_INSTANCE(dev_id, name, instance, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)
```

Create multiple network interfaces and bind them to network device. If your network device needs more than one instance of a network interface, use this macro below and provide a different instance suffix each time (0, 1, 2, . . . or a, b, c . . . whatever works for you)

**Parameters**

- `dev_id` – Network device id.
- `name` – The name this instance of the driver exposes to the system.
- `instance` – Instance identifier.
- `init_fn` – Address to the init function of the driver.
- `pm` – Reference to struct `pm_device` associated with the device. (optional).
• data – Pointer to the device’s private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• prio – The initialization level at which configuration occurs.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• l2 – Network L2 layer for this network interface.
• l2_ctx_type – Type of L2 context data.
• mtu – Maximum transfer unit in bytes for this network interface.

NET_DEVICE_DT_DEFINE_INSTANCE(node_id, instance, init_fn, pm, data, config, prio, api, l2, l2_ctx_type, mtu)

Like NET_DEVICE_OFFLOAD_INIT but taking metadata from a devicetree. Create multiple network interfaces and bind them to network device. If your network device needs more than one instance of a network interface, use this macro below and provide a different instance suffix each time (0, 1, 2, ... or a, b, c ... whatever works for you)

Parameters
• node_id – The devicetree node identifier.
• instance – Instance identifier.
• init_fn – Address to the init function of the driver.
• pm – Reference to struct pm_device associated with the device. (optional).
• data – Pointer to the device’s private data.
• config – The address to the structure containing the configuration information for this instance of the driver.
• prio – The initialization level at which configuration occurs.
• api – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• l2 – Network L2 layer for this network interface.
• l2_ctx_type – Type of L2 context data.
• mtu – Maximum transfer unit in bytes for this network interface.

NET_DEVICE_DT_INST_DEFINE_INSTANCE(inst, ...

Like NET_DEVICE_DT_DEFINE_INSTANCE for an instance of a DT_DRV_COMPAT compatible.

Parameters
• inst – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to NET_DEVICE_DT_DEFINE_INSTANCE.
• ... – other parameters as expected by NET_DEVICE_DT_DEFINE_INSTANCE.

NET_DEVICE_OFFLOAD_INIT(dev_id, name, init_fn, pm, data, config, prio, api, mtu)

Create a offloaded network interface and bind it to network device. The offloaded network interface is implemented by a device vendor HAL or similar.

Parameters
• dev_id – Network device id.
• name – The name this instance of the driver exposes to the system.
• init_fn – Address to the init function of the driver.
• pm – Reference to struct pm_device associated with the device. (optional).
• **data** – Pointer to the device’s private data.
• **config** – The address to the structure containing the configuration information for this instance of the driver.
• **prio** – The initialization level at which configuration occurs.
• **api** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• **mtu** – Maximum transfer unit in bytes for this network interface.

```c
NET_DEVICE_DT_OFFLOAD_DEFINE(node_id, init_fn, pm, data, config, prio, api, mtu)
```

Like `NET_DEVICE_OFFLOAD_INIT` but taking metadata from a devicetree node. Create a offloaded network interface and bind it to network device. The offloaded network interface is implemented by a device vendor HAL or similar.

**Parameters**

• **node_id** – The devicetree node identifier.
• **init_fn** – Address to the init function of the driver.
• **pm** – Reference to struct `pm_device` associated with the device. (optional).
• **data** – Pointer to the device’s private data.
• **config** – The address to the structure containing the configuration information for this instance of the driver.
• **prio** – The initialization level at which configuration occurs.
• **api** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.
• **mtu** – Maximum transfer unit in bytes for this network interface.

```c
NET_DEVICE_DT_INST_OFFLOAD_DEFINE(inst, ...)
```

Like `NET_DEVICE_DT_OFFLOAD_DEFINE` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

• **inst** – instance number. This is replaced by `DT_DRV_COMPAT(inst)` in the call to `NET_DEVICE_DT_OFFLOAD_DEFINE`.
• **...** – other parameters as expected by `NET_DEVICE_DT_OFFLOAD_DEFINE`.

**Typedefs**

typedef int (*net_socket_create_t)(int, int, int)

A function prototype to create an offloaded socket. The prototype is compatible with `socket()` function.

typedef void (*net_if_mcast_callback_t)(struct `net_if` *iface, const struct net_addr *addr, bool is_joined)

Define callback that is called whenever IPv6 multicast address group is joined or left.

**Param iface**

A pointer to a struct `net_if` to which the multicast address is attached.

**Param addr**

IP multicast address.

**Param is_joined**

True if the address is joined, false if left.
typedef void (*net_if_link_callback_t)(struct net_if *iface, struct net_linkaddr *dst, int status)
Define callback that is called after a network packet has been sent.

**Param iface**
A pointer to a struct net_if to which the net_pkt was sent to.

**Param dst**
Link layer address of the destination where the network packet was sent.

**Param status**
Send status, 0 is ok, < 0 error.

typedef void (*net_if_cb_t)(struct net_if *iface, void *user_data)
Callback used while iterating over network interfaces.

**Param iface**
Pointer to current network interface

**Param user_data**
A valid pointer to user data or NULL

**Enums**

enum net_if_flag
Network interface flags.

**Values:**

enumerator NET_IF_UP
Interface is admin up.

enumerator NET_IF_POINTOPOINT
Interface is pointopoint

enumerator NET_IF_PROMISC
Interface is in promiscuous mode

enumerator NET_IF_NO_AUTO_START
Do not start the interface immediately after initialization. This requires that either the device driver or some other entity will need to manually take the interface up when needed. For example for Ethernet this will happen when the driver calls the net_eth_carrier_on() function.

enumerator NET_IF_SUSPENDED
Power management specific: interface is being suspended

enumerator NET_IF_FORWARD_MULTICASTS
Flag defines if received multicasts of other interface are forwarded on this interface. This activates multicast routing / forwarding for this interface.

enumerator NET_IF_IPV4
Interface supports IPv4
enumerator NET_IF_IPV6
   Interface supports IPv6

enumerator NET_IF_RUNNING
   Interface up and running (ready to receive and transmit).

enumerator NET_IF_LOWER_UP
   Driver signals L1 is up.

enumerator NET_IF_DORMANT
   Driver signals dormant.

enum net_if_oper_state
   Network interface operational status (RFC 2863).
   Values:

   enumerator NET_IF_OPER_UNKNOWN

   enumerator NET_IF_OPER_NOTPRESENT

   enumerator NET_IF_OPER_DOWN

   enumerator NET_IF_OPER_LOWERLAYERDOWN

   enumerator NET_IF_OPER_TESTING

   enumerator NET_IF_OPER_DORMANT

   enumerator NET_IF_OPER_UP

Functions

static inline void net_if_flag_set(struct net_if *iface, enum net_if_flag value)
   Set a value in network interface flags.

   Parameters
      • iface – Pointer to network interface
      • value – Flag value

static inline bool net_if_flag_test_and_set(struct net_if *iface, enum net_if_flag value)
   Test and set a value in network interface flags.

   Parameters
      • iface – Pointer to network interface
      • value – Flag value

   Returns
      true if the bit was set, false if it wasn’t.
static inline void net_if_flag_clear(struct net_if *iface, enum net_if_flag value)
Clear a value in network interface flags.

Parameters
• iface – Pointer to network interface
• value – Flag value

static inline bool net_if_flag_test_and_clear(struct net_if *iface, enum net_if_flag value)
Test and clear a value in network interface flags.

Parameters
• iface – Pointer to network interface
• value – Flag value

Returns
true if the bit was set, false if it wasn't.

static inline bool net_if_flag_is_set(struct net_if *iface, enum net_if_flag value)
Check if a value in network interface flags is set.

Parameters
• iface – Pointer to network interface
• value – Flag value

Returns
True if the value is set, false otherwise

static inline enum net_if_oper_state net_if_oper_state_set(struct net_if *iface, enum net_if_oper_state oper_state)
Set an operational state on an interface.

Parameters
• iface – Pointer to network interface
• oper_state – Operational state to set

Returns
The new operational state of an interface

static inline enum net_if_oper_state net_if_oper_state(struct net_if *iface)
Get an operational state of an interface.

Parameters
• iface – Pointer to network interface

Returns
Operational state of an interface

enum net_verdict net_if_send_data(struct net_if *iface, struct net_pkt *pkt)
Send a packet through a net iface.

return verdict about the packet

Parameters
• iface – Pointer to a network interface structure
• pkt – Pointer to a net packet to send
static inline const struct net_l2 *net_if_l2(struct net_if *iface)
Get a pointer to the interface L2.

Parameters
• iface – a valid pointer to a network interface structure

Returns
a pointer to the iface L2

denum net_verdict net_if_recv_data(struct net_if *iface, struct net_pkt *pkt)
Input a packet through a net iface.

Parameters
• iface – Pointer to a network interface structure
• pkt – Pointer to a net packet to input

Returns
verdict about the packet

static inline void *net_if_l2_data(struct net_if *iface)
Get a pointer to the interface L2 private data.

Parameters
• iface – a valid pointer to a network interface structure

Returns
a pointer to the iface L2 data

static inline const struct device *net_if_get_device(struct net_if *iface)
Get an network interface's device.

Parameters
• iface – Pointer to a network interface structure

Returns
a pointer to the device driver instance

void net_if_queue_tx(struct net_if *iface, struct net_pkt *pkt)
Queue a packet to the net interface TX queue.

Parameters
• iface – Pointer to a network interface structure
• pkt – Pointer to a net packet to queue

static inline bool net_if_is_ip_offloaded(struct net_if *iface)
Return the IP offload status.

Parameters
• iface – Network interface

Returns
True if IP offloading is active, false otherwise.

static inline struct net_offload *net_if_offload(struct net_if *iface)
Return the IP offload plugin.

Parameters
• iface – Network interface

Returns
NULL if there is no offload plugin defined, valid pointer otherwise
static inline bool net_if_is_socket_offloaded(struct net_if *iface)
    Return the socket offload status.

Parameters
• iface – Network interface

Returns
True if socket offloading is active, false otherwise.

static inline void net_if_socket_offload_set(struct net_if *iface, net_socket_create_t socket_offload)
Set the function to create an offloaded socket.

Parameters
• iface – Network interface
• socket_offload – A function to create an offloaded socket

static inline net_socket_create_t net_if_socket_offload(struct net_if *iface)
Return the function to create an offloaded socket.

Parameters
• iface – Network interface

Returns
NULL if the interface is not socket offloaded, valid pointer otherwise

static inline struct net_linkaddr *net_if_get_link_addr(struct net_if *iface)
Get an network interface's link address.

Parameters
• iface – Pointer to a network interface structure

Returns
a pointer to the network link address

static inline struct net_if_config *net_if_get_config(struct net_if *iface)
Return network configuration for this network interface.

Parameters
• iface – Pointer to a network interface structure

Returns
Pointer to configuration

static inline void net_if_start_dad(struct net_if *iface)
Start duplicate address detection procedure.

Parameters
• iface – Pointer to a network interface structure

void net_if_start_rs(struct net_if *iface)
Start neighbor discovery and send router solicitation message.

Parameters
• iface – Pointer to a network interface structure

static inline void net_if_stop_rs(struct net_if *iface)
Stop neighbor discovery.

Parameters
• iface – Pointer to a network interface structure
static inline int net_if_set_link_addr(struct net_if *iface, uint8_t *addr, uint8_t len, enum net_link_type type)

Set a network interface's link address.

Parameters

• iface – Pointer to a network interface structure
• addr – A pointer to a uint8_t buffer representing the address. The buffer must remain valid throughout interface lifetime.
• len – length of the address buffer
• type – network bearer type of this link address

Returns

0 on success

static inline uint16_t net_if_get_mtu(struct net_if *iface)

Get an network interface's MTU.

Parameters

• iface – Pointer to a network interface structure

Returns

the MTU

static inline void net_if_set_mtu(struct net_if *iface, uint16_t mtu)

Set an network interface's MTU.

Parameters

• iface – Pointer to a network interface structure
• mtu – New MTU, note that we store only 16 bit mtu value.

static inline void net_if_addr_set_lf(struct net_if_addr *ifaddr, bool is_infinite)

Set the infinite status of the network interface address.

Parameters

• ifaddr – IP address for network interface
• is_infinite – Infinite status

struct net_if *net_if_get_by_link_addr(struct net_linkaddr *ll_addr)

Get an interface according to link layer address.

Parameters

• ll_addr – Link layer address.

Returns

Network interface or NULL if not found.

struct net_if *net_if_lookup_by_dev(const struct device *dev)

Find an interface from it's related device.

Parameters

• dev – A valid struct device pointer to relate with an interface

Returns

a valid struct net_if pointer on success, NULL otherwise

static inline struct net_if_config *net_if_config_get(struct net_if *iface)

Get network interface IP config.

Parameters
• iface – Interface to use.

Returns
NULL if not found or pointer to correct config settings.

void net_if_router_rm(struct net_if_router *router)
Remove a router from the system.

Parameters
• router – Pointer to existing router

void net_if_set_default(struct net_if *iface)
Set the default network interface.

Parameters
• iface – New default interface, or NULL to revert to the one set by Kconfig.

struct net_if *net_if_get_default(void)
Get the default network interface.

Returns
Default interface or NULL if no interfaces are configured.

struct net_if *net_if_get_first_by_type(const struct net_l2 *l2)
Get the first network interface according to its type.

Parameters
• l2 – Layer 2 type of the network interface.

Returns
First network interface of a given type or NULL if no such interfaces was found.

struct net_if *net_if_get_first_up(void)
Get the first network interface which is up.

Returns
First network interface which is up or NULL if all interfaces are down.

int net_if_config_ipv6_get(struct net_if *iface, struct net_if_ipv6 **ipv6)
Allocate network interface IPv6 config.
This function will allocate new IPv6 config.

Parameters
• iface – Interface to use.
• ipv6 – Pointer to allocated IPv6 struct is returned to caller.

Returns
0 if ok, <0 if error

int net_if_config_ipv6_put(struct net_if *iface)
Release network interface IPv6 config.

Parameters
• iface – Interface to use.

Returns
0 if ok, <0 if error

struct net_if_addr *net_if_ipv6_addr_lookup(const struct in6_addr *addr, struct net_if **iface)
Check if this IPv6 address belongs to one of the interfaces.

Parameters
• addr – IPv6 address
• iface – Pointer to interface is returned

Returns
Pointer to interface address, NULL if not found.

\[
\text{struct net_if_addr *} \text{net_if_ipv6_addr_lookup_by_iface(}\text{struct net_if *iface, struct in6_addr *addr)}
\]

Check if this IPv6 address belongs to this specific interfaces.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
Pointer to interface address, NULL if not found.

\[
\text{int net_if_ipv6_addr_lookup_by_index(}\text{const struct in6_addr *addr)}
\]

Check if this IPv6 address belongs to one of the interface indices.

Parameters
• addr – IPv6 address

Returns
>0 if address was found in given network interface index, all other values mean address was not found

\[
\text{struct net_if_addr *} \text{net_if_ipv6_addr_add(}\text{struct net_if *iface, struct in6_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)}
\]

Add a IPv6 address to an interface.

Parameters
• iface – Network interface
• addr – IPv6 address
• addr_type – IPv6 address type
• vlifetime – Validity time for this address

Returns
Pointer to interface address, NULL if cannot be added

\[
\text{bool net_if_ipv6_addr_add_by_index(}\text{int index, struct in6_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)}
\]

Add a IPv6 address to an interface by index.

Parameters
• index – Network interface index
• addr – IPv6 address
• addr_type – IPv6 address type
• vlifetime – Validity time for this address

Returns
True if ok, false if address could not be added

\[
\text{void net_if_ipv6_addr_update_lifetime(}\text{struct net_if_addr *ifaddr, uint32_t vlifetime)}
\]

Update validity lifetime time of an IPv6 address.

Parameters
• ifaddr – Network IPv6 address
bool net_if_ipv6_addr_rm(struct net_if *iface, const struct in6_addr *addr)
Remove an IPv6 address from an interface.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
True if successfully removed, false otherwise

bool net_if_ipv6_addr_rm_by_index(int index, const struct in6_addr *addr)
Remove an IPv6 address from an interface by index.

Parameters
• index – Network interface index
• addr – IPv6 address

Returns
True if successfully removed, false otherwise

struct net_if_mcast_addr *net_if_ipv6_maddr_add(struct net_if *iface, const struct in6_addr *addr)
Add a IPv6 multicast address to an interface.

Parameters
• iface – Network interface
• addr – IPv6 multicast address

Returns
Pointer to interface multicast address, NULL if cannot be added

bool net_if_ipv6_maddr_rm(struct net_if *iface, const struct in6_addr *addr)
Remove an IPv6 multicast address from an interface.

Parameters
• iface – Network interface
• addr – IPv6 multicast address

Returns
True if successfully removed, false otherwise

struct net_if_mcast_addr *net_if_ipv6_maddr_lookup(const struct in6_addr *addr, struct net_if **iface)
Check if this IPv6 multicast address belongs to a specific interface or one of the interfaces.

Parameters
• addr – IPv6 address
• iface – If *iface is null, then pointer to interface is returned, otherwise the *iface value needs to be matched.

Returns
Pointer to interface multicast address, NULL if not found.

void net_if_mcast_mon_register(struct net_if_mcast_monitor *mon, struct net_if *iface, net_if_mcast_callback_t cb)
Register a multicast monitor.

Parameters
• mon – Monitor handle. This is a pointer to a monitor storage structure which should be allocated by caller, but does not need to be initialized.
• iface – Network interface
• cb – Monitor callback

void net_if_mcast_mon_unregister(struct net_if_mcast_monitor *mon)
Unregister a multicast monitor.

Parameters
• mon – Monitor handle

void net_if_mcast_monitor(struct net_if *iface, const struct net_addr *addr, bool is_joined)
Call registered multicast monitors.

Parameters
• iface – Network interface
• addr – Multicast address
• is_joined – Is this multicast address joined (true) or not (false)

void net_if_ipv6_maddr_join(struct net_if_mcast_addr *addr)
Mark a given multicast address to be joined.

Parameters
• addr – IPv6 multicast address

static inline bool net_if_ipv6_maddr_is_joined(struct net_if_mcast_addr *addr)
Check if given multicast address is joined or not.

Parameters
• addr – IPv6 multicast address

Returns
True if address is joined, False otherwise.

void net_if_ipv6_maddr_leave(struct net_if_mcast_addr *addr)
Mark a given multicast address to be left.

Parameters
• addr – IPv6 multicast address

struct net_if_ipv6_prefix *net_if_ipv6_prefix_get(struct net_if *iface, struct in6_addr *addr)
Return prefix that corresponds to this IPv6 address.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
Pointer to prefix, NULL if not found.

struct net_if_ipv6_prefix *net_if_ipv6_prefix_lookup(struct net_if *iface, struct in6_addr *addr, uint8_t len)
Check if this IPv6 prefix belongs to this interface.

Parameters
• iface – Network interface
• addr – IPv6 address
• len – Prefix length

Returns
Pointer to prefix, NULL if not found.

struct net_if_ipv6_prefix *net_if_ipv6_prefix_add(struct net_if *iface, struct in6_addr *prefix, uint8_t len, uint32_t lifetime)

Add a IPv6 prefix to an network interface.

Parameters
• iface – Network interface
• prefix – IPv6 address
• len – Prefix length
• lifetime – Prefix lifetime in seconds

Returns
Pointer to prefix, NULL if the prefix was not added.

bool net_if_ipv6_prefix_rm(struct net_if *iface, struct in6_addr *addr, uint8_t len)

Remove an IPv6 prefix from an interface.

Parameters
• iface – Network interface
• addr – IPv6 prefix address
• len – Prefix length

Returns
True if successfully removed, false otherwise

static inline void net_if_ipv6_prefix_set_lf(struct net_if_ipv6_prefix *prefix, bool is_infinite)

Set the infinite status of the prefix.

Parameters
• prefix – IPv6 address
• is_infinite – Infinite status

void net_if_ipv6_prefix_set_timer(struct net_if_ipv6_prefix *prefix, uint32_t lifetime)

Set the prefix lifetime timer.

Parameters
• prefix – IPv6 address
• lifetime – Prefix lifetime in seconds

void net_if_ipv6_prefix_unset_timer(struct net_if_ipv6_prefix *prefix)

Unset the prefix lifetime timer.

Parameters
• prefix – IPv6 address

bool net_if_ipv6_addr_onlink(struct net_if **iface, struct in6_addr *addr)

Check if this IPv6 address is part of the subnet of our network interface.

Parameters
• iface – Network interface. This is returned to the caller. The iface can be NULL in which case we check all the interfaces.
• addr – IPv6 address
Returns
True if address is part of our subnet, false otherwise

static inline struct in6_addr *net_if_router_ipv6(struct net_if_router *router)
Get the IPv6 address of the given router.

Parameters
• router – a network router

Returns
pointer to the IPv6 address, or NULL if none

struct net_if_router *net_if_ipv6_router_lookup(struct net_if *iface, struct in6_addr *addr)
Check if IPv6 address is one of the routers configured in the system.

Parameters
• iface – Network interface
• addr – IPv6 address

Returns
Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv6_router_find_default(struct net_if *iface, struct in6_addr *addr)
Find default router for this IPv6 address.

Parameters
• iface – Network interface. This can be NULL in which case we go through all the network interfaces to find a suitable router.
• addr – IPv6 address

Returns
Pointer to router information, NULL if cannot be found

void net_if_ipv6_router_update_lifetime(struct net_if_router *router, uint16_t lifetime)
Update validity lifetime time of a router.

Parameters
• router – Network IPv6 address
• lifetime – Lifetime of this router.

struct net_if_router *net_if_ipv6_router_add(struct net_if *iface, struct in6_addr *addr, uint16_t router_lifetime)
Add IPv6 router to the system.

Parameters
• iface – Network interface
• addr – IPv6 address
• router_lifetime – Lifetime of the router

Returns
Pointer to router information, NULL if could not be added

bool net_if_ipv6_router_rm(struct net_if_router *router)
Remove IPv6 router from the system.

Parameters
• router – Router information.
Returns
True if successfully removed, false otherwise

uint8_t net_if.ipv6.get_hop_limit(struct net_if *iface)
Get IPv6 hop limit specified for a given interface. This is the default value but can be overrid-
den by the user.

Parameters
• iface – Network interface

Returns
Hop limit

void net_ipv6.set_hop_limit(struct net_if *iface, uint8_t hop_limit)
Set the default IPv6 hop limit of a given interface.

Parameters
• iface – Network interface
• hop_limit – New hop limit

static inline void net_if.ipv6.set_base_reachable_time(struct net_if *iface, uint32_t reachable_time)
Set IPv6 reachable time for a given interface.

Parameters
• iface – Network interface
• reachable_time – New reachable time

static inline uint32_t net_if.ipv6.get_reachable_time(struct net_if *iface)
Get IPv6 reachable timeout specified for a given interface.

Parameters
• iface – Network interface

Returns
Reachable timeout

uint32_t net_if.ipv6.calc_reachable_time(struct net_if_ipv6 *ipv6)
Calculate next reachable time value for IPv6 reachable time.

Parameters
• ipv6 – IPv6 address configuration

Returns
Reachable time

static inline void net_if_ipv6.set_reachable_time(struct net_if_ipv6 *ipv6)
Set IPv6 reachable time for a given interface. This requires that base reachable time is set for
the interface.

Parameters
• ipv6 – IPv6 address configuration

static inline void net_if_ipv6.set_retrans_timer(struct net_if *iface, uint32_t retrans_timer)
Set IPv6 retransmit timer for a given interface.

Parameters
• iface – Network interface
• retrans_timer – New retransmit timer
static inline uint32_t net_if_ipv6_get_retrans_timer(struct net_if *iface)
Get IPv6 retransmit timer specified for a given interface.

Parameters
• iface – Network interface

Returns
Retransmit timer

static inline const struct in6_addr *net_if_ipv6_select_src_addr(struct net_if *iface, const struct in6_addr *dst)
Get a IPv6 source address that should be used when sending network data to destination.

Parameters
• iface – Interface that was used when packet was received. If the interface is not known, then NULL can be given.
• dst – IPv6 destination address

Returns
Pointer to IPv6 address to use, NULL if no IPv6 address could be found.

static inline struct net_if *net_if_ipv6_select_src_iface(const struct in6_addr *dst)
Get a network interface that should be used when sending IPv6 network data to destination.

Parameters
• dst – IPv6 destination address

Returns
Pointer to network interface to use, NULL if no suitable interface could be found.

static inline struct in6_addr *net_if_ipv6_get_ll(struct net_if *iface, enum net_addr_state addr_state)
Get a IPv6 link local address in a given state.

Parameters
• iface – Interface to use. Must be a valid pointer to an interface.
• addr_state – IPv6 address state (preferred, tentative, deprecated)

Returns
Pointer to link local IPv6 address, NULL if no proper IPv6 address could be found.

struct in6_addr *net_if_ipv6_get_ll_addr(enum net_addr_state state, struct net_if **iface)
Return link local IPv6 address from the first interface that has a link local address matching give state.

Parameters
• state – IPv6 address state (ANY, TENTATIVE, PREFERRED, DEPRECATED)
• iface – Pointer to interface is returned

Returns
Pointer to IPv6 address, NULL if not found.

void net_if_ipv6_dad_failed(struct net_if *iface, const struct in6_addr *addr)
Stop IPv6 Duplicate Address Detection (DAD) procedure if we find out that our IPv6 address is already in use.

Parameters
• iface – Interface where the DAD was running.
• addr – IPv6 address that failed DAD
struct *net_if_ipv6_get_global_addr(enum net_addr_state state, struct **iface)

Return global IPv6 address from the first interface that has a global IPv6 address matching the given state.

Parameters
• state – IPv6 address state (ANY, TENTATIVE, PREFERRED, DEPRECATED)
• iface – Caller can give an interface to check. If iface is set to NULL, then all the interfaces are checked. Pointer to interface where the IPv6 address is defined is returned to the caller.

Returns
Pointer to IPv6 address, NULL if not found.

int net_if_config_ipv4_get(struct *iface, struct *ipv4)

Allocate network interface IPv4 config.

Parameters
• iface – Interface to use.
• ipv4 – Pointer to allocated IPv4 struct is returned to caller.

Returns
0 if ok, <0 if error

int net_if_config_ipv4_put(struct *iface)

Release network interface IPv4 config.

Parameters
• iface – Interface to use.

Returns
0 if ok, <0 if error

uint8_t net_if_ipv4_get_ttl(struct *iface)

Get IPv4 time-to-live value specified for a given interface.

Parameters
• iface – Network interface

Returns
Time-to-live

void net_if_ipv4_set_ttl(struct *iface, uint8_t ttl)

Set IPv4 time-to-live value specified to a given interface.

Parameters
• iface – Network interface
• ttl – Time-to-live value

struct *net_if_ipv4_addr_lookup(const struct in_addr *addr, struct **iface)

Check if this IPv4 address belongs to one of the interfaces.

Parameters
• addr – IPv4 address
• iface – Interface is returned

Returns
Pointer to interface address, NULL if not found.
struct net_if_addr *net_if_ipv4_addr_add(struct net_if *iface, struct in_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv4 address to an interface.

**Parameters**

- `iface` – Network interface
- `addr` – IPv4 address
- `addr_type` – IPv4 address type
- `vlifetime` – Validity time for this address

**Returns**

Pointer to interface address, NULL if cannot be added

bool net_if_ipv4_addr_rm(struct net_if *iface, const struct in_addr *addr)

Remove a IPv4 address from an interface.

**Parameters**

- `iface` – Network interface
- `addr` – IPv4 address

**Returns**

True if successfully removed, false otherwise

int net_if_ipv4_addr_lookup_by_index(const struct in_addr *addr)

Check if this IPv4 address belongs to one of the interface indices.

**Parameters**

- `addr` – IPv4 address

**Returns**

>0 if address was found in given network interface index, all other values mean address was not found

bool net_if_ipv4_addr_add_by_index(int index, struct in_addr *addr, enum net_addr_type addr_type, uint32_t vlifetime)

Add a IPv4 address to an interface by network interface index.

**Parameters**

- `index` – Network interface index
- `addr` – IPv4 address
- `addr_type` – IPv4 address type
- `vlifetime` – Validity time for this address

**Returns**

True if ok, false if the address could not be added

bool net_if_ipv4_addr_rm_by_index(int index, const struct in_addr *addr)

Remove a IPv4 address from an interface by interface index.

**Parameters**

- `index` – Network interface index
- `addr` – IPv4 address

**Returns**

True if successfully removed, false otherwise
struct net_if_mcast_addr *net_if_ipv4_maddr_add(struct net_if *iface, const struct in_addr *addr)

Add a IPv4 multicast address to an interface.

**Parameters**
- *iface* – Network interface
- *addr* – IPv4 multicast address

**Returns**
Pointer to interface multicast address, NULL if cannot be added

bool net_if_ipv4_maddr_rm(struct net_if *iface, const struct in_addr *addr)

Remove an IPv4 multicast address from an interface.

**Parameters**
- *iface* – Network interface
- *addr* – IPv4 multicast address

**Returns**
True if successfully removed, false otherwise

struct net_if_mcast_addr *net_if_ipv4_maddr_lookup(const struct in_addr *addr, struct net_if **iface)

Check if this IPv4 multicast address belongs to a specific interface or one of the interfaces.

**Parameters**
- *addr* – IPv4 address
- *iface* – If *iface is null, then pointer to interface is returned, otherwise the *iface value needs to be matched.

**Returns**
Pointer to interface multicast address, NULL if not found.

void net_if_ipv4_maddr_join(struct net_if_mcast_addr *addr)

Mark a given multicast address to be joined.

**Parameters**
- *addr* – IPv4 multicast address

static inline bool net_if_ipv4_maddr_is_joined(struct net_if_mcast_addr *addr)

Check if given multicast address is joined or not.

**Parameters**
- *addr* – IPv4 multicast address

**Returns**
True if address is joined, False otherwise.

void net_if_ipv4_maddr_leave(struct net_if_mcast_addr *addr)

Mark a given multicast address to be left.

**Parameters**
- *addr* – IPv4 multicast address

static inline struct in_addr *net_if_router_ipv4(struct net_if_router *router)

Get the IPv4 address of the given router.

**Parameters**
- *router* – a network router
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Returns
pointer to the IPv4 address, or NULL if none

struct net_if_router *net_if_ipv4_router_lookup(struct net_if *iface, struct in_addr *addr)

Check if IPv4 address is one of the routers configured in the system.

Parameters
- iface – Network interface
- addr – IPv4 address

Returns
Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv4_router_find_default(struct net_if *iface, struct in_addr *addr)

Find default router for this IPv4 address.

Parameters
- iface – Network interface. This can be NULL in which case we go through all the network interfaces to find a suitable router.
- addr – IPv4 address

Returns
Pointer to router information, NULL if cannot be found

struct net_if_router *net_if_ipv4_router_add(struct net_if *iface, struct in_addr *addr, bool is_default, uint16_t router_lifetime)

Add IPv4 router to the system.

Parameters
- iface – Network interface
- addr – IPv4 address
- is_default – Is this router the default one
- router_lifetime – Lifetime of the router

Returns
Pointer to router information, NULL if could not be added

bool net_if_ipv4_router_rm(struct net_if_router *router)

Remove IPv4 router from the system.

Parameters
- router – Router information.

Returns
True if successfully removed, false otherwise

bool net_if_ipv4_addr_mask_cmp(struct net_if *iface, const struct in_addr *addr)

Check if the given IPv4 address belongs to local subnet.

Parameters
- iface – Interface to use. Must be a valid pointer to an interface.
- addr – IPv4 address

Returns
True if address is part of local subnet, false otherwise.
bool net_if_ipv4_is_addr_bcast(struct net_if *iface, const struct in_addr *addr)

Check if the given IPv4 address is a broadcast address.

**Parameters**
- `iface` – Interface to use. Must be a valid pointer to an interface.
- `addr` – IPv4 address, this should be in network byte order

**Returns**
True if address is a broadcast address, false otherwise.

static inline struct net_if *net_if_ipv4_select_src_iface(const struct in_addr *dst)

Get a network interface that should be used when sending IPv4 network data to destination.

**Parameters**
- `dst` – IPv4 destination address

**Returns**
Pointer to network interface to use, NULL if no suitable interface could be found.

static inline const struct in_addr *net_if_ipv4_select_src_addr(struct net_if *iface, const struct in_addr *dst)

Get a IPv4 source address that should be used when sending network data to destination.

**Parameters**
- `iface` – Interface to use when sending the packet. If the interface is not known, then NULL can be given.
- `dst` – IPv4 destination address

**Returns**
Pointer to IPv4 address to use, NULL if no IPv4 address could be found.

struct in_addr *net_if_ipv4_get_ll(struct net_if *iface, enum net_addr_state addr_state)

Get a IPv4 link local address in a given state.

**Parameters**
- `iface` – Interface to use. Must be a valid pointer to an interface.
- `addr_state` – IPv4 address state (preferred, tentative, deprecated)

**Returns**
Pointer to link local IPv4 address, NULL if no proper IPv4 address could be found.

struct in_addr *net_if_ipv4_get_global_addr(struct net_if *iface, enum net_addr_state addr_state)

Get a IPv4 global address in a given state.

**Parameters**
- `iface` – Interface to use. Must be a valid pointer to an interface.
- `addr_state` – IPv4 address state (preferred, tentative, deprecated)

**Returns**
Pointer to link local IPv4 address, NULL if no proper IPv4 address could be found.

void net_if_ipv4_set_netmask(struct net_if *iface, const struct in_addr *netmask)

Set IPv4 netmask for an interface.

**Parameters**
- `iface` – Interface to use.
- `netmask` – IPv4 netmask
bool net_if_ipv4_set_netmask_by_index(int index, const struct in_addr *netmask)
Set IPv4 netmask for an interface index.

Parameters
- index – Network interface index
- netmask – IPv4 netmask

Returns
True if netmask was added, false otherwise.

void net_if_ipv4_set_gw(struct net_if *iface, const struct in_addr *gw)
Set IPv4 gateway for an interface.

Parameters
- iface – Interface to use.
- gw – IPv4 address of an gateway

bool net_if_ipv4_set_gw_by_index(int index, const struct in_addr *gw)
Set IPv4 gateway for an interface index.

Parameters
- index – Network interface index
- gw – IPv4 address of an gateway

Returns
True if gateway was added, false otherwise.

struct net_if *net_if_select_src_iface(const struct sockaddr *dst)
Get a network interface that should be used when sending IPv6 or IPv4 network data to destination.

Parameters
- dst – IPv6 or IPv4 destination address

Returns
Pointer to network interface to use. Note that the function will return the default network interface if the best network interface is not found.

void net_if_register_link_cb(struct net_if_link_cb *link, net_if_link_callback_t cb)
Register a link callback.

Parameters
- link – Caller specified handler for the callback.
- cb – Callback to register.

void net_if_unregister_link_cb(struct net_if_link_cb *link)
Unregister a link callback.

Parameters
- link – Caller specified handler for the callback.

void net_if_call_link_cb(struct net_if *iface, struct net_linkaddr *lladdr, int status)
Call a link callback function.

Parameters
- iface – Network interface.
- lladdr – Destination link layer address
- status – 0 is ok, < 0 error
bool net_if_need_calc_rx_checksum(struct net_if *iface)
Check if received network packet checksum calculation can be avoided or not. For example many ethernet devices support network packet offloading in which case the IP stack does not need to calculate the checksum.

Parameters
• iface – Network interface

Returns
True if checksum needs to be calculated, false otherwise.

bool net_if_need_calc_tx_checksum(struct net_if *iface)
Check if network packet checksum calculation can be avoided or not when sending the packet. For example many ethernet devices support network packet offloading in which case the IP stack does not need to calculate the checksum.

Parameters
• iface – Network interface

Returns
True if checksum needs to be calculated, false otherwise.

struct net_if *net_if_get_by_index(int index)
Get interface according to index.

This is a syscall only to provide access to the object for purposes of assigning permissions.

Parameters
• index – Interface index

Returns
Pointer to interface or NULL if not found.

int net_if_get_by_iface(struct net_if *iface)
Get interface index according to pointer.

Parameters
• iface – Pointer to network interface

Returns
Interface index

void net_if_foreach(net_if_cb_t cb, void *user_data)
Go through all the network interfaces and call callback for each interface.

Parameters
• cb – User-supplied callback function to call
• user_data – User specified data

int net_if_up(struct net_if *iface)
Bring interface up.

Parameters
• iface – Pointer to network interface

Returns
0 on success

static inline bool net_if_is_up(struct net_if *iface)
Check if interface is is up and running.

Parameters

• iface – Pointer to network interface

**Returns**
True if interface is up, False if it is down.

```c
int net_if_down(struct net_if *iface)
```

Bring interface down.

**Parameters**
• iface – Pointer to network interface

**Returns**
0 on success

```c
static inline bool net_if_is_admin_up(struct net_if *iface)
```

Check if interface was brought up by the administrator.

**Parameters**
• iface – Pointer to network interface

**Returns**
True if interface is admin up, false otherwise.

```c
void net_if_carrier_on(struct net_if *iface)
```

Underlying network device has detected the carrier (cable connected).

The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

**Parameters**
• iface – Pointer to network interface

```c
void net_if_carrier_off(struct net_if *iface)
```

Underlying network device has lost the carrier (cable disconnected).

The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

**Parameters**
• iface – Pointer to network interface

```c
static inline bool net_if_is_carrier_ok(struct net_if *iface)
```

Check if carrier is present on network device.

**Parameters**
• iface – Pointer to network interface

**Returns**
True if carrier is present, false otherwise.

```c
void net_if_dormant_on(struct net_if *iface)
```

Mark interface as dormant. Dormant state indicates that the interface is not ready to pass packets yet, but is waiting for some event (for example Wi-Fi network association).

The function should be used by the respective network device driver or L2 implementation to update its state on a network interface.

**Parameters**
• iface – Pointer to network interface
void net_if_dormant_off(struct net_if *iface)
    Mark interface as not dormant.

    The function should be used by the respective network device driver or L2 implementation to
    update its state on a network interface.

    Parameters
    • iface – Pointer to network interface

static inline bool net_if_is_dormant(struct net_if *iface)
    Check if the interface is dormant.

    Parameters
    • iface – Pointer to network interface

    Returns
    True if interface is dormant, false otherwise.

int net_if_set_promisc(struct net_if *iface)
    Set network interface into promiscuous mode.

    Note that not all network technologies will support this.

    Parameters
    • iface – Pointer to network interface

    Returns
    0 on success, <0 if error

void net_if_unset_promisc(struct net_if *iface)
    Set network interface into normal mode.

    Parameters
    • iface – Pointer to network interface

bool net_if_is_promisc(struct net_if *iface)
    Check if promiscuous mode is set or not.

    Parameters
    • iface – Pointer to network interface

    Returns
    True if interface is in promisc mode, False if interface is not in in promiscuous
    mode.

static inline bool net_if_are_pending_tx_packets(struct net_if *iface)
    Check if there are any pending TX network data for a given network interface.

    Parameters
    • iface – Pointer to network interface

    Returns
    True if there are pending TX network packets for this network interface, False
    otherwise.

struct net_if_addr
    #include <net_if.h> Network Interface unicast IP addresses.

    Stores the unicast IP addresses assigned to this network interface.
Public Members

struct net_addr address
    IP address

d_enum net_addr_type addr_type
    How the IP address was set

d_enum net_addr_state addr_state
    What is the current state of the address

uint8_t is_infinite
    Is the IP address valid forever

uint8_t is_used
    Is this IP address used or not

uint8_t is_mesh_local
    Is this IP address usage limited to the subnet (mesh) or not

struct net_if_mcast_addr
    
#include <net_if.h> Network Interface multicast IP addresses.
    Stores the multicast IP addresses assigned to this network interface.

Public Members

struct net_addr address
    IP address

uint8_t is_used
    Is this multicast IP address used or not

uint8_t is_joined
    Did we join to this group

struct net_if_ipv6_prefix
    
#include <net_if.h> Network Interface IPv6 prefixes.
    Stores the multicast IP addresses assigned to this network interface.

Public Members

struct net_timeout lifetime
    Prefix lifetime

struct in6_addr prefix
    IPv6 prefix
struct net_if *iface
    Backpointer to network interface where this prefix is used

uint8_t len
    Prefix length

uint8_t is_infinite
    Is the IP prefix valid forever

uint8_t is_used
    Is this prefix used or not

struct net_if_router
    
#include <net_if.h> Information about routers in the system.
    Stores the router information.

Public Members

sys_snode_t node
    Slist lifetime timer node

struct net_addr address
    IP address

struct net_if *iface
    Network interface the router is connected to

uint32_t life_start
    Router life timer start

uint16_t lifetime
    Router lifetime

uint8_t is_used
    Is this router used or not

uint8_t is_default
    Is default router

uint8_t is_infinite
    Is the router valid forever

struct net_if_ipv6
    
#include <net_if.h>
Public Members

```c
struct net_if_addr unicast[NET_IF_MAX_IPV6_ADDR]
    Unicast IP addresses
```

```c
struct net_if_mcast_addr mcast[NET_IF_MAX_IPV6_MADDR]
    Multicast IP addresses
```

```c
struct net_if_ipv6_prefix prefix[NET_IF_MAX_IPV6_PREFIX]
    Prefixes
```

```c
uint32_t base_reachable_time
    Default reachable time (RFC 4861, page 52)
```

```c
uint32_t reachable_time
    Reachable time (RFC 4861, page 20)
```

```c
uint32_t retrans_timer
    Retransmit timer (RFC 4861, page 52)
```

```c
uint8_t hop_limit
    IPv6 hop limit
```

```c
#include <net_if.h>
```

Public Members

```c
struct net_if_addr unicast[NET_IF_MAX_IPV4_ADDR]
    Unicast IP addresses
```

```c
struct net_if_mcast_addr mcast[NET_IF_MAX_IPV4_MADDR]
    Multicast IP addresses
```

```c
struct in_addr gw
    Gateway
```

```c
struct in_addr netmask
    Netmask
```

```c
uint8_t ttl
    IPv4 time-to-live
```

```c
#include <net_if.h> Network interface IP address configuration.
```

```c
struct net_if_ip
```

```c
#include <net_if.h> IP and other configuration related data for network interface.
```
struct net_traffic_class

#include <net_if.h> Network traffic class.

Traffic classes are used when sending or receiving data that is classified with different priorities. So some traffic can be marked as high priority and it will be sent or received first. Each network packet that is transmitted or received goes through a fifo to a thread that will transmit it.

Public Members

struct k_fifo fifo
    Fifo for handling this Tx or Rx packet

struct k_thread handler
    Traffic class handler thread

k_thread_stack_t *stack
    Stack for this handler

struct net_if_dev

#include <net_if.h> Network Interface Device structure.

Used to handle a network interface on top of a device driver instance. There can be many net_if_dev instance against the same device.

Such interface is mainly to be used by the link layer, but is also tight to a network context: it then makes the relation with a network context and the network device.

Because of the strong relationship between a device driver and such network interface, each net_if_dev should be instantiated by

Public Members

const struct device *dev
    The actually device driver instance the net_if is related to

const struct net_l2 *const 12
    Interface's L2 layer

void *l2_data
    Interface's private L2 data pointer

struct net_linkaddr link_addr
    The hardware link address

uint16_t mtu
    The hardware MTU

enum net_if_oper_state oper_state
    RFC 2863 operational status
struct net_if
    #include <net_if.h> Network Interface structure. Used to handle a network interface on top of a net_if_dev instance. There can be many net_if instance against the same net_if_dev instance.

Public Members

struct net_if_dev *if_dev
    The net_if_dev instance the net_if is related to

struct net_if_config config
    Network interface instance configuration

struct net_if_mcast_monitor
    #include <net_if.h> Multicast monitor handler struct. Stores the multicast callback information. Caller must make sure that the variable pointed by this is valid during the lifetime of registration. Typically this means that the variable cannot be allocated from stack.

Public Members

sys_snode_t node
    Node information for the slist.

struct net_if *iface
    Network interface

net_if_mcast_callback_t cb
    Multicast callback

struct net_if_link_cb
    #include <net_if.h> Link callback handler struct. Stores the link callback information. Caller must make sure that the variable pointed by this is valid during the lifetime of registration. Typically this means that the variable cannot be allocated from stack.

Public Members

sys_snode_t node
    Node information for the slist.

net_if_link_callback_t cb
    Link callback
L2 Layer Management

- **Overview**
- **L2 layer API**
- **Network Device drivers**
  - Ethernet device driver
  - IEEE 802.15.4 device driver
- **API Reference**

**Overview** The L2 stack is designed to hide the whole networking link-layer part and the related device drivers from the upper network stack. This is made through a `net_if` declared in `include/zephyr/net/net_if.h`.

The upper layers are unaware of implementation details beyond the `net_if` object and the generic API provided by the L2 layer in `include/zephyr/net/net_l2.h` as `net_l2`.

Only the L2 layer can talk to the device driver, linked to the `net_if` object. The L2 layer dictates the API provided by the device driver, specific for that device, and optimized for working together.

Currently, there are L2 layers for Ethernet, IEEE 802.15.4 Soft-MAC, Bluetooth IPSP, CANBUS, OpenThread, Wi-Fi, and a dummy layer example that can be used as a template for writing a new one.

**L2 layer API** In order to create an L2 layer, or a driver for a specific L2 layer, one needs to understand how the L3 layer interacts with it and how the L2 layer is supposed to behave. See also network stack architecture for more details. The generic L2 API has these functions:

- `recv()`: All device drivers, once they receive a packet which they put into a `net_pkt`, will push this buffer to the network stack via `net_recv_data()`. At this point, the network stack does not know what to do with it. Instead, it passes the buffer along to the L2 stack's `recv()` function for handling. The L2 stack does what it needs to do with the packet, for example, parsing the link layer header, or handling link-layer only packets. The `recv()` function will return `NET_DROP` in case of an erroneous packet, `NET_OK` if the packet was fully consumed by the L2, or `NET_CONTINUE` if the network stack should then handle it.

- `send()`: Similar to receive function, the network stack will call this function to actually send a network packet. All relevant link-layer content will be generated and added by this function. The `send()` function returns the number of bytes sent, or a negative error code if there was a failure sending the network packet.

- `enable()`: This function is used to enable/disable traffic over a network interface. The function returns <0 if error and >=0 if no error.

- `get_flags()`: This function will return the capabilities of an L2 driver, for example whether the L2 supports multicast or promiscuous mode.

**Network Device drivers** Network device drivers fully follow Zephyr device driver model as a basis. Please refer to Device Driver Model.

There are, however, two differences:

- The `driver_api` pointer must point to a valid `net_if_api` pointer.
- The network device driver must use `NET_DEVICE_INIT_INSTANCE()` or `ETH_NET_DEVICE_INIT()` for Ethernet devices. These macros will call the `DEVICE_DEFINE()` macro, and also instantiate a unique `net_if` related to the created device driver instance.
Implementing a network device driver depends on the L2 stack it belongs to: *Ethernet, IEEE 802.15.4*, etc. In the next section, we will describe how a device driver should behave when receiving or sending a network packet. The rest is hardware dependent and is not detailed here.

**Ethernet device driver** On reception, it is up to the device driver to fill-in the network packet with as many data buffers as required. The network packet itself is a `net_pkt` and should be allocated through `net_pkt_rx_alloc_with_buffer()`. Then all data buffers will be automatically allocated and filled by `net_pkt_write()`.

After all the network data has been received, the device driver needs to call `net_recv_data()`. If that call fails, it will be up to the device driver to unreference the buffer via `net_pkt_unref()`.

On sending, the device driver send function will be called, and it is up to the device driver to send the network packet all at once, with all the buffers.

Each Ethernet device driver will need, in the end, to call `ETH_NET_DEVICE_INIT()` like this:

```c
ETH_NET_DEVICE_INIT(..., CONFIG_ETH_INIT_PRIORITY,
                       &the_valid_net_if_api_instance, 1500);
```

**IEEE 802.15.4 device driver** Device drivers for IEEE 802.15.4 L2 work basically the same as for Ethernet. What has been described above, especially for `recv()`, applies here as well. There are two specific differences however:

- It requires a dedicated device driver API: `ieee802154_radio_api`, which overloads `net_if_api`. This is because 802.15.4 L2 needs more from the device driver than just `send()` and `recv()` functions. This dedicated API is declared in `include/zephyr/net/ieee802154_radio.h`. Each and every IEEE 802.15.4 device driver must provide a valid pointer on such relevantly filled-in API structure.

- Sending a packet is slightly different than in Ethernet. IEEE 802.15.4 sends relatively small frames, 127 bytes all inclusive: frame header, payload and frame checksum. Buffers are meant to fit such frame size limitation. But a buffer containing an IPv6/UDP packet might have more than one fragment. IEEE 802.15.4 drivers handle only one buffer at a time. This is why the `ieee802154_radio_api` requires a tx function pointer which differs from the `net_if_api` send function pointer. Instead, the IEEE 802.15.4 L2, provides a generic `ieee802154_radio_send()` meant to be given as `net_if` send function. It turn, the implementation of `ieee802154_radio_send()` will ensure the same behavior: sending one buffer at a time through `ieee802154_radio_api` tx function, and unreferencing the network packet only when all the transmission were successful.

Each IEEE 802.15.4 device driver, in the end, will need to call `NET_DEVICE_INIT_INSTANCE()` that way:

```c
NET_DEVICE_INIT_INSTANCE(...,
                          the_device_init_prio,
                          &the_valid_ieee802154_radio_api_instance,
                          IEEE802154_L2, NET_L2_GET_CTX_TYPE(IEEE802154_L2), 125);
```

**API Reference**

`group net_12`

Network Layer 2 abstraction layer.
enum net_l2_flags  
L2 flags  
*Values:*  
enumerator NET_L2_MULTICAST = BIT(0)  
  IP multicast supported  
enumerator NET_L2_MULTICAST_SKIP_JOIN_SOLICIT_NODE = BIT(1)  
  Do not join solicited node multicast group  
enumerator NET_L2_PROMISC_MODE = BIT(2)  
  Is promiscuous mode supported  
enumerator NET_L2_POINT_TO_POINT = BIT(3)  
  Is this L2 point-to-point with tunneling so no need to have IP address etc to network interface.

struct net_l2  
#include <net_l2.h> Network L2 structure.  
Used to provide an interface to lower network stack.

Public Members

enum net_verdict (*recv)(struct net_if *iface, struct net_pkt *pkt)  
  This function is used by net core to get iface's L2 layer parsing what's relevant to itself.

int (*send)(struct net_if *iface, struct net_pkt *pkt)  
  This function is used by net core to push a packet to lower layer (interface's L2), which in turn might work on the packet relevantly. (adding proper header etc...) Returns a negative error code, or the number of bytes sent otherwise.

int (*enable)(struct net_if *iface, bool state)  
  This function is used to enable/disable traffic over a network interface. The function returns <0 if error and >=0 if no error.

enum net_l2_flags (*get_flags)(struct net_if *iface)  
  Return L2 flags for the network interface.

Network Traffic Offloading

- Network Offloading
  - Overview
  - API Reference
- Socket Offloading
  - Overview
Network Offloading

Overview  The network offloading API provides hooks that a device vendor can use to provide an alternate implementation for an IP stack. This means that the actual network connection creation, data transfer, etc., is done in the vendor HAL instead of the Zephyr network stack.

API Reference

group net_offload
  Network offloading interface.

Socket Offloading

Overview  In addition to the network offloading API, Zephyr allows offloading of networking functionality at the socket API level. With this approach, vendors who provide an alternate implementation of the networking stack, exposing socket API for their networking devices, can easily integrate it with Zephyr. See drivers/wifi/simplelink/simplelink_sockets.c for a sample implementation on how to integrate network offloading at socket level.

Link Layer Address Handling

Overview  The link layer addresses are set for network interfaces so that L2 connectivity works correctly in the network stack. Typically the link layer addresses are 6 bytes long like in Ethernet but for IEEE 802.15.4 the link layer address length is 8 bytes.

API Reference

group net_linkaddr
  Network link address library.

Defines

NET_LINK_ADDR_MAX_LENGTH
  Maximum length of the link address

Enums

enum net_link_type
  Type of the link address. This indicates the network technology that this address is used in. Note that in order to save space we store the value into a uint8_t variable, so please do not introduce any values > 255 in this enum.

Values:
enumerator NET_LINK_UNKNOW = 0
    Unknown link address type.

enumerator NET_LINK_IEEE802154
    IEEE 802.15.4 link address.

enumerator NET_LINK_BLUETOOTH
    Bluetooth IPSP link address.

enumerator NET_LINK_ETHERNET
    Ethernet link address.

enumerator NET_LINK_DUMMY
    Dummy link address. Used in testing apps and loopback support.

enumerator NET_LINK_CANBUS_RAW
    CANBUS link address.

Functions

static inline bool net_linkaddr_cmp(struct net_linkaddr *lladdr1, struct net_linkaddr *lladdr2)
    Compare two link layer addresses.

Parameters
    • lladdr1 – Pointer to a link layer address
    • lladdr2 – Pointer to a link layer address

Returns
    True if the addresses are the same, false otherwise.

static inline int net_linkaddr_set(struct net_linkaddr_storage *lladdr_store, uint8_t *new_addr, uint8_t new_len)
    Set the member data of a link layer address storage structure.

Parameters
    • lladdr_store – The link address storage structure to change.
    • new_addr – Array of bytes containing the link address.
    • new_len – Length of the link address array. This value should always be <= NET_LINK_ADDR_MAX_LENGTH.

struct net_linkaddr
    #include <net_linkaddr.h> Hardware link address structure.
    Used to hold the link address information

Public Members

uint8_t *addr
    The array of byte representing the address
uint8_t len
    Length of that address array

uint8_t type
    What kind of address is this for

struct net_linkaddr_storage
    
    #include <net_linkaddr.h> Hardware link address structure.
    
    Used to hold the link address information. This variant is needed when we have to store the
    link layer address.
    
    Note that you cannot cast this to net_linkaddr as uint8_t * is handled differently than uint8_t
    addr[] and the fields are purposely in different order.

Public Members

uint8_t type
    What kind of address is this for

uint8_t len
    The real length of the ll address.

uint8_t addr[6]
    The array of bytes representing the address

Ethernet Management

- Overview
- API Reference

Overview  Ethernet management API provides functions to manage the Ethernet network interface low
level status. The caller of these functions can:

- raise carrier ON or carrier OFF management events
- raise VLAN enabled or VLAN disabled management events

Typically the carrier OFF event would be generated by the Ethernet device driver when it notices that
the Ethernet cable is disconnected. The carrier ON event would be generated if the Ethernet device
driver notices that the Ethernet cable is re-connected.

Currently the VLAN events are generated by the Ethernet L2 layer when a specific VLAN tag is either
enabled or disabled.

The user application can monitor these events if it needs to act when the corresponding status changes.

API Reference

group ethernet_mgmt
    Ethernet library.
Functions

void ethernet_mgmt_raise_carrier_on_event(struct net_if *iface)
    Raise CARRIER_ON event when Ethernet is connected.

Parameters
    • iface – Ethernet network interface.

void ethernet_mgmt_raise_carrier_off_event(struct net_if *iface)
    Raise CARRIER_OFF event when Ethernet is disconnected.

Parameters
    • iface – Ethernet network interface.

void ethernet_mgmt_raise_vlan_enabled_event(struct net_if *iface, uint16_t tag)
    Raise VLAN_ENABLED event when VLAN is enabled.

Parameters
    • iface – Ethernet network interface.
    • tag – VLAN tag which is enabled.

void ethernet_mgmt_raise_vlan_disabled_event(struct net_if *iface, uint16_t tag)
    Raise VLAN_DISABLED event when VLAN is disabled.

Parameters
    • iface – Ethernet network interface.
    • tag – VLAN tag which is disabled.

Traffic Classification

Overview  Traffic classification is an automated process that categorizes computer network traffic according to various parameters. For Zephyr, the VLAN priority code point (PCP) is used to classify both received and sent network packets. See more information about VLAN priority at IEEE 802.1Q.

By default, all network traffic is treated equal in Zephyr. If desired, the option CONFIG_NET_TC_TX_COUNT can be used to set the number of transmit queues. The option CONFIG_NET_TC_RX_COUNT can be used to set the number of receive queues. Each traffic class queue corresponds to a specific kernel work queue. Each kernel work queue has a priority. The VLAN priority is mapped to a certain traffic class according to rules specified in IEEE 802.1Q spec chapter 1.3, chapter 8.6.6 table 8-4, and chapter 34.5 table 34-1. Each traffic class is in turn mapped to a certain kernel work queue. The maximum number of traffic classes for both Rx and Tx is 8.

See subsys/net/ip/net_tc.c for details of how various mappings are done.

Network Packet Filtering

• Overview
• Examples
• API Reference

6.2. Networking 2009
Overview  The Network Packet Filtering facility provides the infrastructure to construct custom rules for accepting and/or denying packet transmission and reception. This can be used to create a basic firewall, control network traffic, etc.

The CONFIG_NET_PKT_FILTER must be set in order to enable the relevant APIs.

Both the transmission and reception paths may have a list of filter rules. Each rule is made of a set of conditions and a packet outcome. Every packet is subjected to the conditions attached to a rule. When all the conditions for a given rule are true then the packet outcome is immediately determined as specified by the current rule and no more rules are considered. If one condition is false then the next rule in the list is considered.

Packet outcome is either NET_OK to accept the packet or NET_DROP to drop it.

A rule is represented by a npf_rule object. It can be inserted to, appended to or removed from a rule list contained in a npf_rule_list object using npf_insert_rule(), npf_append_rule(), and npf_remove_rule(). Currently, two such rule lists exist: npf_send_rules for outgoing packets, and npf_recv_rules for incoming packets.

If a filter rule list is empty then NET_OK is assumed. If a non-empty rule list runs to the end then NET_DROP is assumed. However it is recommended to always terminate a non-empty rule list with an explicit default termination rule, either npf_default_ok or npf_default_drop.

Rule conditions are represented by a npf_test. This structure can be embedded into a larger structure when a specific condition requires extra test data. It is up to the test function for such conditions to retrieve the outer structure from the provided npf_test structure pointer.

Convenience macros are provided in include/zephyr/net/net_pkt_filter.h to statically define condition instances for various conditions, and NPF_RULE() to create a rule instance to tie them.

Examples  Here's an example usage:

```c
static NPF_SIZE_MAX(maxsize_200, 200);
static NPF_ETH_TYPE_MATCH(ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(small_ip_pkt, NET_OK, ip_packet, maxsize_200);

void install_my_filter(void)
{
    npf_insert_recv_rule(&npf_default_drop);
    npf_insert_recv_rule(&small_ip_pkt);
}
```

The above would accept IP packets that are 200 bytes or smaller, and drop all other packets.

Another (less efficient) way to achieve the same result could be:

```c
static NPF_SIZE_MIN(minsize_201, 201);
static NPF_ETH_TYPE_UNMATCH(not_ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(reject_big_pkts, NET_DROP, minsize_201);
static NPF_RULE(reject_non_ip, NET_DROP, not_ip_packet);

void install_my_filter(void) {
    npf_append_recv_rule(&reject_big_pkts);
    npf_append_recv_rule(&reject_non_ip);
    npf_append_recv_rule(&npf_default_ok);
}
```

API Reference
**group net_pkt_filter**

Network Packet Filter API.

**Defines**

- `npf_insert_send_rule(rule)`
- `npf_insert_recv_rule(rule)`
- `npf_append_send_rule(rule)`
- `npf_append_recv_rule(rule)`
- `npf_remove_send_rule(rule)`
- `npf_remove_recv_rule(rule)`
- `npf_remove_all_send_rules()`
- `npf_remove_all_recv_rules()`

**NPF_RULE(_name, _result, ...)**

Statically define one packet filter rule.

This creates a rule from a variable amount of filter conditions. This rule can then be inserted or appended to the rule list for a given network packet path.

**Example:**

```c
static NPF_SIZE_MAX(maxsize_200, 200);
static NPF_ETH_TYPE_MATCH(ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(small_ip_pkt, NET_OK, ip_packet, maxsize_200);

void install_my_filter(void)
{
    npf_insert_recv_rule(&npf_default_drop);
    npf_insert_recv_rule(&small_ip_pkt);
}
```

The above would accept IP packets that are 200 bytes or smaller, and drop all other packets. Another (less efficient) way to create the same result could be:

```c
static NPF_SIZE_MIN(minsize_201, 201);
static NPF_ETH_TYPE_UNMATCH(not_ip_packet, NET_ETH_PTYPE_IP);
static NPF_RULE(reject_big_pkts, NET_DROP, minsize_201);
static NPF_RULE(reject_non_ip, NET_DROP, not_ip_packet);

void install_my_filter(void) {
    npf_append_recv_rule(&reject_big_pkts);
    npf_append_recv_rule(&reject_non_ip);
    npf_append_recv_rule(&npf_default_ok);
}
```
The first rule in the list for which all conditions are true determines the fate of the packet. If one condition is false then the next rule in the list is evaluated.

**Parameters**

- `_name` – Name for this rule.
- `_result` – Fate of the packet if all conditions are true, either `NET_OK` or `NET_DROP`.
- ... – List of conditions for this rule.

**Functions**

```c
void npf_insert_rule(struct npf_rule_list *rules, struct npf_rule *rule)
```

Insert a rule at the front of given rule list.

**Parameters**

- `rules` – the affected rule list
- `rule` – the rule to be inserted

```c
void npf_append_rule(struct npf_rule_list *rules, struct npf_rule *rule)
```

Append a rule at the end of given rule list.

**Parameters**

- `rules` – the affected rule list
- `rule` – the rule to be appended

```c
bool npf_remove_rule(struct npf_rule_list *rules, struct npf_rule *rule)
```

Remove a rule from the given rule list.

**Parameters**

- `rules` – the affected rule list
- `rule` – the rule to be removed

**Return values**

`true` – if given rule was found in the rule list and removed

```c
bool npf_remove_all_rules(struct npf_rule_list *rules)
```

Remove all rules from the given rule list.

**Parameters**

- `rules` – the affected rule list

**Return values**

`true` – if at least one rule was removed from the rule list

**Variables**

```c
struct npf_rule npf_default_ok
```

Default rule list termination for accepting a packet.

```c
struct npf_rule npf_default_drop
```

Default rule list termination for rejecting a packet.
struct npf_rule_list npf_send_rules
    rule list applied to outgoing packets

struct npf_rule_list npf_recv_rules
    rule list applied to incoming packets

struct npf_test
    #include <net_pkt_filter.h> common filter test structure to be embedded into larger structures

    Public Members

    npf_test_fn_t *fn
        packet condition test function

struct npf_rule
    #include <net_pkt_filter.h> filter rule structure

    Public Members

    enum net_verdict result
        result if all tests pass

    uint32_t nb_tests
        number of tests for this rule

    struct npf_test *tests[]
        pointers to npf_test instances

struct npf_rule_list
    #include <net_pkt_filter.h> rule set for a given test location

group npf_basic_cond

Defines

NPF_IFACE_MATCH(_name, _iface)
    Statically define an “interface match” packet filter condition.

    Parameters
    • _name – Name of the condition
    • _iface – Interface to match

NPF_IFACE_UNMATCH(_name, _iface)
    Statically define an “interface unmatch” packet filter condition.

    Parameters
    • _name – Name of the condition
    • _ iface – Interface to exclude
NPF_ORIG_IFACE_MATCH(_name, _iface)
   Statically define an “orig interface match” packet filter condition.
   
   Parameters
   • _name – Name of the condition
   • _iface – Interface to match

NPF_ORIG_IFACE_UNMATCH(_name, _iface)
   Statically define an “orig interface unmatch” packet filter condition.
   
   Parameters
   • _name – Name of the condition
   • _iface – Interface to exclude

NPF_SIZE_MIN(_name, _size)
   Statically define a “data minimum size” packet filter condition.
   
   Parameters
   • _name – Name of the condition
   • _size – Lower bound of the packet's data size

NPF_SIZE_MAX(_name, _size)
   Statically define a “data maximum size” packet filter condition.
   
   Parameters
   • _name – Name of the condition
   • _size – Higher bound of the packet's data size

NPF_SIZE_BOUNDS(_name, _min_size, _max_size)
   Statically define a “data bounded size” packet filter condition.
   
   Parameters
   • _name – Name of the condition
   • _min_size – Lower bound of the packet's data size
   • _max_size – Higher bound of the packet's data size

**group npf_eth_cond**

**Defines**

NPF_ETH_SRC_ADDR_MATCH(_name, _addr_array)
   Statically define a “source address match” packet filter condition.
   
   This tests if the packet source address matches any of the Ethernet addresses contained in the
   provided set.
   
   Parameters
   • _name – Name of the condition
   • _addr_array – Array of struct net_eth_addr items to test against

NPF_ETH_SRC_ADDR_UNMATCH(_name, _addr_array)
   Statically define a “source address unmatch” packet filter condition.
   
   This tests if the packet source address matches none of the Ethernet addresses contained in
   the provided set.
NPF_ETH_DST_ADDR_MATCH(_name, _addr_array)
Statically define a “destination address match” packet filter condition.
This tests if the packet destination address matches any of the Ethernet addresses contained in the provided set.

Parameters
• _name – Name of the condition
• _addr_array – Array of struct net_eth_addr items to test against

NPF_ETH_DST_ADDR_UNMATCH(_name, _addr_array)
Statically define a “destination address unmatch” packet filter condition.
This tests if the packet destination address matches none of the Ethernet addresses contained in the provided set.

Parameters
• _name – Name of the condition
• _addr_array – Array of struct net_eth_addr items to test against

NPF_ETH_SRC_ADDR_MASK_MATCH(_name, _addr_array, ...)
Statically define a “source address match with mask” packet filter condition.
This tests if the packet source address matches any of the Ethernet addresses contained in the provided set after applying specified mask.

Parameters
• _name – Name of the condition
• _addr_array – Array of struct net_eth_addr items to test against
• ... – up to 6 mask bytes

NPF_ETH_DST_ADDR_MASK_MATCH(_name, _addr_array, ...)
Statically define a “destination address match with mask” packet filter condition.
This tests if the packet destination address matches any of the Ethernet addresses contained in the provided set after applying specified mask.

Parameters
• _name – Name of the condition
• _addr_array – Array of struct net_eth_addr items to test against
• ... – up to 6 mask bytes

NPF_ETH_TYPE_MATCH(_name, _type)
Statically define an “Ethernet type match” packet filter condition.

Parameters
• _name – Name of the condition
• _type – Ethernet type to match

NPF_ETH_TYPE_UNMATCH(_name, _type)
Statically define an “Ethernet type unmatch” packet filter condition.

Parameters
• _name – Name of the condition
• _type – Ethernet type to exclude

**Network Shell**  Network shell provides helpers for figuring out network status, enabling/disabling features, and issuing commands like ping or DNS resolving. Note that net-shell should probably not be used in production code as it will require extra memory. See also *generic shell* for detailed shell information.

The following net-shell commands are implemented:

<table>
<thead>
<tr>
<th>Command</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>net allocs</td>
<td>Print network memory allocations. Only available if CONFIG_NET_DEBUG_NET_PKT_ALLOC is set.</td>
</tr>
<tr>
<td>net arp</td>
<td>Print information about IPv4 ARP cache. Only available if CONFIG_NET_ARP is set in IPv4 enabled networks.</td>
</tr>
<tr>
<td>net capture</td>
<td>Monitor network traffic See <em>Monitor Network Traffic</em> for details.</td>
</tr>
<tr>
<td>net conn</td>
<td>Print information about network connections.</td>
</tr>
<tr>
<td>net dns</td>
<td>Show how DNS is configured. The command can also be used to resolve a DNS name. Only available if CONFIG_DNS_RESOLVER is set.</td>
</tr>
<tr>
<td>net events</td>
<td>Enable network event monitoring. Only available if CONFIG_NET_MGMT_EVENT_MONITOR is set.</td>
</tr>
<tr>
<td>net gptp</td>
<td>Print information about gPTP support. Only available if CONFIG_NET_GPTP is set.</td>
</tr>
<tr>
<td>net iface</td>
<td>Print information about network interfaces.</td>
</tr>
<tr>
<td>net ipv6</td>
<td>Print IPv6 specific information and configuration. Only available if CONFIG_NET_IPV6 is set.</td>
</tr>
<tr>
<td>net mem</td>
<td>Print information about network memory usage. The command will print more information if CONFIG_NET_BUF_POOL_USAGE is set.</td>
</tr>
<tr>
<td>net nbr</td>
<td>Print neighbor information. Only available if CONFIG_NET_IPV6 is set.</td>
</tr>
<tr>
<td>net ping</td>
<td>Ping a network host.</td>
</tr>
<tr>
<td>net route</td>
<td>Show IPv6 network routes. Only available if CONFIG_NET_ROUTE is set.</td>
</tr>
<tr>
<td>net stats</td>
<td>Show network statistics.</td>
</tr>
<tr>
<td>net tcp</td>
<td>Connect/send data/close TCP connection. Only available if CONFIG_NET_TCP is set.</td>
</tr>
<tr>
<td>net vlan</td>
<td>Show Ethernet virtual LAN information. Only available if CONFIG_NET_VLAN is set.</td>
</tr>
</tbody>
</table>

**Time Sensitive Networking**

generic Precision Time Protocol (gPTP)

- **Overview**
- **Supported features**
- **Supported hardware**
- **Enabling the stack**
- **Application interfaces**
- **Testing**
- **API Reference**

**Overview**  This gPTP stack supports the protocol and procedures as defined in the IEEE 802.1AS-2011 standard (Timing and Synchronization for Time-Sensitive Applications in Bridged Local Area Networks).
**Supported features**  The stack handles communications and state machines defined in the IEEE 802.1AS-2011 standard. Mandatory requirements for a full-duplex point-to-point link endpoint, as defined in Annex A of the standard, are supported.

The stack is in principle capable of handling communications on multiple network interfaces (also defined as “ports” in the standard) and thus act as a 802.1AS bridge. However, this mode of operation has not been validated on the Zephyr OS.

**Supported hardware**  Although the stack itself is hardware independent, Ethernet frame timestamping support must be enabled in ethernet drivers.

Boards supported:
- frdm_k64f
- nucleo_h743zi_board
- nucleo_h745zi_q_board
- nucleo_f767zi_board
- sam_e70_xplained
- nativeposix (only usable for simple testing, limited capabilities due to lack of hardware clock)
- qemu_x86 (emulated, limited capabilities due to lack of hardware clock)

**Enabling the stack**  The following configuration option must me enabled in prj.conf file.

- CONFIG_NET_GPTP

**Application interfaces**  Only two Application Interfaces as defined in section 9 of the standard are available:

- ClockTargetPhaseDiscontinuity interface (*gptp_register_phase_dis_cb()*)
- ClockTargetEventCapture interface (*gptp_event_capture()*)

**Testing**  The stack has been informally tested using the OpenAVnu gPTP and Linux ptp4l daemons. The gPTP sample application from the Zephyr source distribution can be used for testing.

**API Reference**

**group gptp**

generic Precision Time Protocol (gPTP) support

**Typedefs**

```c
typedef void (*gptp_phase_dis_callback_t)(uint8_t *gm_identity, uint16_t *time_base, struct gptp_scaled_ns *last_gm_ph_change, double *last_gm_freq_change)
```

Define callback that is called after a phase discontinuity has been sent by the grandmaster.

**Param gm_identity**  A pointer to first element of a ClockIdentity array. The size of the array is GPTP_CLOCK_ID_LEN.

**Param time_base**  A pointer to the value of timeBaseIndicator of the current grandmaster.
Param last_gm_ph_change
   A pointer to the value of lastGmPhaseChange received from grandmaster.

Param last_gm_freq_change
   A pointer to the value of lastGmFreqChange received from the grandmaster.

typedef void (*gptp_port_cb_t)(int port, struct net_if *iface, void *user_data)
Callback used while iterating over gPTP ports.

Param port
   Port number

Param iface
   Pointer to network interface

Param user_data
   A valid pointer to user data or NULL

Functions

void gptp_register_phase_dis_cb(struct gptp_phase_dis_cb *phase_dis,
                                 gptp_phase_dis_callback_t cb)
Register a phase discontinuity callback.

Parameters
   • phase_dis – Caller specified handler for the callback.
   • cb – Callback to register.

void gptp_unregister_phase_dis_cb(struct gptp_phase_dis_cb *phase_dis)
Unregister a phase discontinuity callback.

Parameters
   • phase_dis – Caller specified handler for the callback.

void gptp_call_phase_dis_cb(void)
Call a phase discontinuity callback function.

int gptp_event_capture(struct net_ptp_time *slave_time, bool *gm_present)
Get gPTP time.

Parameters
   • slave_time – A pointer to structure where timestamp will be saved.
   • gm_present – A pointer to a boolean where status of the presence of a grand
     master will be saved.

Returns
   Error code. 0 if no error.

char *gptp_sprint_clock_id(const uint8_t *clk_id, char *output, size_t output_len)
Utility function to print clock id to a user supplied buffer.

Parameters
   • clk_id – Clock id
   • output – Output buffer
   • output_len – Output buffer len

Returns
   Pointer to output buffer
void gptp_foreach_port(gptp_port_cb_t cb, void *user_data)
   Go through all the gPTP ports and call callback for each of them.

   Parameters
   • cb – User-supplied callback function to call
   • user_data – User specified data

struct gptp_domain *gptp_get_domain(void)
   Get gPTP domain.
   This contains all the configuration / status of the gPTP domain.

   Returns
   Pointer to domain or NULL if not found.

void gptp_clk_src_time_invoke(struct gptp_clk_src_time_invoke_params *arg)
   This interface is used by the ClockSource entity to provide time to the ClockMaster entity of a
   time-aware system.

   Parameters
   • arg – Current state and parameters of the ClockSource entity.

struct gptp_hdr *gptp_get_hdr(struct net_pkt *pkt)
   Return pointer to gPTP packet header in network packet.

   Parameters
   • pkt – Network packet (received or sent)

   Returns
   Pointer to gPTP header.

struct gptp_scaled_ns
   #include <gptp.h> Scaled Nanoseconds.

   Public Members

   int32_t high
      High half.

   int64_t low
      Low half.

struct gptp_uscaled_ns
   #include <gptp.h> UScaled Nanoseconds.

   Public Members

   uint32_t high
      High half.

   uint64_t low
      Low half.
struct gptp_port_identity
#include <gptp.h> Port Identity.

Public Members

uint8_t clk_id[GPTP_CLOCK_ID_LEN]
Clock identity of the port.

uint16_t port_number
Number of the port.

struct gptp_flags
#include <gptp.h>

Public Members

uint8_t octets[2]
Byte access.

uint16_t all
Whole field access.

struct gptp_hdr
#include <gptp.h>

Public Members

uint8_t message_type
Type of the message.

uint8_t transport_specific
Transport specific, always 1.

uint8_t ptp_version
Version of the PTP, always 2.

uint8_t reserved0
Reserved field.

uint16_t message_length
Total length of the message from the header to the last TLV.

uint8_t domain_number
Domain number, always 0.
uint8_t reserved1
   Reserved field.

struct gptp_flags flags
   Message flags.

int64_t correction_field
   Correction Field. The content depends of the message type.

uint32_t reserved2
   Reserved field.

struct gptp_port_identity port_id
   Port Identity of the sender.

uint16_t sequence_id
   Sequence Id.

uint8_t control
   Control value. Sync: 0, Follow-up: 2, Others: 5.

int8_t log_msg_interval
   Message Interval in Log2 for Sync and Announce messages.

struct gptp_phase_dis_cb
   #include <gptp.h> Phase discontinuity callback structure.
   Stores the phase discontinuity callback information. Caller must make sure that the variable pointed by this is valid during the lifetime of registration. Typically this means that the variable cannot be allocated from stack.

Public Members

sys_sn_t node
   Node information for the slist.

  gptp_phase_dis_callback_t cb
   Phase discontinuity callback.

struct gptp_clk_src_time_invoke_params
   #include <gptp.h> ClockSourceTime.invoke function parameters.
   Parameters passed by ClockSourceTime.invoke function.

Public Members

double last_gm_freq_change
   Frequency change on the last Time Base Indicator Change.
struct net_ptp_extended_time src_time
    The time this function is invoked.

struct gptp_scaled_ns last_gm_phase_change
    Phase change on the last Time Base Indicator Change.

uint16_t time_base_indicator
    Time Base - changed only if Phase or Frequency changes.

Precision Time Protocol (PTP) time format

- **Overview**
  The PTP time struct can store time information in high precision format (nanoseconds). The extended timestamp format can store the time in fractional nanoseconds accuracy. The PTP time format is used in *generic Precision Time Protocol (gPTP)* implementation.

- **API Reference**

  **group** ptp_time
  Precision Time Protocol time specification.

  **struct** net_ptp_time
  #include <ptp_time.h> Precision Time Protocol Timestamp format.
  This structure represents a timestamp according to the Precision Time Protocol standard.
  Seconds are encoded as a 48 bits unsigned integer. Nanoseconds are encoded as a 32 bits unsigned integer.

  **Public Members**

  union net_ptp_time.[anonymous] [anonymous]
  Seconds encoded on 48 bits.

  **struct** net_ptp_extended_time
  #include <ptp_time.h> Precision Time Protocol Extended Timestamp format.
  This structure represents an extended timestamp according to the Precision Time Protocol standard.
  Seconds are encoded as 48 bits unsigned integer. Fractional nanoseconds are encoded as 48 bits, their unit is $2^{-16}$ ns.
Public Members

union net_ptp_extended_time [anonymous] [anonymous]
Seconds encoded on 48 bits.

union net_ptp_extended_time [anonymous] [anonymous]
Fractional nanoseconds on 48 bits.

Generic GSM Modem

Overview The generic GSM modem driver allows the user to connect Zephyr to a GSM modem which provides a data connection to cellular operator's network. The Zephyr uses PPP (Point-to-Point Protocol) to connect to the GSM modem using UART. Note that some cellular modems have proprietary offloading support using AT commands, but usually those modems also support 3GPP standards and provide PPP connection to them. See GSM modem sample application how to setup Zephyr to use the GSM modem.

The GSM muxing, that is defined in GSM 07.10, and which allows mixing of AT commands and PPP traffic, is also supported in this version of Zephyr. One needs to enable CONFIG_GSM_MUX and CONFIG_UART_MUX configuration options to enable muxing.

zperf: Network Traffic Generator

Overview zperf is a shell utility which allows to generate network traffic in Zephyr. The tool may be used to evaluate network bandwidth.

zperf is compatible with iPerf_2.0.5. Note that in newer iPerf versions, an error message like this is printed and the server reported statistics are missing.

LAST PACKET NOT RECEIVED!!!

zperf can be enabled in any application, a dedicated sample is also present in Zephyr. See zperf sample application for details.

Sample Usage If Zephyr acts as a client, iPerf must be executed in server mode. For example, the following command line must be used for UDP testing:

$ iperf -s -l 1K -u -V -B 2001:db8::2

For TCP testing, the command line would look like this:

$ iperf -s -l 1K -V -B 2001:db8::2

In the Zephyr console, zperf can be executed as follows:

zperf udp upload 2001:db8::2 5001 10 1K 1M

For TCP the zperf command would look like this:

zperf tcp upload 2001:db8::2 5001 10 1K 1M
If the IP addresses of Zephyr and the host machine are specified in the config file, `zperf` can be started as follows:

```
zperf udp upload2 v6 10 1K 1M
```

or like this if you want to test TCP:

```
zperf tcp upload2 v6 10 1K 1M
```

If Zephyr is acting as a server, set the download mode as follows for UDP:

```
zperf udp download 5001
```

or like this for TCP:

```
zperf tcp download 5001
```

and in the host side, `iperf` must be executed with the following command line if you are testing UDP:

```
$ iperf -l 1K -u -V -c 2001:db8::1 -p 5001
```

and this if you are testing TCP:

```
$ iperf -l 1K -V -c 2001:db8::1 -p 5001
```

`iperf` output can be limited by using the `-b` option if Zephyr is not able to receive all the packets in orderly manner.

### 6.3 LoRa and LoRaWAN

#### 6.3.1 Overview

LoRa (abbrev. for Long Range) is a proprietary low-power wireless communication protocol developed by the Semtech Corporation.

LoRa acts as the physical layer (PHY) based on the chirp spread spectrum (CSS) modulation technique. LoRaWAN (for Long Range Wide Area Network) defines a networking layer on top of the LoRa PHY.

Zephyr provides APIs for LoRa to send raw data packets directly over the wireless interface as well as APIs for LoRaWAN to connect the end device to the internet through a gateway.

The Zephyr implementation is based on Semtech's LoRaMac-node library, which is included as a Zephyr module.

The LoRaWAN specification is published by the LoRa Alliance.

#### 6.3.2 Configuration Options

**LoRa PHY**

Related configuration options can be found under `drivers/lora/Kconfig`.

- `CONFIG_LORA`
- `CONFIG_LORA_SHELL`
- `CONFIG_LORA_INIT_PRIORITY`
LoRaWAN

Related configuration options can be found under `subsys/lorawan/Kconfig`.

- `CONFIG_LORAWAN`
- `CONFIG_LORAWAN_SYSTEM_MAX_RX_ERROR`
- `CONFIG_LORAMAC_REGION_AS923`
- `CONFIG_LORAMAC_REGION_AU915`
- `CONFIG_LORAMAC_REGION_CN470`
- `CONFIG_LORAMAC_REGION_CN779`
- `CONFIG_LORAMAC_REGION_EU433`
- `CONFIG_LORAMAC_REGION_EU868`
- `CONFIG_LORAMAC_REGION_KR920`
- `CONFIG_LORAMAC_REGION_IN865`
- `CONFIG_LORAMAC_REGION_US915`
- `CONFIG_LORAMAC_REGION_RU864`

### 6.3.3 API Reference

**LoRa PHY**

`group lora_api`

**Enums**

```c
enum lora_signal_bandwidth

Values:

enumerator BW_125_KHZ = 0
enumerator BW_250_KHZ
enumerator BW_500_KHZ
```

```c
enum lora_datarate

Values:

enumerator SF_6 = 6
enumerator SF_7
enumerator SF_8
enumerator SF_9
```
enumerator SF_10
enumerator SF_11
enumerator SF_12

enum lora_coding_rate
Values:
enumerator CR_4_5 = 1
enumerator CR_4_6 = 2
enumerator CR_4_7 = 3
enumerator CR_4_8 = 4

Functions

static inline int lora_config(const struct device *dev, struct lora_modem_config *config)
Configure the LoRa modem.

Parameters
• dev – LoRa device
• config – Data structure containing the intended configuration for the modem

Returns
0 on success, negative on error

static inline int lora_send(const struct device *dev, uint8_t *data, uint32_t data_len)
Send data over LoRa.

Note: This blocks until transmission is complete.

Parameters
• dev – LoRa device
• data – Data to be sent
• data_len – Length of the data to be sent

Returns
0 on success, negative on error

static inline int lora_send_async(const struct device *dev, uint8_t *data, uint32_t data_len,
struct k_poll_signal *async)
Asynchronously send data over LoRa.

Note: This returns immediately after starting transmission, and locks the LoRa modem until the transmission completes.
Parameters

• dev – LoRa device
• data – Data to be sent
• data_len – Length of the data to be sent
• async – A pointer to a valid and ready to be signaled struct k_poll_signal. (Note: if NULL this function will not notify the end of the transmission).

Returns

0 on success, negative on error

static inline int lora_recv(const struct device *dev, uint8_t *data, uint8_t size, k_timeout_t *timeout, int16_t *rssi, int8_t *snr)

Receive data over LoRa.

Note: This is a blocking call.

Parameters

• dev – LoRa device
• data – Buffer to hold received data
• size – Size of the buffer to hold the received data. Max size allowed is 255.
• timeout – Duration to wait for a packet.
• rssi – RSSI of received data
• snr – SNR of received data

Returns

Length of the data received on success, negative on error

static inline int lora_recv_async(const struct device *dev, lora_recv_cb cb)

Receive data asynchronously over LoRa.

Receive packets continuously under the configuration previously setup by lora_config.

Reception is cancelled by calling this function again with cb = NULL. This can be done within the callback handler.

Parameters

• dev – Modem to receive data on.
• cb – Callback to run on receiving data. If NULL, any pending asynchronous receptions will be cancelled.

Returns

0 when reception successfully setup, negative on error

static inline int lora_test_cw(const struct device *dev, uint32_t frequency, int8_t tx_power, uint16_t duration)

Transmit an unmodulated continuous wave at a given frequency.

Note: Only use this functionality in a test setup where the transmission does not interfere with other devices.
• dev – LoRa device
• frequency – Output frequency (Hertz)
• tx_power – TX power (dBm)
• duration – Transmission duration in seconds.

**Returns**
0 on success, negative on error

```c
struct lora_modem_config
```

```
#include <lora.h>
```

**Public Members**

bool iq_inverted
Invert the In-Phase and Quadrature (IQ) signals. Normally this should be set to false. In advanced use-cases where a differentiation is needed between “uplink” and “downlink” traffic, the IQ can be inverted to create two different channels on the same frequency

bool public_network
Sets the sync-byte to use:
• false: for using the private network sync-byte
• true: for using the public network sync-byte The public network sync-byte is only intended for advanced usage. Normally the private network sync-byte should be used for peer to peer communications and the LoRaWAN APIs should be used for interacting with a public network.

**LoRaWAN**

*group lorawan_api*

**Defines**

LW_RECV_PORT_ANY

**Enums**

enum lorawan_class
LoRaWAN class types.
*Values:*

enumerator LORAWAN_CLASS_A = 0x00
enumerator LORAWAN_CLASS_B = 0x01
enumerator LORAWAN_CLASS_C = 0x02
enum lorawan_act_type
LoRaWAN activation types.

Values:

enumerator LORAWAN_ACT_OTAA = 0
enumerator LORAWAN_ACT_ABP

enum lorawan_datarate
LoRaWAN datarate types.

Values:

enumerator LORAWAN_DR_0 = 0
enumerator LORAWAN_DR_1
enumerator LORAWAN_DR_2
enumerator LORAWAN_DR_3
enumerator LORAWAN_DR_4
enumerator LORAWAN_DR_5
enumerator LORAWAN_DR_6
enumerator LORAWAN_DR_7
enumerator LORAWAN_DR_8
enumerator LORAWAN_DR_9
enumerator LORAWAN_DR_10
enumerator LORAWAN_DR_11
enumerator LORAWAN_DR_12
enumerator LORAWAN_DR_13
enumerator LORAWAN_DR_14
enumerator LORAWAN_DR_15
enum lorawan_region
   LoRaWAN region types.
   Values:

   enumerator LORAWAN_REGION_AS923
   enumerator LORAWAN_REGION_AU915
   enumerator LORAWAN_REGION_CN470
   enumerator LORAWAN_REGION_CN779
   enumerator LORAWAN_REGION_EU433
   enumerator LORAWAN_REGION_EU868
   enumerator LORAWAN_REGION_KR920
   enumerator LORAWAN_REGION_IN865
   enumerator LORAWAN_REGION_US915
   enumerator LORAWAN_REGION_RU864

enum lorawan_message_type
   LoRaWAN message types.
   Values:

   enumerator LORAWAN_MSG_UNCONFIRMED = 0
   enumerator LORAWAN_MSG_CONFIRMED

Functions

int lorawan_set_battery_level_callback(uint8_t (*battery_lvl_cb)(void))
   Add battery level callback function.

   Provide the LoRaWAN stack with a function to be called whenever a battery level needs to be read. As per LoRaWAN specification the callback needs to return "0: node is connected to an external power source,
1..254: battery level, where 1 is the minimum and 254 is the maximum value,
255: the node was not able to measure the battery level"
   Should no callback be provided the lorawan backend will report 255.

Parameters
• battery_lvl_cb – Pointer to the battery level function

Returns
0 if successful, negative errno code if failure

void lorawan_register_downlink_callback(struct lorawan_downlink_cb *cb)
Register a callback to be run on downlink packets.

Parameters
• cb – Pointer to structure containing callback parameters

void lorawan_register_dr_changed_callback(void (*dr_cb)(enum lorawan_datarate))
Register a callback to be called when the datarate changes.
The callback is called once upon successfully joining a network and again each time the datarate changes due to ADR.
The callback function takes one parameter:
• dr - updated datarate

Parameters
• dr_cb – Pointer to datarate update callback

int lorawan_join(const struct lorawan_join_config *config)
Join the LoRaWAN network.
Join the LoRaWAN network using OTAA or AWB.

Parameters
• config – Configuration to be used

Returns
0 if successful, negative errno code if failure

int lorawan_start(void)
Start the LoRaWAN stack.
This function need to be called before joining the network.

Returns
0 if successful, negative errno code if failure

int lorawan_send(uint8_t port, uint8_t *data, uint8_t len, enum lorawan_message_type type)
Send data to the LoRaWAN network.
Send data to the connected LoRaWAN network.

Parameters
• port – Port to be used for sending data. Must be set if the payload is not empty.
• data – Data buffer to be sent
• len – Length of the buffer to be sent. Maximum length of this buffer is 255 bytes but the actual payload size varies with region and datarate.
• type – Specifies if the message shall be confirmed or unconfirmed. Must be one of lorawan_message_type.

Returns
0 if successful, negative errno code if failure
int lorawan_set_class(enum lorawan_class dev_class)
Set the current device class.

  Change the current device class. This function may be called before or after a network connection has been established.

  **Parameters**
  - dev_class – New device class

  **Returns**
  - 0 if successful, negative errno code if failure

int lorawan_set_conf_msg_tries(uint8_t tries)
Set the number of tries used for transmissions.

  **Parameters**
  - tries – Number of tries to be used

  **Returns**
  - 0 if successful, negative errno code if failure

void lorawan_enable_adr(bool enable)
Enable Adaptive Data Rate (ADR)

  Control whether adaptive data rate (ADR) is enabled. When ADR is enabled, the data rate is treated as a default data rate that will be used if the ADR algorithm has not established a data rate. ADR should normally only be enabled for devices with stable RF conditions (i.e., devices in a mostly static location).

  **Parameters**
  - enable – Enable or Disable adaptive data rate.

int lorawan_set_datarate(enum lorawan_datarate dr)
Set the default data rate.

  Change the default data rate.

  **Parameters**
  - dr – Data rate used for transmissions

  **Returns**
  - 0 if successful, negative errno code if failure

enum lorawan_datarate lorawan_get_min_datarate(void)
Get the minimum possible datarate.

  The minimum possible datarate may change in response to a TxParamSetupReq command from the network server.

  **Returns**
  - Minimum possible data rate

void lorawan_get_payload_sizes(uint8_t *max_next_payload_size, uint8_t *max_payload_size)
Get the current payload sizes.

  Query the current payload sizes. The maximum payload size varies with datarate, while the current payload size can be less due to MAC layer commands which are inserted into uplink packets.

  **Parameters**
  - max_next_payload_size – Maximum payload size for the next transmission
  - max_payload_size – Maximum payload size for this datarate
int lorawan_set_region(enum lorawan_region region)
    Set the region and frequency to be used.

    Control the LoRa region and frequency settings. This should be called before lorawan_start().
    If you only have support for a single region selected via Kconfig, this function does not need to be called at all.

    Parameters
    • region – The region to be selected

    Returns
    0 if successful, negative errno otherwise

struct lorawan_join_otaa
    #include <lorawan.h> LoRaWAN join parameters for over-the-Air activation (OTAA)

    Note that all of the fields use LoRaWAN 1.1 terminology.
    All parameters are optional if a secure element is present in which case the values stored in the secure element will be used instead.

    Public Members

    uint8_t * join_eui
        Join EUI

    uint8_t * nwk_key
        Network Key

    uint8_t * app_key
        Application Key

    uint32_t dev_nonce
        Device Nonce

        Starting with LoRaWAN 1.0.4 the DevNonce must be monotonically increasing for each OTAA join with the same EUI. The DevNonce should be stored in non-volatile memory by the application.

struct lorawan_join_abp
    #include <lorawan.h>

    Public Members

    uint32_t dev_addr
        Device address on the network

    uint8_t * app_skey
        Application session key

    uint8_t * nwk_skey
        Network session key
uint8_t *app_eui
        Application EUI

struct lorawan_join_config
    #include <lorawan.h>

Public Members

uint8_t *dev_eui
        Device EUI. Optional if a secure element is present.

struct lorawan_downlink_cb
    #include <lorawan.h>

Public Members

void (*cb)(uint8_t port, bool data_pending, int16_t rssi, int8_t snr, uint8_t len, const uint8_t *data)
        Callback function to run on downlink data.

Note: Callbacks are run on the system workqueue, and should therefore be as short as possible.

Param port
    Port message was sent on

Param data_pending
    Network server has more downlink packets pending

Param rssi
    Received signal strength in dBm

Param snr
    Signal to Noise ratio in dBm

Param len
    Length of data received, will be 0 for ACKs

Param data
    Data received, will be NULL for ACKs

sys_snodel_t node
        Node for callback list

6.4 USB-C device support

6.4.1 USB-C device stack

The USB-C device stack is a hardware independent interface between a Type-C Port Controller (TCPC) and customer applications. It is a port of the Google ChromeOS Type-C Port Manager (TCPM) stack. It provides the following functionalities:

- Uses the APIs provided by the Type-C Port Controller drivers to interact with the Type-C Port Controller.
• Provides a programming interface that’s used by a customer applications. The APIs is described in include/zephyr/usb_c/usbc.h

Currently the device stack only support implementation of Sink devices.

List of samples for different purposes.

**Implementing a Sink Type-C and Power Delivery USB-C device**

The configuration of a USB-C Device is done in the stack layer and devicetree.

The following devicetree, structures and callbacks need to be defined:

• Devicetree `usb-c-connector` node referencing a TCPC
• Devicetree `vbus` node referencing a VBUS measurement device
• User defined structure that encapsulates application specific data
• Policy callbacks

For example, for the Sample USB-C Sink application:

Each Physical Type-C port is represented in the devicetree by a `usb-c-connector` compatible node:

```
port1: usbc-port@1 {
    compatible = "usb-c-connector";
    reg = <1>;
    tcpc = &ucpd1;
    vbus = &vbus1;
    power-role = "sink";
    sink-pdos = <PDO_FIXED(5000, 100, 0)>;
}
```

VBUS is measured by a device that’s referenced in the devicetree by a `usb-c-vbus-adc` compatible node:

```
vbus1: vbus {
    compatible = "zephyr,usb-c-vbus-adc";
    io-channels = <&adc2 8>;
    output-ohms = <49900>;
    full-ohms = <(330000 + 49900)>;
}
```

A user defined structure is defined and later registered with the subsystem and can be accessed from callback through an API:

```
/**
 * @brief A structure that encapsulates Port data.
 */

static struct port1_data_t {
    /** Sink Capabilities */
    uint32_t snk_caps[DT_PROP_LEN(DT_NODELABEL(port1), sink_pdos)];
    /** Number of Sink Capabilities */
    int snk_cap_cnt;
    /** Source Capabilities */
    uint32_t src_caps[PDO_MAX_DATA_OBJECTS];
    /** Number of Source Capabilities */
    int src_cap_cnt;
    /* Power Supply Ready flag */
    atomic_t ps_ready;
} port1_data = {
    .snk_caps = {DT_FOREACH_PROP_ELEM(DT_NODELABEL(port1), sink_pdos, SINK_PDO)},
    (continues on next page)
These callbacks are used by the subsystem to set or get application specific data:

```c
static int port1_policy_cb_get_snk_cap(const struct device *dev,
                                        uint32_t **pdos,
                                        int *num_pdos)
{
    struct port1_data_t *dpm_data = usbc_get_dpm_data(dev);
    *pdos = dpm_data->snk_caps;
    num_pdos = &dpm_data->snk_cap_cnt;
    return 0;
}

static void port1_policy_cb_set_src_cap(const struct device *dev,
                                         const uint32_t *pdos,
                                         const int num_pdos)
{
    struct port1_data_t *dpm_data;
    int num;
    int i;

    dpm_data = usbc_get_dpm_data(dev);
    num = num_pdos;
    if (num > PDO_MAX_DATA_OBJECTS) {
        num = PDO_MAX_DATA_OBJECTS;
    }
    for (i = 0; i < num; i++) {
        dpm_data->src_caps[i] = *(pdos + i);
    }
    dpm_data->src_cap_cnt = num;
}

static uint32_t port1_policy_cb_get_rdo(const struct device *dev)
{
    struct port1_data_t *dpm_data = usbc_get_dpm_data(dev);
    return build_rdo(dpm_data);
}
```

This callback is used by the subsystem to query if a certain action can be taken:

```c
bool port1_policy_check(const struct device *dev,
                         const enum usbc_policy_check_t policy_check)
{
    switch (policy_check) {
    case CHECK_POWER_ROLE_SWAP:
```
/* Reject power role swaps */
return false;

case CHECK_DATA_ROLE_SWAP_TO_DFP:
 /* Reject data role swap to DFP */
return false;

case CHECK_DATA_ROLE_SWAP_TO_UFP:
 /* Accept data role swap to UFP */
return true;

case CHECK_SNK_AT_DEFAULT_LEVEL:
 /* This device is always at the default power level */
return true;

default:
 /* Reject all other policy checks */
return false;

}

This callback is used by the subsystem to notify the application of an event:

```c
static void port1_notify(const struct device *dev,
                         const enum usbc_policy_notify_t policy_notify)
{
    struct port1_data_t *dpm_data = usbc_get_dpm_data(dev);

    switch (policy_notify) {
    case PROTOCOL_ERROR:
        break;
    case MSG_DISCARDED:
        break;
    case MSG_ACCEPT_RECEIVED:
        break;
    case MSG_REJECTED_RECEIVED:
        break;
    case MSG_NOT_SUPPORTED_RECEIVED:
        break;
    case TRANSITION_PS:
        atomic_set_bit(&dpm_data->ps_ready, 0);
        break;
    case PD_CONNECTED:
        break;
    case NOT_PD_CONNECTED:
        break;
    case POWER_CHANGE_0A0:
        LOG_INF("PWR 0A");
        break;
    case POWER_CHANGE_DEF:
        LOG_INF("PWR DEF");
        break;
    case POWER_CHANGE_1A5:
        LOG_INF("PWR 1A5");
        break;
    case POWER_CHANGE_3A0:
        LOG_INF("PWR 3A0");
        break;
    case DATA_ROLE_IS_UFP:
        break;

    (continues on next page)
Registering the callbacks:

```
/* Register USB-C Callbacks */

/* Register Policy Check callback */
usbc_set_policy_cb_check(usbc_port1, port1_policy_check);
/* Register Policy Notify callback */
usbc_set_policy_cb_notify(usbc_port1, port1_notify);
/* Register Policy Get Sink Capabilities callback */
usbc_set_policy_cb_get_snk_cap(usbc_port1, port1_policy_cb_get_snk_cap);
/* Register Policy Set Source Capabilities callback */
usbc_set_policy_cb_set_src_cap(usbc_port1, port1_policy_cb_set_src_cap);
/* Register Policy Get Request Data Object callback */
usbc_set_policy_cb_get_rdo(usbc_port1, port1_policy_cb_get_rdo);
```

Register the user defined structure:

```
/* Set Application port data object. This object is passed to the policy callback */
port1_data.ps_ready = ATOMIC_INIT(0);
usbc_set_dpm_data(usbc_port1, &port1_data);
```

Start the USB-C subsystem:

```
/* Start the USB-C Subsystem */
usbc_start(usbc_port1);
```

API reference

`group _usbc_device_api`
USB-C Device APIs.

**Defines**

`FIXED_5V_100MA_RDO`

This Request Data Object (RDO) value can be returned from the policy_cb_get_rdo if 5V@100mA with the following options are sufficient for the Sink to operate.

The RDO is configured as follows: Maximum operating current 100mA Operating current 100mA Unchunked Extended Messages Not Supported No USB Suspend Not USB Communications Capable No capability mismatch Don't giveback Object position 1 (5V PDO)
Enums

enum usbc_policy_request_t

Device Policy Manager requests.

Values:

enumerator REQUEST_NOP
    No request

denumerator REQUEST_TC_DISABLED
    Request Type-C layer to transition to Disabled State

denumerator REQUEST_TC_ERROR_RECOVERY
    Request Type-C layer to transition to Error Recovery State

denumerator REQUEST_TC_END
    End of Type-C requests

denumerator REQUEST_PE_DR_SWAP
    Request Policy Engine layer to perform a Data Role Swap

denumerator REQUEST_PE_HARD_RESET_SEND
    Request Policy Engine layer to send a hard reset

denumerator REQUEST_PE_SOFT_RESET_SEND
    Request Policy Engine layer to send a soft reset

denumerator REQUEST_PE_GET_SRC_CAPS
    Request Policy Engine layer to get Source Capabilities from port partner

enum usbc_policy_notify_t

Device Policy Manager notifications.

Values:

enumerator MSG_ACCEPT_RECEIVED
    Power Delivery Accept message was received

denumerator MSG_REJECTED_RECEIVED
    Power Delivery Reject message was received

denumerator MSG_DISCARDED
    Power Delivery discarded the message being transmited

denumerator MSG_NOT_SUPPORTED_RECEIVED
    Power Delivery Not Supported message was received

denumerator DATA_ROLE_IS_UFP
    Data Role has been set to Upstream Facing Port (UFP)
enumerator DATA_ROLE_IS_DFP
    Data Role has been set to Downstream Facing Port (DFP)

enumerator PD_CONNECTED
    A PD Explicit Contract is in place

enumerator NOT_PD_CONNECTED
    No PD Explicit Contract is in place

enumerator TRANSITION_PS
    Transition the Power Supply

enumerator PORT_PARTNER_NOT_RESPONSIVE
    Port partner is not responsive

enumerator PROTOCOL_ERROR
    Protocol Error occurred

enumerator SNK_TRANSITION_TO_DEFAULT
    Transition the Sink to default

enumerator HARD_RESET_RECEIVED
    Hard Reset Received

enumerator POWER_CHANGE_0A0
    Sink SubPower state at 0V

enumerator POWER_CHANGE_DEF
    Sink SubPower state a 5V / 500mA

enumerator POWER_CHANGE_1A5
    Sink SubPower state a 5V / 1.5A

enumerator POWER_CHANGE_3A0
    Sink SubPower state a 5V / 3A

def usbc_policy_check_t
    Device Policy Manager checks.
    Values:

enumerator CHECK_POWER_ROLE_SWAP
    Check if Power Role Swap is allowed

enumerator CHECK_DATA_ROLE_SWAP_TO_DFP
    Check if Data Role Swap to DFP is allowed

enumerator CHECK_DATA_ROLE_SWAP_TO_UFP
    Check if Data Role Swap to UFP is allowed
enumerator CHECK_SNK_AT_DEFAULT_LEVEL
    Check if Sink is at default level

eenum usbc_policy_wait_t
    Device Policy Manager Wait message notifications.
    Values:
    
enumerator WAIT_SINK_REQUEST
        The port partner is unable to meet the sink request at this time
    
enumerator WAIT_POWER_ROLE_SWAP
        The port partner is unable to do a Power Role Swap at this time
    
enumerator WAIT_DATA_ROLE_SWAP
        The port partner is unable to do a Data Role Swap at this time
    
enumerator WAIT_VCONN_SWAP
        The port partner is unable to do a VCONN Swap at this time

Functions

int usbc_start(const struct device *dev)
    Start the USB-C Subsystem.
    Parameters
    • dev – Runtime device structure
    Return values
    0 – on success

int usbc_suspend(const struct device *dev)
    Suspend the USB-C Subsystem.
    Parameters
    • dev – Runtime device structure
    Return values
    0 – on success

int usbc_request(const struct device *dev, const enum usbc_policy_request_t req)
    Make a request of the USB-C Subsystem.
    Parameters
    • dev – Runtime device structure
    • req – request
    Return values
    0 – on success

void usbc_set_dpm_data(const struct device *dev, void *dpm_data)
    Set pointer to Device Policy Manager (DPM) data.
    Parameters
    • dev – Runtime device structure
• dpm_data – pointer to dpm data

void *usbc_get_dpm_data(const struct device *dev)
Get pointer to Device Policy Manager (DPM) data.

Parameters
• dev – Runtime device structure

Return values
• pointer – to dpm data that was set with usbc_set_dpm_data
• NULL – if dpm data was not set

void usbc_set_vconn_control_cb(const struct device *dev, const tcpc_vconn_control_cb_t cb)
Set the callback used to set VCONN control.

Parameters
• dev – Runtime device structure
• cb – VCONN control callback

void usbc_set_policy_cb_check(const struct device *dev, const policy_cb_check_t cb)
Set the callback used to check a policy.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_notify(const struct device *dev, const policy_cb_notify_t cb)
Set the callback used to notify Device Policy Manager of a policy change.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_wait_notify(const struct device *dev, const policy_cb_wait_notify_t cb)
Set the callback used to notify Device Policy Manager of WAIT message reception.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_get_snk_cap(const struct device *dev, const policy_cb_get_snk_cap_t cb)
Set the callback used to get the Sink Capabilities.

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_set_src_cap(const struct device *dev, const policy_cb_set_src_cap_t cb)
Set the callback used to store the received Port Partner’s Source Capabilities.

Parameters
• dev – Runtime device structure
• cb – callback
void usbc_set_policy_cb_get_rdo(const struct device *dev, const policy_cb_get_rdo_t cb)
Set the callback used to get the Request Data Object (RDO)

Parameters
• dev – Runtime device structure
• cb – callback

void usbc_set_policy_cb_is_snk_at_default(const struct device *dev, const policy_cb_is_snk_at_default_t cb)
Set the callback used to check if the sink power supply is at the default level.

Parameters
• dev – Runtime device structure
• cb – callback
Chapter 7

Hardware Support

7.1 Architecture-related Guides

7.1.1 Zephyr support status on ARC processors

Overview

This page describes current state of Zephyr for ARC processors and some future plans. Please note that

- plans are given without exact deadlines
- software features require corresponding hardware to be present and configured the proper way
- not all the features can be enabled at the same time

Support status

Legend: Y - yes, supported; N - no, not supported; WIP - Work In Progress; TBD - to be decided
<table>
<thead>
<tr>
<th>Processor families</th>
<th>EM</th>
<th>HS3x/4x</th>
<th>EV</th>
<th>HS5x</th>
<th>HS6x</th>
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<tr>
<td>Port status</td>
<td>up-streamed</td>
<td>up-streamed</td>
<td>WIP</td>
<td>up-streamed</td>
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<tr>
<td>Features</td>
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</tr>
<tr>
<td>Closely coupled memories (ICCM, DCCM)</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>TBD</td>
<td>TBD</td>
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<tr>
<td>Execution with caches - Instruction/Data, L1/L2 caches</td>
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<td>Y</td>
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<td>Hardware-assisted unaligned memory access</td>
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<td>TBD</td>
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<td>Regular interrupts with multiple priority levels, direct interrupts</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>Fast interrupts, separate register banks for fast interrupts</td>
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<td>Y</td>
<td>TBD</td>
<td>N</td>
<td>N</td>
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<td>Hardware floating point unit (FPU)</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>TBD</td>
<td>TBD</td>
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<td>Symmetric multiprocessing (SMP) support, switch-based</td>
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<td>Y</td>
<td>TBD</td>
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<td>Hardware-assisted stack checking</td>
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<td>TBD</td>
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<td>Hardware-assisted atomic operations</td>
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<td>Y</td>
<td>TBD</td>
<td>Y</td>
<td>Y</td>
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<tr>
<td>DSP ISA</td>
<td>Y</td>
<td>N</td>
<td>TBD</td>
<td>TBD</td>
<td>TBD</td>
</tr>
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<td>DSP AGU/XY extensions</td>
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<td>TBD</td>
<td>TBD</td>
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<td>TBD</td>
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<td>Memory protection unit (MPU)</td>
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<td>TBD</td>
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<td>Memory management unit (MMU)</td>
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<td>N/A</td>
<td>N/A</td>
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<td>Single-thread kernel support</td>
<td>Y</td>
<td>Y</td>
<td>TBD</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>

**Toolchains**

| GNU (open source GCC-based) | Y | Y | N | Y | Y |
| MetaWare (proprietary Clang-based) | Y | Y | Y | Y | Y |

**Simulators**

| QEMU (open source) | Y | Y | N | Y | Y |
| nSIM (proprietary, provided by MetaWare Development Tools) | Y | Y | Y | Y | Y |

**Notes**

### 7.1.2 Arm Cortex-M Developer Guide

**Overview**

This page contains detailed information about the status of the Arm Cortex-M architecture porting in the Zephyr RTOS and describes key aspects when developing Zephyr applications for Arm Cortex-M-based platforms.

**Key supported features**

The table below summarizes the status of key OS features in the different Arm Cortex-M implementation variants.

---

1. usage of CCMs is limited on SMP systems
2. except the systems with secure features (SecureShield) due to HW limitation
3. We only support save/restore ACCL/ACCH registers in task’s context. Rest of DSP/AGU registers save/restore isn’t implemented but kernel itself does not use these registers. This allows single task per core to use DSP/AGU safely.
4. Single-thread kernel is support only for single core targets
5. QEMU doesn’t support all the ARC processor’s HW features. For the detailed info please check the ARC QEMU documentation

---
<table>
<thead>
<tr>
<th>Processor families</th>
<th>Arm v6-M</th>
<th>Arm v7-M</th>
<th>Arm v8-M</th>
<th>Arm v8.1-M</th>
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<td>Programmable fault IRQ priorities</td>
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<td>Single-thread kernel support</td>
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<td>HW-assisted null-pointer dereference detection</td>
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<td>Support for non-cacheable regions</td>
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<td>Execute SRAM functions</td>
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<td>SW-based vector table relaying</td>
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<tr>
<td>HW-assisted timing functions</td>
<td>N</td>
<td>N</td>
<td>Y</td>
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</tr>
</tbody>
</table>

Notes

1 SysTick is optional in Cortex-M1
2 Stack limit checking only in Secure builds in Cortex-M23
OS features

Threads

Thread stack alignment Each Zephyr thread is defined with its own stack memory. By default, Cortex-M enforces a double word thread stack alignment, see CONFIG_STACK_ALIGN_DOUBLE_WORD. If MPU-based HW-assisted stack overflow detection (CONFIG_MPU_STACK_GUARD) is enabled, thread stacks need to be aligned with a larger value, reflected by CONFIG_ARM_MPU_REGION_MIN_ALIGN_AND_SIZE. In Arm v6-M and Arm v7-M architecture variants, thread stacks are additionally required to be align with a value equal to their size, in applications that need to support user mode (CONFIG_USERSPACE). The thread stack sizes in that case need to be a power of two. This is all reflected by CONFIG_MPU.Requires.Power_of_Two.Alignment, that is enforced in Arm v6-M and Arm v7-M builds with user mode support.

Stack pointers While executing in thread mode the processor is using the Process Stack Pointer (PSP). The processor uses the Main Stack Pointer (MSP) while executing in handler mode, that is, while servicing exceptions and HW interrupts. Using PSP in thread mode facilitates thread stack pointer manipulation during thread context switching, without affecting the current execution context flow in handler mode.

In Arm Cortex-M builds a single interrupt stack memory is shared among exceptions and interrupts. The size of the interrupt stack needs to be selected taking into consideration nested interrupts, each pushing an additional stack frame. Developers can modify the interrupt stack size using CONFIG_ISR_STACK_SIZE.

The interrupt stack is also used during early boot so the kernel can initialize the main thread's stack before switching to the main thread.

Thread context switching In Arm Cortex-M builds, the PendSV exception is used in order to trigger a context switch to a different thread. PendSV exception is always present in Cortex-M implementations. PendSV is configured with the lowest possible interrupt priority level, in all Cortex-M variants. The main reasons for that design are

• to utilize the tail chaining feature of Cortex-M processors, and thus limit the number of context switch operations that occur.
• to not impact the interrupt latency observed by HW interrupts.

As a result, context switch in Cortex-M is non-atomic, i.e. it may be preempted by HW interrupts, however, a context-switch operation must be completed before a new thread context-switch may start.

Typically a thread context-switch will perform the following operations

• When switching-out the current thread, the processor stores
  – the callee-saved registers (R4 - R11) in the thread’s container for callee-saved registers, which is located in kernel memory
  – the thread’s current operation mode
    * user or privileged execution mode
    * presence of an active floating point context
    * the EXC_RETURN value of the current handler context (PendSV)
  – the floating point callee-saved registers (S16 - S31) in the thread’s container for FP callee-saved registers, if the current thread has an active FP context
  – the PSP of the current thread which points to the beginning of the current thread’s exception stack frame. The latter contains the caller-saved context and the return address of the switched-out thread.

• When switching-in a new thread the processor
- restores the new thread’s callee-saved registers from the thread’s container for callee-saved registers
- restores the new thread’s operation mode
- restores the FP callee-saved registers if the switched-in thread had an active FP context before being switched-out
- reprograms the dynamic MPU regions to allow a user thread access its stack and application memories, and/or programs a stack-overflow MPU guard at the bottom of the thread’s privileged stack
- restores the PSP for the incoming thread and reprograms the stack pointer limit register (if applicable, see CONFIG_BUILTIN_STACK_GUARD)
- optionally does a stack limit checking for the switched-in thread, if sentinel-based stack limit checking is enabled (see CONFIG_STACK_SENTINEL).

PendSV exception return sequence restores the new thread’s caller-saved registers and the return address, as part of unstacking the exception stack frame.

The implementation of the context-switch mechanism is present in arch/arm/core/aarch32/swap_helper.S.

Stack limit checking (Arm v8-M) Armv8-M and Armv8.1-M variants support stack limit checking using the MSPLIM and PSPLIM core registers. The feature is enabled when CONFIG_BUILTIN_STACK_GUARD is set. When stack limit checking is enabled, both the thread’s privileged or user stack, as well as the interrupt stack are guarded by PSPLIM and MSPLIM registers, respectively. MSPLIM is configured once during kernel boot, while PSLIM is re-programmed during every thread context-switch or during system calls, when the thread switches from using its default stack to using its privileged stack, and vice versa. PSPLIM re-programming
- has a relatively low runtime overhead (programming is done with MSR instructions)
- does not impact interrupt latency
- does not require any memory areas to be reserved for stack guards
- does not make use of MPU regions

It is, therefore, considered as a lightweight but very efficient stack overflow detection mechanism in Cortex-M applications.

Stack overflows trigger the dedicated UsageFault exception provided by Arm v8-M.

Interrupt handling features This section describes certain aspects around exception and interrupt handling in Arm Cortex-M.

Interrupt priority levels The number of available (configurable) interrupt priority levels is determined by the number of implemented interrupt priority bits in NVIC; this needs to be described for each Cortex-M platform using DeviceTree:

```
&nvic {
    arm,num-irq-priority-bits = <#priority-bits>;
};
```

Reserved priority levels A number of interrupt priority levels are reserved for the OS.

By design, system fault exceptions have the highest priority level. In Baseline Cortex-M, this is actually enforced by hardware, as HardFault is the only available processor fault exception, and its priority is higher than any configurable exception priority.
In Mainline Cortex-M, the available fault exceptions (e.g. MemManageFault, UsageFault, etc.) are assigned the highest configurable priority level. (CONFIG_CPU_CORTEX_M_HAS_PROGRAMMABLE_FAULT_PRIOS signifies explicitly that the Cortex-M implementation supports configurable fault priorities.)

This priority level is never shared with HW interrupts (an exception to this rule is described below). As a result, processor faults occurring in regular ISRs will be handled by the corresponding fault handler and will not escalate to a HardFault, similar to processor faults occurring in thread mode.

SVC exception is normally configured with the highest configurable priority level (an exception to this rule will be described below). SVCs are used by the Zephyr kernel to dispatch system calls, trigger runtime system errors (e.g. Kernel oops or panic), or implement IRQ offloading.

In Baseline Cortex-M the priority level of SVC may be shared with other exceptions or HW interrupts that are also given the highest configurable priority level (As a result of this, kernel runtime errors during interrupt handling will escalate to HardFault. Additional logic in the fault handling routines ensures that such runtime errors are detected successfully).

In Mainline Cortex-M, however, the SVC priority level is reserved, thus normally it is only shared with the fault exceptions of configurable priority. This simplifies the fault handling routines in Mainline Cortex-M architecture, since runtime kernel errors are serviced by the SVC handler (i.e no HardFault escalation, even if the kernel errors occur in ISR context).

HW interrupts in Mainline Cortex-M builds are allocated a priority level lower than the SVC.

One exception to the above rules is when Zephyr applications support Zero Latency Interrupts (ZLIs). Such interrupts are designed to have a priority level higher than any HW or system interrupt. If the ZLI feature is enabled in Mainline Cortex-M builds (see CONFIG_ZERO_LATENCY_IRQS), then

- ZLIs are assigned the highest configurable priority level
- SVCs are assigned the second highest configurable priority level
- Regular HW interrupts are assigned priority levels lower than SVC.

The priority level configuration in Cortex-M is implemented in include/arch/arm/aarch32/exc.h.

**Locking and unlocking IRQs**

In Baseline Cortex-M locking interrupts is implemented using the PRIMASK register.

`arch_irq_lock()`

will set the PRIMASK register to 1, eventually, masking all IRQs with configurable priority. While this fulfils the OS requirement of locking interrupts, the consequence is that kernel runtime errors (triggering SVCs) will escalate to HardFault.

In Mainline Cortex-M locking interrupts is implemented using the BASEPRI register (Mainline Cortex-M builds select CONFIG_CPU_CORTEX_M_HAS_BASEPRI to signify that BASEPRI register is implemented.). By modifying BASEPRI (or BASEPRI_MAX) `arch_irq_lock()` masks all system and HW interrupts with the exception of

- SVCs
- processor faults
- ZLIs

This allows zero latency interrupts to be triggered inside OS critical sections. Additionally, this allows system (processor and kernel) faults to be handled by Zephyr in exactly the same way, regardless of whether IRQs have been locked or not when the error occurs. It also allows for system calls to be dispatched while IRQs are locked.

**Note:** Mainline Cortex-M fault handling is designed and configured in a way that all processor and kernel faults are handled by the corresponding exception handlers and never result in HardFault escalation. In other words, a HardFault may only occur in Zephyr applications that have modified the default
fault handling configurations. The main reason for this design was to reserve the HardFault exception for handling exceptional error conditions in safety critical applications.

**Dynamic direct interrupts**  
Cortex-M builds support the installation of direct interrupt service routines during runtime. Direct interrupts are designed for performance-critical interrupt handling and do not go through all of the common Zephyr interrupt handling code.

Direct dynamic interrupts are enabled via switching on `CONFIG_DYNAMIC_DIRECT_INTERRUPTS`.

Note that enabling direct dynamic interrupts requires enabling support for dynamic interrupts in the kernel, as well (see `CONFIG_DYNAMIC_INTERRUPTS`).

**Zero Latency interrupts**  
As described above, in Mainline Cortex-M applications, the Zephyr kernel reserves the highest configurable interrupt priority level for its own use (SVC). SVCs will not be masked by interrupt locking. Zero-latency interrupt can be used to set up an interrupt at the highest interrupt priority which will not be blocked by interrupt locking. To use the ZLI feature `CONFIG_ZERO_LATENCY_IRQS` needs to be enabled.

Zero latency IRQs have minimal interrupt latency, as they will always preempt regular HW or system interrupts.

Note, however, that since ZLI ISRs will run at a priority level higher than the kernel exceptions they cannot use any kernel functionality. Additionally, since the ZLI interrupt priority level is equal to processor fault priority level, faults occurring in ZLI ISRs will escalate to HardFault and will not be handled in the same way as regular processor faults. Developers need to be aware of this limitation.

**CPU Idling**  
The Cortex-M architecture port implements both `k_cpu_idle()` and `k_cpu_atomic_idle()`. The implementation is present in `arch/arm/core/aarch32/cpu_idle.S`.

In both implementations, the processor will attempt to put the core to low power mode. In `k_cpu_idle()` the processor ends up executing WFI (Wait For Interrupt) instruction, while in `k_cpu_atomic_idle()` the processor will execute a WFE (Wait For Event) instruction.

When using the CPU idling API in Cortex-M it is important to note the following:

- Both `k_cpu_idle()` and `k_cpu_atomic_idle()` are assumed to be invoked with interrupts locked. This is taken care of by the kernel if the APIs are called by the idle thread.
- After waking up from low power mode, both functions will restore interrupts unconditionally, that is, regardless of the interrupt lock status before the CPU idle API was called.

The Zephyr CPU Idling mechanism is detailed in [CPU Idling](#).

**Memory protection features**  
This section describes certain aspects around memory protection features in Arm Cortex-M applications.

**User mode system calls**  
User mode is supported in Cortex-M platforms that implement the standard (Arm) MPU or a similar core peripheral logic for memory access policy configuration and control, such as the NXP MPU for Kinetis platforms. (Currently, `CONFIG_ARCH_HAS_USERSPACE` is selected if `CONFIG_ARM_MPU` is enabled by the user in the board default kconfig settings).

A thread performs a system call by triggering a (synchronous) SVC exception, where

- up to 5 arguments are placed on registers R1 - R5
- system call ID is placed on register R6.

The SVC Handler will branch to the system call preparation logic, which will perform the following operations.
• switch the thread's PSP to point to the beginning of the thread's privileged stack area, optionally reprogramming the PSPLIM if stack limit checking is enabled
• modify CONTROL register to switch to privileged mode
• modify the return address in the SVC exception stack frame, so that after exception return the system call dispatcher is executed (in thread privileged mode)

Once the system call execution is completed the system call dispatcher will restore the user's original PSP and PSPLIM and switch the CONTROL register back to unprivileged mode before returning back to the caller of the system call.

System calls execute in thread mode and can be preempted by interrupts at any time. A thread may also be context-switched-out while doing a system call; the system call will resume as soon as the thread is switched-in again.

The system call dispatcher executes at SVC priority, therefore it cannot be preempted by HW interrupts (with the exception of ZLIs), which may observe some additional interrupt latency if they occur during a system call preparation.

**MPU-assisted stack overflow detection** Cortex-M platforms with MPU may enable `CONFIG_MPU_STACK_GUARD` to enable the MPU-based stack overflow detection mechanism. The following points need to be considered when enabling the MPU stack guards

• stack overflows are triggering processor faults as soon as they occur
• the mechanism is essential for detecting stack overflows in supervisor threads, or user threads in privileged mode; stack overflows in threads in user mode will always be detected regardless of `CONFIG_MPU_STACK_GUARD` being set.
• stack overflows are always detected, however, the mechanism does not guarantee that no memory corruption occurs when supervisor threads overflow their stack memory
• `CONFIG_MPU_STACK_GUARD` will normally reserve one MPU region for programming the stack guard (in certain Arm v8-M configurations with `CONFIG_MPU_GAP_FILLING` enabled 2 MPU regions are required to implement the guard feature)
• MPU guards are re-programmed at every context-switch, adding a small overhead to the thread swap routine. Compared, however, to the `CONFIG_BUILTIN_STACK_GUARD` feature, no re-programming occurs during system calls.
• When `CONFIG_HW_STACK_PROTECTION` is enabled on Arm v8-M platforms the native stack limit checking mechanism is used by default instead of the MPU-based stack overflow detection mechanism; users may override this setting by manually enabling `CONFIG_MPU_STACK_GUARD` in these scenarios.

**Memory map and MPU considerations**

**Fixed MPU regions** By default, when `CONFIG_ARM_MPU` is enabled a set of fixed MPU regions are programmed during system boot.

• One MPU region programs the entire flash area as read-execute. User can override this setting by enabling `CONFIG_MPU_ALLOW_FLASH_WRITE`, which programs the flash with RWX permissions. If `CONFIG_USERSPACE` is enabled unprivileged access on the entire flash area is allowed.
• One MPU region programs the entire SRAM area with privileged-only RW permissions. That is, an MPU region is utilized to disallow execute permissions on SRAM. (An exception to this setting is when `CONFIG_MPU_GAP_FILLING` is disabled (Arm v8-M only); in that case no SRAM MPU programming is done so the access is determined by the default Arm memory map policies, allowing for privileged-only RWX permissions on SRAM).
• All the memory regions defined in the devicetree with the compatible zephyr,memory-region and at least the property zephyr,memory-region-mpu defining the MPU permissions for the memory region. See the next section for more details.

The above MPU regions are defined in soc/arm/common/cortex_m/arm_mpu_regions.c. Alternative MPU configurations are allowed by enabling CONFIG_CPU_HAS_CUSTOM_FIXED_SOC_MPU_REGIONS. When enabled, this option signifies that the Cortex-M SoC will define and configure its own fixed MPU regions in the SoC definition.

**Fixed MPU regions defined in devicetree**  The user can define memory regions to be allocated and created in the linker script using nodes with the zephyr,memory-region devicetree compatible. When the property zephyr,memory-region-mpu is present in such a node, a new MPU region will be allocated and programmed during system boot.

The property zephyr,memory-region-mpu is a string carrying the attributes for the MPU region. It is converted to a C token for use defining the attributes of the MPU region.

For example, to define a new non-cacheable memory region in devicetree:

```c
sram_no_cache: memory@20300000 {
    compatible = "zephyr,memory-region", "mmio-sram";
    reg = <0x20300000 0x100000>;
    zephyr,memory-region = "SRAM_NO_CACHE";
    zephyr,memory-region-mpu = "RAM_NOCACHE";
};
```

This will automatically create a new MPU entry in soc/arm/common/cortex_m/arm_mpu_regions.c with the correct name, base, size and attributes gathered directly from the devicetree. See include/zephyr/linker/devicetree_regions.h for more details.

**Static MPU regions** Additional static MPU regions may be programmed once during system boot. These regions are required to enable certain features:

- a RX region to allow execution from SRAM, when CONFIG_ARCH_HAS_RAMFUNC_SUPPORT is enabled and users have defined functions to execute from SRAM.
- a RX region for relocating text sections to SRAM, when CONFIG_CODE_DATA_RELOCATION_SRAM is enabled
- a no-cache region to allow for a none-cacheable SRAM area, when CONFIG_NOCACHE_MEMORY is enabled
- a possibly unprivileged RW region for GCOV code coverage accounting area, when CONFIG_COVERAGE_GCOV is enabled
- a no-access region to implement null pointer dereference detection, when CONFIG_NULL_POINTER_EXCEPTION_DETECTION_MPU is enabled

The boundaries of these static MPU regions are derived from symbols exposed by the linker, in include/linker/linker-defs.h.

**Dynamic MPU regions** Certain thread-specific MPU regions may be re-programmed dynamically, at each thread context switch:

- an unprivileged RW region for the current thread's stack area (for user threads)
- a read-only region for the MPU stack guard
- unprivileged RW regions for the partitions of the current thread's application memory domain.
Considerations  The number of available MPU regions for a Cortex-M platform is a limited resource. Most platforms have 8 MPU regions, while some Cortex-M33 or Cortex-M7 platforms may have up to 16 MPU regions. Therefore there is a relatively strict limitation on how many fixed, static and dynamic MPU regions may be programmed simultaneously. For platforms with 8 available MPU regions it might not be possible to enable all the aforementioned features that require MPU region programming. In most practical applications, however, only a certain set of features is required and 8 MPU regions are, in many cases, sufficient.

In Arm v8-M processors the MPU architecture does not allow programmed MPU regions to overlap. `CONFIG_MPU_GAP_FILLING` controls whether the fixed MPU region covering the entire SRAM is programmed. When it does, a full SRAM area partitioning is required, in order to program the static and the dynamic MPU regions. This increases the total number of required MPU regions. When `CONFIG_MPU_GAP_FILLING` is not enabled the fixed MPU region covering the entire SRAM is not programmed, thus, the static and dynamic regions are simply programmed on top of the always-existing background region (full-SRAM partitioning is not required). Note, however, that the background SRAM region allows execution from SRAM, so when `CONFIG_MPU_GAP_FILLING` is not set Zephyr is not protected against attacks that attempt to execute malicious code from SRAM.

Floating point Services  Both unshared and shared FP registers mode are supported in Cortex-M (see Floating Point Services for more details).

When FPU support is enabled in the build (`CONFIG_FPU` is enabled), the sharing FP registers mode (`CONFIG_FPU_SHARING`) is enabled by default. This is done as some compiler configurations may activate a floating point context by generating FP instructions for any thread, regardless of whether floating point calculations are performed, and that context must be preserved when switching such threads in and out.

The developers can still disable the FP sharing mode in their application projects, and switch to Unshared FP registers mode, if it is guaranteed that the image code does not generate FP instructions outside the single thread context that is allowed (and supposed) to do so.

Under FPU sharing mode, the callee-saved FPU registers are saved and restored in context-switch, if the corresponding threads have an active FP context. This adds some runtime overhead on the swap routine. In addition to the runtime overhead, the sharing FPU mode

- requires additional memory for each thread to save the callee-saved FP registers
- requires additional stack memory for each thread, to stack the caller-saved FP registers, upon exception entry, if an FP context is active. Note, however, that since lazy stacking is enabled, there is no runtime overhead of FP context stacking in regular interrupts (FP state preservation is only activated in the swap routine in PendSV interrupt).

Misc

Chain-loadable images  Cortex-M applications may either be standalone images or chain-loadable, for instance, by a bootloader. Application images chain-loadable by bootloaders (or other applications) normally occupy a specific area in the flash denoted as their code partition. `CONFIG_USE_DT_CODE_PARTITION` will ensure that a Zephyr chain-loadable image will be linked into its code partition, specified in Device-Tree.

HW initialization at boot  In order to boot properly, chain-loaded applications may require that the core Arm hardware registers and peripherals are initialized in their reset values. Enabling `CONFIG_INIT_ARCH_HW_AT_BOOT` Zephyr to force the initialization of the internal Cortex-M architectural state during boot to the reset values as specified by the corresponding Arm architecture manual.

Software vector relaying  In Cortex-M platforms that implement the VTOR register (see `CONFIG_CPU_CORTEX_M_HAS_VTOR`), chain-loadable images relocate the Cortex-M vector table by updating the VTOR register with the offset of the image vector table.
Baseline Cortex-M platforms without VTOR register might not be able to relocate their vector table which remains at a fixed location. Therefore, a chain-loadable image will require an alternative way to route HW interrupts and system exceptions to its own vector table; this is achieved with software vector relaying.

When a bootloader image enables CONFIG_SW_VECTOR_RELAY it is able to relay exceptions and interrupts based on a vector table pointer that is set by the chain-loadable application. The latter sets the CONFIG_SW_VECTOR_RELAY_CLIENT option to instruct the boot sequence to set the vector table pointer in SRAM so that the bootloader can forward the exceptions and interrupts to the chain-loadable image's software vector table.

While this feature is intended for processors without VTOR register, it may also be used in Mainline Cortex-M platforms.

**Code relocation** Cortex-M support the code relocation feature. When CONFIG_CODE_DATA_RELOCATION_SRAM is selected, Zephyr will relocate .text, data and .bss sections from the specified files and place it in SRAM. It is possible to relocate only parts of the code sections into SRAM, without relocating the whole image text and data sections. More details on the code relocation feature can be found in *Code And Data Relocation*.

**Linking Cortex-M applications**

Most Cortex-M platforms make use of the default Cortex-M GCC linker script in include/arch/arm/aarch32/cortex-m/scripts/linked.ld, although it is possible for platforms to use a custom linker script as well.

**CMSIS**

Cortex-M CMSIS headers are hosted in a standalone module repository: `zephyrproject-rtos/cmsis`. CONFIG_CPU_CORTEX_M selects CONFIG_HAS_CMSIS_CORE to signify that CMSIS headers are available for all supported Cortex-M variants.

**Testing**

A list of unit tests for the Cortex-M porting and miscellaneous features is present in tests/arch/arm/. The tests suites are continuously extended and new test suites are added, in an effort to increase the coverage of the Cortex-M architecture support in Zephyr.

**QEMU**

We use QEMU to verify the implemented features of the Cortex-M architecture port in Zephyr. Adequate coverage is achieved by defining and utilizing a list of QEMU targets, each with a specific architecture variant and Arm peripheral support list.

The table below lists the QEMU platform targets defined in Zephyr along with the corresponding Cortex-M implementation variant and the peripherals these targets emulate.
### Maintainers & Collaborators

The status of the Arm Cortex-M architecture port in Zephyr is: maintained. The updated list of maintainers and collaborators for Cortex-M can be found in MAINTAINERS.yml.

### 7.1.3 Zephyr support status on RISC-V processors

#### Overview

This page describes current state of Zephyr for RISC-V processors. Currently, there's support for some boards, as well as Qemu support and support for some FPGA implementations such as neorv32 and litex_vexriscv.

Zephyr support includes PMP, user mode, several ISA extensions as well as semihosting.

#### User mode and PMP support

When the platform has Physical Memory Protection (PMP) support, enabling it on Zephyr allows user space support and stack protection to be selected.

#### ISA extensions

It's possible to set in Zephyr which ISA extensions (RV32/64I(E)MAFD(G)QC) are available on a given platform, by setting the appropriate RISCV_ISA_* kconfig. Look at `arch/riscv/Kconfig.isa` for more information.

Note that Zephyr SDK toolchain support may not be defined for all combinations.

#### SMP support

SMP is supported on RISC-V, but currently only on Qemu platforms. In order to test the SMP support, one can use `qemu_riscv32_smp` or `qemu_riscv64_smp` boards.

### 7.1.4 Semihosting Guide

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2056 Chapter 7. Hardware Support
Overview

Semihosting is a mechanism that enables code running on ARM and RISC-V targets to communicate and use the Input/Output facilities on a host computer that is running a debugger or emulator.

More complete documentation on the available functionality is available at the ARM Github documentation.

The RISC-V functionality borrows from the ARM definitions, as described at the RISC-V Github documentation.

File Operations

Semihosting enables files on the host computer to be opened, read, and modified by an application. This can be useful when attempting to validate the behaviour of code across datasets that are larger than what can fit into ROM of an emulated platform. File paths can be either absolute, or relative to the directory of the running process.

```c
const char *path = "./data.bin";
long file_len, bytes_read, fd;
uint8_t buffer[16];

/* Open the data file for reading */
fd = semihost_open(path, SEMIHOST_OPEN_RB);
if (fd < 0) {
    return -ENOENT;
}
/* Read all data from the file */
file_len = semihost_flen(fd);
while(file_len > 0) {
    bytes_read = semihost_read(fd, buffer, MIN(file_len, sizeof(buffer)));
    if (bytes_read < 0) {
        break;
    }
    /* Process read data */
    do_data_processing(buffer, bytes_read);
    /* Update remaining length */
    file_len -= bytes_read;
}
/* Close the file */
semihost_close(fd);
```

7.1.5 Additional Functionality

Additional functionality is available by running semihosting instructions directly with `semihost_exec()` with one of the instructions defined in `semihost_instr`. For complete documentation on the required arguments and return codes, see the ARM Github documentation.

API Reference

```
group semihost

 Enums
```
enum semihost_instr
Semihosting instructions.

Values:

enumerator SEMIHOST_OPEN = 0x01
    Open a file or stream on the host system.

enumerator SEMIHOST_ISTTY = 0x09
    Check whether a file is associated with a stream/terminal

enumerator SEMIHOST_WRITE = 0x05
    Write to a file or stream.

enumerator SEMIHOST_READ = 0x06
    Read from a file at the current cursor position.

enumerator SEMIHOST_CLOSE = 0x02
    Closes a file on the host which has been opened by SEMIHOST_OPEN.

enumerator SEMIHOST_FLEN = 0x0C
    Get the length of a file.

enumerator SEMIHOST_SEEK = 0x0A
    Set the file cursor to a given position in a file.

enumerator SEMIHOST_TMPNAM = 0x0D
    Get a temporary absolute file path to create a temporary file.

enumerator SEMIHOST_REMOVE = 0x0E
    Remove a file on the host system. Possibly insecure!

enumerator SEMIHOST_RENAME = 0x0F
    Rename a file on the host system. Possibly insecure!

enumerator SEMIHOST_WRITEC = 0x03
    Write one character to the debug terminal.

enumerator SEMIHOST_WRITE0 = 0x04
    Write a NULL terminated string to the debug terminal.

enumerator SEMIHOST_READC = 0x07
    Read one character from the debug terminal.

enumerator SEMIHOST_CLOCK = 0x10

enumerator SEMIHOST_ELAPSED = 0x30

enumerator SEMIHOST_TICKFREQ = 0x31
enumerator SEMIHOST_TIME = 0x11

text

text

text

enumerator SEMIHOST_ERRNO = 0x13

- Retrieve the errno variable from semihosting operations.

text

text

text

enumerator SEMIHOST_GET_CMDLINE = 0x15

- Get commandline parameters for the application to run with

text

text

text

text

text

enumerator SEMIHOST_HEAPINFO = 0x16

enumerator SEMIHOST_ISERROR = 0x08

enumerator SEMIHOST_SYSTEM = 0x12

enum semihost_open_mode

- Modes to open a file with.

Behaviour corresponds to equivalent fopen strings. i.e. SEMIHOST.OPEN_RB_PLUS == "rb+"

Values:

enumerator SEMIHOST_OPEN_R = 0

enumerator SEMIHOST_OPEN_RB = 1

enumerator SEMIHOST_OPEN_R_PLUS = 2

enumerator SEMIHOST_OPEN_RB_PLUS = 3

enumerator SEMIHOST_OPEN_W = 4

enumerator SEMIHOST_OPEN_WB = 5

enumerator SEMIHOST_OPEN_W_PLUS = 6

enumerator SEMIHOST_OPEN_WB_PLUS = 7

enumerator SEMIHOST_OPEN_A = 8

enumerator SEMIHOST_OPEN_AB = 9

enumerator SEMIHOST.OPEN.A_PLUS = 10

enumerator SEMIHOST.OPEN_AB_PLUS = 11
Functions

long semihost_exec(enum semihost_instr instr, void *args)
Manually execute a semihosting instruction.

Parameters
• instr – instruction code to run
• args – instruction specific arguments

Returns
integer return code of instruction

char semihost_poll_in(void)
Read a byte from the console.

Returns
char byte read from the console.

void semihost_poll_out(char c)
Write a byte to the console.

Parameters
• c – byte to write to console

long semihost_open(const char *path, long mode)
Open a file on the host system.

Parameters
• path – file path to open. Can be absolute or relative to current directory of the running process.
• mode – value from semihost_open_mode.

Return values
• handle – positive handle on success.
• -1 – on failure.

long semihost_close(long fd)
Close a file.

Parameters
• fd – handle returned by semihost_open.

Return values
• 0 – on success.
• -1 – on failure.

long semihost_flen(long fd)
Query the size of a file.

Parameters
• fd – handle returned by semihost_open.

Return values
• positive – file size on success.
• -1 – on failure.
long semihost.seek(long fd, long offset)
   Seeks to an absolute position in a file.

Parameters
   • fd – handle returned by semihost_open.
   • offset – offset from the start of the file in bytes.

Return values
   • 0 – on success.
   • -errno – negative error code on failure.

long semihost.read(long fd, void *buf, long len)
   Read the contents of a file into a buffer.

Parameters
   • fd – handle returned by semihost_open.
   • buf – buffer to read data into.
   • len – number of bytes to read.

Return values
   • read – number of bytes read on success.
   • -errno – negative error code on failure.

long semihost.write(long fd, const void *buf, long len)
   Write the contents of a buffer into a file.

Parameters
   • fd – handle returned by semihost_open.
   • buf – buffer to write data from.
   • len – number of bytes to write.

Return values
   • 0 – on success.
   • -errno – negative error code on failure.

7.1.6  x86 Developer Guide

Overview

This page contains information on certain aspects when developing for x86-based platforms.

Virtual Memory

During very early boot, page tables are loaded so technically the kernel is executing in virtual address space. By default, physical and virtual memory are identity mapped and thus giving the appearance of execution taking place in physical address space. The physical address space is marked by kconfig CONFIG_SRAM_BASE_ADDRESS and CONFIG_SRAM_SIZE while the virtual address space is marked by CONFIG_KERNEL_VM_BASE and CONFIG_KERNEL_VM_SIZE. Note that CONFIG_SRAM_OFFSET controls where the Zephyr kernel is being placed in the memory, and its counterpart CONFIG_KERNEL_VM_OFFSET.
Separate Virtual Address Space from Physical Address Space  
On 32-bit x86, it is possible to have separate physical and virtual address space. Code and data are linked in virtual address space, but are still loaded in physical memory. However, during boot, code and data must be available and also addressable in physical address space before `vm_enter` inside `arch/x86/core/ia32/crt0.S`. After `vm_enter`, code execution is done via virtual addresses and data can be referred via their virtual addresses. This is possible as the page table generation script (`arch/x86/gen_mmu.py`) identity maps the physical addresses at the page directory level, in addition to mapping virtual addresses to the physical memory. Later in the boot process, the entries for identity mapping at the page directory level are cleared in `z_x86_mmu_init()`, effectively removing the identity mapping of physical memory. This unmapping must be done for userspace isolation or else they would be able to access restricted memory via physical addresses. Since the identity mapping is done at the page directory level, there is no need to allocate additional space for the page table. However, additional space may still be required for additional page directory table.

There are restrictions on where virtual address space can be:

- Physical and virtual address spaces must be disjoint. This is required as the entries in page directory table will be cleared. If they are not disjoint, it would clear the entries needed for virtual addresses.
  - If `CONFIG_X86_PAE` is enabled (=y), each address space must reside in their own 1GB region, due to each entry of PDP (Page Directory Pointer) covers 1GB of memory. For example:
    ```
    * Assuming `CONFIG_SRAM_OFFSET` and `CONFIG_KERNEL_VM_OFFSET` are both 0x0.
    * `CONFIG_SRAM_BASE_ADDRESS == 0x00000000` and `CONFIG_KERNEL_VM_BASE = 0x40000000` is valid, while
    * `CONFIG_SRAM_BASE_ADDRESS == 0x00000000` and `CONFIG_KERNEL_VM_BASE = 0x20000000` is not.
    - If `CONFIG_X86_PAE` is disabled (=n), each address space must reside in their own 4MB region, due to each entry of PD (Page Directory) covers 4MB of memory.
    - Both `CONFIG_SRAM_BASE_ADDRESS` and `CONFIG_KERNEL_VM_BASE` must also align with the starting addresses of targeted regions.

Specifying Additional Memory Mappings at Build Time

The page table generation script (`arch/x86/gen_mmu.py`) generates the necessary multi-level page tables for code execution and data access using the kernel image produced by the first linker pass. Additional command line arguments can be passed to the script to generate additional memory mappings. This is useful for static mappings and/or device MMIO access during very early boot. To pass extra command line arguments to the script, populate a CMake list named `X86_EXTRA_GEN_MMU_ARGUMENTS` in the board configuration file. Here is an example:

```cmake
set(X86_EXTRA_GEN_MMU_ARGUMENTS
    --map 0xA0000000,0x2000
    --map 0x80000000,0x400000,LWUX,0xB0000000)
```

The argument `--map` takes the following value: `<physical address>,<size>[,<flags:LUWX>[,<virtual address>]]`, where:

- `<physical address>` is the physical address of the mapping. (Required)
- `<size>` is the size of the region to be mapped. (Required)
- `<flags>` is the flag associated with the mapping: (Optional)
  - L: Large page at the page directory level.
  - U: Allow userspace access.
  - W: Read/write.
  - X: Allow execution.
- D: Cache disabled.
  * Default is small page (4KB), supervisor only, read only, and execution disabled.
  * <virtual address is the virtual address of the mapping. (Optional)

Note that specifying additional memory mappings requires larger storage space for the pre-allocated page tables (both kernel and per-domain tables). CONFIG_X86_EXTRA_PAGE_TABLE_PAGES is needed to specify how many more memory pages to be reserved for the page tables. If the needed space is not exactly the same as required space, the gen_mmu.py script will print out a message indicating what needs to be the value for the kconfig.

7.2 Peripheral and Hardware Emulators

7.2.1 Overview

Zephyr supports a simple emulator framework to support testing of drivers without requiring real hardware.

Emulators are used to emulate hardware devices, to support testing of various subsystems. For example, it is possible to write an emulator for an I2C compass such that it appears on the I2C bus and can be used just like a real hardware device.

Emulators often implement special features for testing. For example a compass may support returning bogus data if the I2C bus speed is too high, or may return invalid measurements if calibration has not yet been completed. This allows for testing that high-level code can handle these situations correctly. Test coverage can therefore approach 100% if all failure conditions are emulated.

7.2.2 Concept

The diagram below shows application code / high-level tests at the top. This is the ultimate application we want to run.

Below that are peripheral drivers, such as the AT24 EEPROM driver. We can test peripheral drivers using an emulation driver connected via a native_posix I2C controller/emulator which passes I2C traffic from the AT24 driver to the AT24 simulator.

Separately we can test the STM32 and NXP I2C drivers on real hardware using API tests. These require some sort of device attached to the bus, but with this, we can validate much of the driver functionality.

Putting the two together, we can test the application and peripheral code entirely on native_posix. Since we know that the I2C driver on the real hardware works, we should expect the application and peripheral drivers to work on the real hardware also.

Using the above framework we can test an entire application (e.g. Embedded Controller) on native_posix using emulators for all non-chip drivers:

The 'real' code is shown in green. The Zephyr emulation-framework code is shown in yellow. The blue boxes are the extra code we have to write to emulate the peripherals.

With this approach we can:

- Write individual tests for each driver (green), covering all failure modes, error conditions, etc.
- Ensure 100% test coverage for drivers (green)
- Write tests for combinations of drivers, such as GPIOs provided by an I2C GPIO expander driver talking over an I2C bus, with the GPIOs controlling a charger. All of this can work in the emulated environment or on real hardware.
- Write a complex application that ties together all of these pieces and runs on native_posix. We can develop on a host, use source-level debugging, etc.
Chapter 7. Hardware Support
7.2.3 Available emulators

Zephyr includes the following emulators:

- EEPROM, which uses a file as the EEPROM contents
- I2C emulator driver, allowing drivers to be connected to an emulator so that tests can be performed without access to the real hardware
- SPI emulator driver, which does the same for SPI
- eSPI emulator driver, which does the same for eSPI. The emulator is being developed to support more functionalities.
- CAN loopback driver

A GPIO emulator is planned but is not yet complete.

7.2.4 Samples

Here are some examples present in Zephyr:

1. Bosch BMI160 sensor driver connected via both I2C and SPI to an emulator:
   
   ```
   west build -b native_posix tests/drivers/sensor/accel/
   ```

2. Simple test of the EEPROM emulator:
   
   ```
   west build -b native_posix tests/drivers/eeprom
   ```

3. The same test has a second EEPROM which is an Atmel AT24 EEPROM driver connected via I2C an emulator:

   ```
   west build -b native_posix tests/drivers/eeprom
   ```

7.3 Peripherals

7.3.1 ADC

Overview

API Reference

```
group adc_interface
    ADC driver APIs.
```

Defines
ADC_CHANNEL_CFG_DT(node_id)

Get ADC channel configuration from a given devicetree node.

This returns a static initializer for a struct `adc_channel_cfg` filled with data from a given devicetree node.

Example devicetree fragment:

```
kadc {
    #address-cells = <1>;
    #size-cells = <0>;

    channel00 {
        reg = <0>;
        zephyr,gain = "ADC_GAIN_1_6";
        zephyr,reference = "ADC_REF_INTERNAL";
        zephyr,acquisition-time = "ADC_ACQ_TIME(ADC_ACQ_TIME_MICROSECONDS, 20)";
        zephyr,input-positive = <NRF_SAADC_AIN6>;
        zephyr,input-negative = <NRF_SAADC_AIN7>;
    }

    channel01 {
        reg = <1>;
        zephyr,gain = "ADC_GAIN_1_6";
        zephyr,reference = "ADC_REF_INTERNAL";
        zephyr,acquisition-time = "ADC_ACQ_TIME_DEFAULT";
        zephyr,input-positive = <NRF_SAADC_AIN0>;
    }
}
```

Example usage:

```
static const struct adc_channel_cfg ch0_cfg_dt =
    ADC_CHANNEL_CFG_DT(DT_CHILD(DT_NODELABEL(adc), channel_0));
static const struct adc_channel_cfg ch1_cfg_dt =
    ADC_CHANNEL_CFG_DT(DT_CHILD(DT_NODELABEL(adc), channel_1));
```

// Initializes 'ch0_cfg_dt' to:
// {
// .channel_id = 0,
// .gain = ADC_GAIN_1_6,
// .reference = ADC_REF_INTERNAL,
// .acquisition_time = ADC_ACQ_TIME(ADC_ACQ_TIME_MICROSECONDS, 20),
// .differential = true,
// .input_positive = NRF_SAADC_AIN6,
// .input-negative = NRF_SAADC_AIN7,
// }
// and 'ch1_cfg_dt' to:
// {
// .channel_id = 1,
// .gain = ADC_GAIN_1_6,
// .reference = ADC_REF_INTERNAL,
// .acquisition_time = ADC_ACQ_TIME_DEFAULT,
// .input_positive = NRF_SAADC_AIN0,
// }
Parameters

• node_id – Devicetree node identifier.

Returns

Static initializer for an \textit{adc\_channel\_cfg} structure.

\texttt{ADC\_DT\_SPEC\_GET\_BY\_IDX(node\_id, idx)}

Get ADC io-channel information from devicetree.

This returns a static initializer for an \textit{adc\_dt\_spec} structure given a devicetree node and a channel index. The node must have the “io-channels” property defined.

Example devicetree fragment:

\begin{verbatim}
/ {
   zephyr,user {
      io-channels = <&adc0 1>, <&adc0 3>;
   };
};&adc0 {
   #address-cells = <1>;
   #size-cells = <0>;
   channel03 {
      reg = <3>;
      zephyr,gain = "ADC\_GAIN\_1\_5";
      zephyr,reference = "ADC\_REF\_VDD\_1\_4";
      zephyr,vref-mv = <750>;
      zephyr,acquisition-time = <ADC\_ACQ\_TIME\_DEFAULT>;
      zephyr,resolution = <12>;
      zephyr,oversampling = <4>;
   }
};
\end{verbatim}

Example usage:

\begin{verbatim}
static const struct adc\_dt\_spec adc\_chan0 =
   ADC\_DT\_SPEC\_GET\_BY\_IDX(DT\_PATH(zephyr\_user), 0);
static const struct adc\_dt\_spec adc\_chan1 =
   ADC\_DT\_SPEC\_GET\_BY\_IDX(DT\_PATH(zephyr\_user), 1);

// Initializes 'adc\_chan0' to:
//  {
//    .dev = DEVICE\_DT\_GET(DT\_NODELABEL(adc0)),
//    .channel\_id = 1,
//  }
// and 'adc\_chan1' to:
//  {
//    .dev = DEVICE\_DT\_GET(DT\_NODELABEL(adc0)),
//    .channel\_id = 3,
//    .channel\_cfg\_dt\_node\_exists = true,
//    .channel\_cfg = {
//      .channel\_id = 3,
//      .gain = ADC\_GAIN\_1\_5,
//      .reference = ADC\_REF\_VDD\_1\_4,
//    }
\end{verbatim}
// .acquisition_time = ADC_ACQ_TIME_DEFAULT,
// },
// .vref_mv = 750,
// .resolution = 12,
// .oversampling = 4,
// }

See also:

`ADC_DT_SPEC_GET()`

Parameters

- `node_id` – Devicetree node identifier.
- `idx` – Channel index.

Returns

Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_INST_GET_BY_IDX`(inst, idx)

Get ADC io-channel information from a DT_DRV_COMPAT devicetree instance.

See also:

`ADC_DT_SPEC_GET_BY_IDX()`

Parameters

- `inst` – DT_DRV_COMPAT instance number
- `idx` – Channel index.

Returns

Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_GET(node_id)`

Equivalent to `ADC_DT_SPEC_GET_BY_IDX(node_id, 0)`.

See also:

`ADC_DT_SPEC_GET()`

Parameters

- `node_id` – Devicetree node identifier.

Returns

Static initializer for an `adc_dt_spec` structure.

`ADC_DT_SPEC_INST_GET`(inst)

Equivalent to `ADC_DT_SPEC_INST_GET_BY_IDX(inst, 0)`.

See also:

`ADC_DT_SPEC_GET()`
• inst – DT_DRV_COMPAT instance number

Returns
Static initializer for an adc_dt_spec structure.

Typedefs

typedef enum adc_action (*adc_sequence_callback)(const struct device *dev, const struct adc_sequence *sequence, uint16_t sampling_index)
  Type definition of the optional callback function to be called after a requested sampling is done.
  
  Param dev
  Pointer to the device structure for the driver instance.
  
  Param sequence
  Pointer to the sequence structure that triggered the sampling. This parameter points to a copy of the structure that was supplied to the call that started the sampling sequence, thus it cannot be used with the CONTAINER_OF() macro to retrieve some other data associated with the sequence. Instead, the adc_sequence_options::user_data field should be used for such purpose.
  
  Param sampling_index
  Index (0-65535) of the sampling done.
  
  Return
  Action to be performed by the driver. See adc_action.

typedef int (*adc_api_channel_setup)(const struct device *dev, const struct adc_channel_cfg *channel_cfg)
  Type definition of ADC API function for configuring a channel. See adc_channel_setup() for argument descriptions.

typedef int (*adc_api_read)(const struct device *dev, const struct adc_sequence *sequence)
  Type definition of ADC API function for setting a read request. See adc_read() for argument descriptions.

typedef int (*adc_api_read_async)(const struct device *dev, const struct adc_sequence *sequence, struct k_poll_signal *async)
  Type definition of ADC API function for setting an asynchronous read request. See adc_read_async() for argument descriptions.

Enums

enum adc_gain
  ADC channel gain factors.
  
  Values:

  enumerator ADC_GAIN_1_6
      x 1/6.

  enumerator ADC_GAIN_1_5
      x 1/5.
enumerator ADC_GAIN_1_4
  x 1/4.
enumerator ADC_GAIN_1_3
  x 1/3.
enumerator ADC_GAIN_2_5
  x 2/5.
enumerator ADC_GAIN_1_2
  x 1/2.
enumerator ADC_GAIN_2_3
  x 2/3.
enumerator ADC_GAIN_4_5
  x 4/5.
enumerator ADC_GAIN_1
  x 1.
enumerator ADC_GAIN_2
  x 2.
enumerator ADC_GAIN_3
  x 3.
enumerator ADC_GAIN_4
  x 4.
enumerator ADC_GAIN_6
  x 6.
enumerator ADC_GAIN_8
  x 8.
enumerator ADC_GAIN_12
  x 12.
enumerator ADC_GAIN_16
  x 16.
enumerator ADC_GAIN_24
  x 24.
enumerator ADC_GAIN_32
  x 32.
enumerator ADC_GAIN_64
    x 64.

enumerator ADC_GAIN_128
    x 128.

enum adc_reference
    ADC references.
    Values:

enumerator ADC_REF_VDD_1
    VDD.

enumerator ADC_REF_VDD_1_2
    VDD/2.

enumerator ADC_REF_VDD_1_3
    VDD/3.

enumerator ADC_REF_VDD_1_4
    VDD/4.

enumerator ADC_REF_INTERNAL
    Internal.

enumerator ADC_REF_EXTERNAL0
    External, input 0.

enumerator ADC_REF_EXTERNAL1
    External, input 1.

enum adc_action
    Action to be performed after a sampling is done.
    Values:

enumerator ADC_ACTION_CONTINUE = 0
    The sequence should be continued normally.

enumerator ADC_ACTION_REPEAT
    The sampling should be repeated. New samples or sample should be read from the ADC
    and written in the same place as the recent ones.

enumerator ADC_ACTION_FINISH
    The sequence should be finished immediately.

Functions

7.3. Peripherals
int adc_gain_invert(enum adc_gain gain, int32_t *value)
Invert the application of gain to a measurement value.

For example, if the gain passed in is ADC_GAIN_1_6 and the referenced value is 10, the value after the function returns is 60.

Parameters
- **gain** – the gain used to amplify the input signal.
- **value** – a pointer to a value that initially has the effect of the applied gain but has that effect removed when this function successfully returns. If the gain cannot be reversed the value remains unchanged.

Return values
- 0 – if the gain was successfully reversed
- EINVAL – if the gain could not be interpreted

int adc_channel_setup(const struct device *dev, const struct adc_channel_cfg *channel_cfg)
Configure an ADC channel.

It is required to call this function and configure each channel before it is selected for a read request.

Parameters
- **dev** – Pointer to the device structure for the driver instance.
- **channel_cfg** – Channel configuration.

Return values
- 0 – On success.
- EINVAL – If a parameter with an invalid value has been provided.

static inline int adc_channel_setup_dt(const struct adc_dt_spec *spec)
Configure an ADC channel from a struct adc_dt_spec.

See also:
- **adc_channel_setup()**

Parameters
- **spec** – ADC specification from Devicetree.

Returns
A value from adc_channel_setup() or -ENOTSUP if information from Devicetree is not valid.

int adc_read(const struct device *dev, const struct adc_sequence *sequence)
Set a read request.

If invoked from user mode, any sequence struct options for callback must be NULL.

Parameters
- **dev** – Pointer to the device structure for the driver instance.
- **sequence** – Structure specifying requested sequence of samplings.

Return values
- 0 – On success.
-EINVAL – If a parameter with an invalid value has been provided.
-ENOMEM – If the provided buffer is too small to hold the results of all requested samplings.
-ENOTSUP – If the requested mode of operation is not supported.
-EBUSY – If another sampling was triggered while the previous one was still in progress. This may occur only when samplings are done with intervals, and it indicates that the selected interval was too small. All requested samples are written in the buffer, but at least some of them were taken with an extra delay compared to what was scheduled.

```c
int adc_read_async(const struct device *dev, const struct adc_sequence *sequence, struct k_poll_signal *async)
```

Set an asynchronous read request.

If invoked from user mode, any sequence struct options for callback must be NULL.

**Note:** This function is available only if `CONFIG_ADC_ASYNC` is selected.

**Parameters**
- `dev` – Pointer to the device structure for the driver instance.
- `sequence` – Structure specifying requested sequence of samplings.
- `async` – Pointer to a valid and ready to be signaled struct `k_poll_signal`. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).

**Returns**
0 on success, negative error code otherwise. See `adc_read()` for a list of possible error codes.

```c
static inline uint16_t adc_ref_internal(const struct device *dev)
```

Get the internal reference voltage.

**Returns**
Returns the voltage corresponding to `ADC_REF_INTERNAL`, measured in millivolts.

```c
static inline int adc_raw_to_millivolts(int32_t ref_mv, enum adc_gain gain, uint8_t resolution, int32_t *valp)
```

Convert a raw ADC value to millivolts.

This function performs the necessary conversion to transform a raw ADC measurement to a voltage in millivolts.

**Parameters**
- `ref_mv` – the reference voltage used for the measurement, in millivolts. This may be from `adc_ref_internal()` or a known external reference.
- `gain` – the ADC gain configuration used to sample the input
- `resolution` – the number of bits in the absolute value of the sample. For differential sampling this needs to be one less than the resolution in struct `adc_sequence`.
• `valp` – pointer to the raw measurement value on input, and the corresponding millivolt value on successful conversion. If conversion fails the stored value is left unchanged.

**Return values**

• 0 – on successful conversion
• -EINVAL – if the gain is not reversible

static inline int adc_raw_to_millivolts_dt(const struct adc_dt_spec *spec, int32_t *valp)
Convert a raw ADC value to millivolts using information stored in a struct `adc_dt_spec`.

See also:

`adc_raw_to_millivolts()`

**Parameters**

• `spec` – [in] ADC specification from Devicetree.
• `valp` – [inout] Pointer to the raw measurement value on input, and the corresponding millivolt value on successful conversion. If conversion fails the stored value is left unchanged.

**Returns**

A value from `adc_raw_to_millivolts()` or -ENOTSUP if information from Device-tree is not valid.

static inline int adc_sequence_init_dt(const struct adc_dt_spec *spec, struct adc_sequence *seq)
Initialize a struct `adc_sequence` from information stored in struct `adc_dt_spec`.

Note that this function only initializes the following fields:

• `adc_sequence::channels`
• `adc_sequence::resolution`
• `adc_sequence::oversampling`

Other fields should be initialized by the caller.

**Parameters**

• `spec` – [in] ADC specification from Devicetree.
• `seq` – [out] Sequence to initialize.

**Return values**

• 0 – On success
• -ENOTSUP – If `spec` does not have valid channel configuration

```c
struct adc_channel_cfg
    #include <adc.h> Structure for specifying the configuration of an ADC channel.
```

**Public Members**

```c
enum adc_gain gain
    Gain selection.
```
enum adc_reference reference
  Reference selection.

uint16_t acquisition_time
  Acquisition time. Use the ADC_ACQ_TIME macro to compose the value for this field
  or pass ADC_ACQ_TIME_DEFAULT to use the default setting for a given hardware (e.g.
  when the hardware does not allow to configure the acquisition time). Particular drivers
  do not necessarily support all the possible units. Value range is 0-16383 for a given unit.

uint8_t channel_id
  Channel identifier. This value primarily identifies the channel within the ADC API - when
  a read request is done, the corresponding bit in the “channels” field of the “adc_sequence”
  structure must be set to include this channel in the sampling. For hardware that does not
  allow selection of analog inputs for given channels, but rather have dedicated ones, this
  value also selects the physical ADC input to be used in the sampling. Otherwise, when it is
  needed to explicitly select an analog input for the channel, or two inputs when the channel
  is a differential one, the selection is done in “input_positive” and “input_negative” fields.
  Particular drivers indicate which one of the above two cases they support by selecting or
  not a special hidden Kconfig option named ADC_CONFIGURABLE_INPUTS. If this option
  is not selected, the macro CONFIG_ADC_CONFIGURABLE_INPUTS is not defined and
  consequently the mentioned two fields are not present in this structure. While this API
  allows identifiers from range 0-31, particular drivers may support only a limited number
  of channel identifiers (dependent on the underlying hardware capabilities or configured
  via a dedicated Kconfig option).

uint8_t differential
  Channel type: single-ended or differential.

struct adc_dt_spec
  #include <adc.h> Container for ADC channel information specified in devicetree.

  See also:
  ADC_DT_SPEC_GET_BY_IDX

  See also:
  ADC_DT_SPEC_GET

Public Members

const struct device *dev
  Pointer to the device structure for the ADC driver instance used by this io-channel.

uint8_t channel_id
  ADC channel identifier used by this io-channel.

bool channel_cfg_dt_node_exists
  Flag indicating whether configuration of the associated ADC channel is provided as a child
  node of the corresponding ADC controller in devicetree.
struct adc_channel_cfg channel_cfg

Configuration of the associated ADC channel specified in devicetree. This field is valid only when channel_cfg_dt_node_exists is set to true.

uint16_t vref_mv

Voltage of the reference selected for the channel or 0 if this value is not provided in devicetree. This field is valid only when channel_cfg_dt_node_exists is set to true.

uint8_t resolution

ADC resolution to be used for that channel. This field is valid only when channel_cfg_dt_node_exists is set to true.

uint8_t oversampling

Oversampling setting to be used for that channel. This field is valid only when channel_cfg_dt_node_exists is set to true.

struct adc_sequence_options

#include <adc.h> Structure defining additional options for an ADC sampling sequence.

Public Members

uint32_t interval_us

Interval between consecutive samplings (in microseconds), 0 means sample as fast as possible, without involving any timer. The accuracy of this interval is dependent on the implementation of a given driver. The default routine that handles the intervals uses a kernel timer for this purpose, thus, it has the accuracy of the kernel's system clock. Particular drivers may use some dedicated hardware timers and achieve a better precision.

adc_sequence_callback callback

Callback function to be called after each sampling is done. Optional - set to NULL if it is not needed.

void *user_data

Pointer to user data. It can be used to associate the sequence with any other data that is needed in the callback function.

uint16_t extra_samplings

Number of extra samplings to perform (the total number of samplings is 1 + extra_samplings).

struct adc_sequence

#include <adc.h> Structure defining an ADC sampling sequence.

Public Members

const struct adc_sequence_options *options

Pointer to a structure defining additional options for the sequence. If NULL, the sequence consists of a single sampling.
uint32_t channels
   Bit-mask indicating the channels to be included in each sampling of this sequence. All
   selected channels must be configured with `adc_channel_setup()` before they are used in a
   sequence.

void *buffer
   Pointer to a buffer where the samples are to be written. Samples from subsequent sam-
   plings are written sequentially in the buffer. The number of samples written for each
   sampling is determined by the number of channels selected in the “channels” field. The
   buffer must be of an appropriate size, taking into account the number of selected chan-
   nels and the ADC resolution used, as well as the number of samplings contained in the
   sequence.

size_t buffer_size
   Specifies the actual size of the buffer pointed by the “buffer” field (in bytes). The driver
   must ensure that samples are not written beyond the limit and it must return an error if
   the buffer turns out to be not large enough to hold all the requested samples.

uint8_t resolution
   ADC resolution. For single-ended channels the sample values are from range: 0 .. 2^res-
   olution - 1, for differential ones:
   • 2^(resolution-1) .. 2^(resolution-1) - 1.

uint8_t oversampling
   Oversampling setting. Each sample is averaged from 2^oversampling conversion results.
   This feature may be unsupported by a given ADC hardware, or in a specific mode (e.g.
   when sampling multiple channels).

bool calibrate
   Perform calibration before the reading is taken if requested.
   The impact of channel configuration on the calibration process is specific to the underlying
   hardware. ADC implementations that do not support calibration should ignore this flag.

struct adc_driver_api
   #include <adc.h> ADC driver API.
   This is the mandatory API any ADC driver needs to expose.

### 7.3.2 Audio

**Audio Codec**

**Overview** The Audio Codec API provides access to digital audio codecs.

**Configuration Options** Related configuration options:

- `CONFIG_AUDIO_CODEC`

**API Reference**

*group audio_codec_interface*

Abstraction for audio codecs.
Enums

```c
enum audio_pcm_rate_t
    PCM audio sample rates
    Values:

    enumerator AUDIO_PCM_RATE_8K = 8000
    enumerator AUDIO_PCM_RATE_16K = 16000
    enumerator AUDIO_PCM_RATE_24K = 24000
    enumerator AUDIO_PCM_RATE_32K = 32000
    enumerator AUDIO_PCM_RATE_44P1K = 44100
    enumerator AUDIO_PCM_RATE_48K = 48000
    enumerator AUDIO_PCM_RATE_96K = 96000
    enumerator AUDIO_PCM_RATE_192K = 192000

enum audio_pcm_width_t
    PCM audio sample bit widths
    Values:

    enumerator AUDIO_PCM_WIDTH_16_BITS = 16
    enumerator AUDIO_PCM_WIDTH_20_BITS = 20
    enumerator AUDIO_PCM_WIDTH_24_BITS = 24
    enumerator AUDIO_PCM_WIDTH_32_BITS = 32

enum audio_dai_type_t
    Digital Audio Interface (DAI) type
    Values:

    enumerator AUDIO_DAI_TYPE_I2S
    enumerator AUDIO_DAI_TYPE_INVALID

enum audio_property_t
    Codec properties that can be set by `audio_codec_set_property()`
    Values:
```
enumerator AUDIOPROPERTYOUTPUTVOLUME
enumerator AUDIOPROPERTYOUTPUTMUTE

enum audio_channel_t
    Audio channel identifiers to use in audio_codec_set_property()
    Values:
    enumerator AUDIOCHANNELFRONTLEFT
    enumerator AUDIOCHANNELFRONTRIGHT
    enumerator AUDIOCHANNELLFE
    enumerator AUDIOCHANNELFRONTCENTER
    enumerator AUDIOCHANNELREARLEFT
    enumerator AUDIOCHANNELREARRIGHT
    enumerator AUDIOCHANNELREARCENTER
    enumerator AUDIOCHANNELSIDELEFT
    enumerator AUDIOCHANNELSIDERIGHT
    enumerator AUDIOCHANNELALL

Functions

static inline int audio_codec_configure(const struct device *dev, struct audio_codec_cfg *cfg)
Configure the audio codec.
    Configure the audio codec device according to the configuration parameters provided as input
    Parameters
        • dev – Pointer to the device structure for codec driver instance.
        • cfg – Pointer to the structure containing the codec configuration.
    Returns
        0 on success, negative error code on failure

static inline void audio_codec_start_output(const struct device *dev)
Set codec to start output audio playback.
    Setup the audio codec device to start the audio playback
    Parameters
        • dev – Pointer to the device structure for codec driver instance.
static inline void audio_codec_stop_output(const struct device *dev)
Set codec to stop output audio playback.

Parameters
• dev – Pointer to the device structure for codec driver instance.

static inline int audio_codec_set_property(const struct device *dev, audio_property_t property, audio_channel_t channel, audio_property_value_t val)
Set a codec property defined by audio_property_t.
Set a property such as volume level, clock configuration etc.

Parameters
• dev – Pointer to the device structure for codec driver instance.
• property – The codec property to set
• channel – The audio channel for which the property has to be set
• val – Pointer to a property value of type audio_codec_property_value_t

Returns
0 on success, negative error code on failure

static inline int audio_codec_apply_properties(const struct device *dev)
Atomically apply any cached properties.
Following one or more invocations of audio_codec_set_property, that may have been cached by the driver, audio_codec_apply_properties can be invoked to apply all the properties as atomic as possible

Parameters
• dev – Pointer to the device structure for codec driver instance.

Returns
0 on success, negative error code on failure

union audio_dai_cfg_t
#include <codec.h> Digital Audio Interface Configuration Configuration is dependent on DAI type

Public Members

struct i2s_config 12s

struct audio_codec_cfg
#include <codec.h> Codec configuration parameters

union audio_property_value_t
#include <codec.h> Codec property values

Public Members
Audio DMIC

Overview  The audio DMIC interface provides access to digital microphones.

Configuration Options  Related configuration options:

- CONFIG_AUDIO_DMIC

API Reference

*group* audio_dmic_interface

Abstraction for digital microphones.

Enums

enum dmic_state

DMIC driver states

*Values:*

- enumerator DMIC_STATE_UNINIT
- enumerator DMIC_STATE_INITIALIZED
- enumerator DMIC_STATE_CONFIGURED
- enumerator DMIC_STATE_ACTIVE
- enumerator DMIC_STATE_PAUSED

enum dmic_trigger

DMIC driver trigger commands

*Values:*

- enumerator DMIC_TRIGGER_STOP
- enumerator DMIC_TRIGGER_START
- enumerator DMIC_TRIGGER_PAUSE
- enumerator DMIC_TRIGGER_RELEASE
enumerator DMIC_TRIGGER_RESET

enum pdm_lr
  PDM Channels LEFT / RIGHT
Values:
  enumerator PDM_CHAN_LEFT
  enumerator PDM_CHAN_RIGHT

Functions

static inline uint32_t dmic_build_channel_map(uint8_t channel, uint8_t pdm, enum pdm_lr lr)
  Build the channel map to populate struct pdm_chan_cfg
  Returns the map of PDM controller and LEFT/RIGHT channel shifted to the bit position corresponding to the input logical channel value
Parameters
  • channel – The logical channel number
  • pdm – The PDM hardware controller number
  • lr – LEFT/RIGHT channel within the chosen PDM hardware controller
Returns
  Bit-map containing the PDM and L/R channel information

static inline void dmic_parse_channel_map(uint32_t channel_map_lo, uint32_t channel_map_hi, uint8_t channel, uint8_t *pdm, enum pdm_lr *lr)
  Helper function to parse the channel map in pdm_chan_cfg
  Returns the PDM controller and LEFT/RIGHT channel corresponding to the channel map and the logical channel provided as input
Parameters
  • channel_map_lo – Lower order/significant bits of the channel map
  • channel_map_hi – Higher order/significant bits of the channel map
  • channel – The logical channel number
  • pdm – Pointer to the PDM hardware controller number
  • lr – Pointer to the LEFT/RIGHT channel within the PDM controller
Returns
  Bit-map containing the PDM and L/R channel information

static inline uint32_t dmic_build_clk_skew_map(uint8_t pdm, uint8_t skew)
  Build a bit map of clock skew values for each PDM channel
  Returns the bit-map of clock skew value shifted to the bit position corresponding to the input PDM controller value
Parameters
  • pdm – The PDM hardware controller number
  • skew – The skew to apply for the clock output from the PDM controller
Returns
  Bit-map containing the clock skew information
static inline int dmic_configure(const struct device *dev, struct dmic_cfg *cfg)
    Configure the DMIC driver and controller(s)
    Configures the DMIC driver device according to the number of channels, channel mapping, PDM I/O configuration, PCM stream configuration, etc.

    Parameters
    • dev – Pointer to the device structure for DMIC driver instance
    • cfg – Pointer to the structure containing the DMIC configuration

    Returns
    0 on success, a negative error code on failure

static inline int dmic_trigger(const struct device *dev, enum dmic_trigger cmd)
    Send a command to the DMIC driver
    Sends a command to the driver to perform a specific action

    Parameters
    • dev – Pointer to the device structure for DMIC driver instance
    • cmd – The command to be sent to the driver instance

    Returns
    0 on success, a negative error code on failure

static inline int dmic_read(const struct device *dev, uint8_t stream, void **buffer, size_t *size, int32_t timeout)
    Read received decimated PCM data stream
    Optionally waits for audio to be received and provides the received audio buffer from the requested stream

    Parameters
    • dev – Pointer to the device structure for DMIC driver instance
    • stream – Stream identifier
    • buffer – Pointer to the received buffer address
    • size – Pointer to the received buffer size
    • timeout – Timeout in milliseconds to wait in case audio is not yet received, or SYS_FOREVER_MS

    Returns
    0 on success, a negative error code on failure

struct pdm_io_cfg
    #include <dmic.h> PDM Input/Output signal configuration

struct pcm_stream_cfg
    #include <dmic.h> Configuration of the PCM streams to be output by the PDM hardware

struct pdm_chan_cfg
    #include <dmic.h> Mapping/ordering of the PDM channels to logical PCM output channel

struct dmic_cfg
    #include <dmic.h> Input configuration structure for the DMIC configuration API
I2S

Overview  The I2S (Inter-IC Sound) API provides support for the standard I2S interface as well as common non-standard extensions such as PCM Short/Long Frame Sync and Left/Right Justified Data Formats.

Configuration Options  Related configuration options:

- CONFIG_I2S

API Reference

group i2s_interface

I2S (Inter-IC Sound) Interface.

The I2S API provides support for the standard I2S interface standard as well as common non-standard extensions such as PCM Short/Long Frame Sync, Left/Right Justified Data Format.

Defines

I2S_FMT_DATA_FORMAT_SHIFT
  Data Format bit field position.

I2S_FMT_DATA_FORMAT_MASK
  Data Format bit field mask.

I2S_FMT_DATA_FORMAT_I2S
  Standard I2S Data Format.
  Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal (SCK). The MSB is always sent one clock period after the WS changes. Left channel data are sent first indicated by WS = 0, followed by right channel data indicated by WS = 1.

I2S_FMT_DATA_FORMAT_PCM_SHORT
  PCM Short Frame Sync Data Format.
  Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the falling edge of the clock signal (SCK). The falling edge of the frame sync signal (WS) indicates the start of the PCM word. The frame sync is one clock cycle long. An arbitrary number of data words can be sent in one frame.
I2S_FMT_DATA_FORMAT_PCM_LONG

PCM Long Frame Sync Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the falling edge of the clock signal (SCK). The rising edge of the frame sync signal (WS) indicates the start of the PCM word. The frame sync has an arbitrary length, however it has to fall before the start of the next frame. An arbitrary number of data words can be sent in one frame.

I2S_FMT_DATA_FORMAT_LEFT_JUSTIFIED

Left Justified Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal (SCK). The bits within the data word are left justified such that the MSB is always sent in the clock period following the WS transition. Left channel data are sent first indicated by WS = 1, followed by right channel data indicated by WS = 0.

I2S_FMT_DATA_FORMAT_RIGHT_JUSTIFIED

Right Justified Data Format.

Serial data is transmitted in two's complement with the MSB first. Both Word Select (WS) and Serial Data (SD) signals are sampled on the rising edge of the clock signal (SCK). The bits within the data word are right justified such that the LSB is always sent in the clock period preceding the WS transition. Left channel data are sent first indicated by WS = 1, followed by right channel data indicated by WS = 0.
I2S_FMT_DATA_ORDER_MSB
    Send MSB first

I2S_FMT_DATA_ORDER_LSB
    Send LSB first

I2S_FMT_DATA_ORDER_INV
    Invert bit ordering, send LSB first

I2S_FMT_CLK_FORMAT_SHIFT
    Data Format bit field position.

I2S_FMT_CLK_FORMAT_MASK
    Data Format bit field mask.

I2S_FMT_BIT_CLK_INV
    Invert bit clock

I2S_FMT_FRAME_CLK_INV
    Invert frame clock

I2S_FMT_CLK_NF_NB
    NF represents “Normal Frame” whereas IF represents “Inverted Frame” NB represents “Normal Bit Clk” whereas IB represents “Inverted Bit clk”

I2S_FMT_CLK_NF_IB

I2S_FMT_CLK_IF_NB

I2S_FMT_CLK_IF_IB

I2S_OPT_BIT_CLK_CONT
    Run bit clock continuously

I2S_OPT_BIT_CLK_GATED
    Run bit clock when sending data only

I2S_OPT_BIT_CLK_MASTER
    I2S driver is bit clock master

I2S_OPT_BIT_CLK_SLAVE
    I2S driver is bit clock slave
I2S_OPT_FRAME_CLK_MASTER
   I2S driver is frame clock master

I2S_OPT_FRAME_CLK_SLAVE
   I2S driver is frame clock slave

I2S_OPT_LOOPBACK
   Loop back mode.
   In loop back mode RX input will be connected internally to TX output. This is used primarily
   for testing.

I2S_OPT_PINGPONG
   Ping pong mode.
   In ping pong mode TX output will keep alternating between a ping buffer and a pong buffer.
   This is normally used in audio streams when one buffer is being populated while the other
   is being played (DMAed) and vice versa. So, in this mode, 2 sets of buffers fixed in size are
   used. Static Arrays are used to achieve this and hence they are never freed.

Typedefs

typedef uint8_t i2s_fmt_t

typedef uint8_t i2s_opt_t

Enums

enum i2s_dir
   I2C Direction.
   Values:

   enumerator I2S_DIR_RX
      Receive data

   enumerator I2S_DIR_TX
      Transmit data

   enumerator I2S_DIR_BOTH
      Both receive and transmit data

enum i2s_state
   Interface state
   Values:

   enumerator I2S_STATE_NOT_READY
      The interface is not ready.
The interface was initialized but **is not** yet ready to receive / transmit data. Call `i2s_configure()` to configure interface and change its state to READY.

**enumerator I2S_STATE_READY**

The interface is ready to receive / transmit data.

**enumerator I2S_STATE_RUNNING**

The interface is receiving / transmitting data.

**enumerator I2S_STATE_STOPPING**

The interface is draining its transmit queue.

**enumerator I2S_STATE_ERROR**

TX buffer underrun or RX buffer overrun has occurred.

**enum i2s_trigger_cmd**

Trigger command

**Values:**

**enumerator I2S_TRIGGER_START**

Start the transmission / reception of data.

If `I2S_DIR_TX` is set some data has to be queued for transmission by the `i2s_write()` function. This trigger can be used in READY state only and changes the interface state to RUNNING.

**enumerator I2S_TRIGGER_STOP**

Stop the transmission / reception of data.

Stop the transmission / reception of data at the end of the current memory block. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When the current TX / RX block is transmitted / received the state is changed to READY. Subsequent START trigger will resume transmission / reception where it stopped.

**enumerator I2S_TRIGGER_DRAIN**

Empty the transmit queue.

Send all data in the transmit queue and stop the transmission. If the trigger is applied to the RX queue it has the same effect as `I2S_TRIGGER_STOP`. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When all TX blocks are transmitted the state is changed to READY.
enumerator I2S_TRIGGER_DROP
Discard the transmit / receive queue.

Stop the transmission / reception immediately and discard the contents of the respective queue. This trigger can be used in any state other than NOT_READY and changes the interface state to READY.

enumerator I2S_TRIGGER_PREPARE
Prepare the queues after underrun/overrun error has occurred.

This trigger can be used in ERROR state only and changes the interface state to READY.

Functions

int i2s_configure(const struct device *dev, enum i2s_dir dir, const struct i2s_config *cfg)
Configure operation of a host I2S controller.

The dir parameter specifies if Transmit (TX) or Receive (RX) direction will be configured by data provided via cfg parameter.

The function can be called in NOT_READY or READY state only. If executed successfully the function will change the interface state to READY.

If the function is called with the parameter cfg->frame_clk_freq set to 0 the interface state will be changed to NOT_READY.

Parameters

• dev – Pointer to the device structure for the driver instance.
• dir – Stream direction: RX, TX, or both, as defined by I2S_DIR_*. The I2S_DIR_BOTH value may not be supported by some drivers. For those, the RX and TX streams need to be configured separately.
• cfg – Pointer to the structure containing configuration parameters.

Return values

• 0 – If successful.
• -EINVAL – Invalid argument.
• -ENOSYS – I2S_DIR_BOTH value is not supported.

static inline const struct i2s_config *i2s_config_get(const struct device *dev, enum i2s_dir dir)
Fetch configuration information of a host I2S controller.

Parameters

• dev – Pointer to the device structure for the driver instance
• dir – Stream direction: RX or TX as defined by I2S_DIR_*

Return values

Pointer – to the structure containing configuration parameters, or NULL if un-configured
static inline int i2s_read(const struct device *dev, void **mem_block, size_t *size)

Read data from the RX queue.

Data received by the I2S interface is stored in the RX queue consisting of memory blocks preallocated by this function from rx_mem_slab (as defined by i2s_configure). Ownership of the RX memory block is passed on to the user application which has to release it.

The data is read in chunks equal to the size of the memory block. If the interface is in READY state the number of bytes read can be smaller.

If there is no data in the RX queue the function will block waiting for the next RX memory block to fill in. This operation can timeout as defined by i2s_configure. If the timeout value is set to K_NO_WAIT the function is non-blocking.

Reading from the RX queue is possible in any state other than NOT_READY. If the interface is in the ERROR state it is still possible to read all the valid data stored in RX queue. Afterwards the function will return -EIO error.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- mem_block – Pointer to the RX memory block containing received data.
- size – Pointer to the variable storing the number of bytes read.

**Return values**

- 0 – If successful.
- -EIO – The interface is in NOT_READY or ERROR state and there are no more data blocks in the RX queue.
- -EBUSY – Returned without waiting.
- -EAGAIN – Waiting period timed out.

int i2s_buf_read(const struct device *dev, void *buf, size_t *size)

Read data from the RX queue into a provided buffer.

Data received by the I2S interface is stored in the RX queue consisting of memory blocks preallocated by this function from rx_mem_slab (as defined by i2s_configure). Calling this function removes one block from the queue which is copied into the provided buffer and then freed.

The provided buffer must be large enough to contain a full memory block of data, which is parameterized for the channel via i2s_configure() .

This function is otherwise equivalent to i2s_read().

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- buf – Destination buffer for read data, which must be at least the as large as the configured memory block size for the RX channel.
- size – Pointer to the variable storing the number of bytes read.

**Return values**

- 0 – If successful.
- -EIO – The interface is in NOT_READY or ERROR state and there are no more data blocks in the RX queue.
- -EBUSY – Returned without waiting.
- -EAGAIN – Waiting period timed out.
static inline int i2s_write(const struct device *dev, void *mem_block, size_t size)
{
    Write data to the TX queue.

    Data to be sent by the I2S interface is stored first in the TX queue. TX queue consists of
    memory blocks preallocated by the user from tx_mem slab (as defined by i2s_configure).
    This function takes ownership of the memory block and will release it when all data are
    transmitted.

    If there are no free slots in the TX queue the function will block waiting for the next TX
    memory block to be send and removed from the queue. This operation can timeout as defined
    by i2s_config. If the timeout value is set to K_NO_WAIT the function is non-blocking.

    Writing to the TX queue is only possible if the interface is in READY or RUNNING state.

    Parameters

    • dev – Pointer to the device structure for the driver instance.
    • mem_block – Pointer to the TX memory block containing data to be sent.
    • size – Number of bytes to write. This value has to be equal or smaller than the
      size of the memory block.

    Return values

    • 0 – If successful.
    • -EIO – The interface is not in READY or RUNNING state.
    • -EBUSY – Returned without waiting.
    • -EAGAIN – Waiting period timed out.

int i2s_buf_write(const struct device *dev, void *buf, size_t size)
{
    Write data to the TX queue from a provided buffer.

    This function acquires a memory block from the I2S channel TX queue and copies the provided
    data buffer into it. It is otherwise equivalent to i2s_write().

    Parameters

    • dev – Pointer to the device structure for the driver instance.
    • buf – Pointer to a buffer containing the data to transmit.
    • size – Number of bytes to write. This value has to be equal or smaller than the
      size of the channel's TX memory block configuration.

    Return values

    • 0 – If successful.
    • -EIO – The interface is not in READY or RUNNING state.
    • -EBUSY – Returned without waiting.
    • -EAGAIN – Waiting period timed out.
    • -ENOMEM – No memory in TX slab queue.
    • -EINVAL – Size parameter larger than TX queue memory block.

int i2s_trigger(const struct device *dev, enum i2s_dir dir, enum i2s_trigger_cmd cmd)
{
    Send a trigger command.

    Parameters

    • dev – Pointer to the device structure for the driver instance.
    • dir – Stream direction: RX, TX, or both, as defined by I2S_DIR_. The
      I2S_DIR_BOTH value may not be supported by some drivers. For those, trig-
      gering need to be done separately for the RX and TX streams.
Return values

- **0** – If successful.
- **-EINVAL** – Invalid argument.
- **-EIO** – The trigger cannot be executed in the current state or a DMA channel cannot be allocated.
- **-ENOMEM** – RX/TX memory block not available.
- **-ENOSYS** – I2S_DIR_BOTH value is not supported.

```c
struct i2s_config
```

```
#include <i2s.h> Interface configuration options.
```

Memory slab pointed to by the mem_slab field has to be defined and initialized by the user. For I2S driver to function correctly number of memory blocks in a slab has to be at least 2 per queue. Size of the memory block should be multiple of frame_size where frame_size = (channels * word_size_bytes). As an example 16 bit word will occupy 2 bytes, 24 or 32 bit word will occupy 4 bytes.

Please check Zephyr Kernel Primer for more information on memory slabs.

Remark

When I2S data format is selected parameter channels is ignored, number of words in a frame is always 2.

**Param word_size**
Number of bits representing one data word.

**Param channels**
Number of words per frame.

**Param format**
Data stream format as defined by I2S_FMT_* constants.

**Param options**
Configuration options as defined by I2S_OPT_* constants.

**Param frame_clk_freq**
Frame clock (WS) frequency, this is sampling rate.

**Param mem_slab**
Memory slab to store RX/TX data.

**Param block_size**
Size of one RX/TX memory block (buffer) in bytes.

**Param timeout**
Read/Write timeout. Number of milliseconds to wait in case TX queue is full or RX queue is empty, or 0, or SYS_FOREVER_MS.

DAI

**Overview** The DAI (Digital Audio Interface) is a generic high level API for audio drivers. It can be configured with bespoke data for vendor specific configuration.
Configuration Options
Related configuration options:
- CONFIG_DAI

API Reference

group dai_interface

DAI Interface.
The DAI API provides support for the standard I2S (SSP) and its common variants. It supports also DMIC, HDA and SDW backends. The API has a config function with bespoke data argument for device/vendor specific config. There are also optional timestamping functions to get device specific audio clock time.

Enums

enum dai_type

Types of DAI.
The type of the DAI. This ID type is used to configure bespoke DAI HW settings.
DAIs have a lot of physical link feature variability and therefore need different configuration data to cater for different use cases. We usually need to pass extra bespoke configuration prior to DAI start.
Values:

enumerator DAI_LEGACY_I2S = 0
Legacy I2S compatible with i2s.h
enumerator DAI_INTEL_SSP
Intel SSP
enumerator DAI_INTEL_DMIC
Intel DMIC
enumerator DAI_INTEL_HDA
Intel HD/A
enumerator DAI_INTEL_ALH
Intel ALH
enumerator DAI_IMX_SAI
i.MX SAI
enumerator DAI_IMX_ESAI
i.MX ESAI
enumerator DAI_AMD_BT
Amd BT
enumerator DAI_AMD_SP
Amd SP
enumerator DAI_AMD_DMIC
    Amd DMIC

enumerator DAI_MEDIATEK_AFE
    Mtk AFE

denominator DAI_INTEL_SSP_NHLT
    nhlt ssp

denominator DAI_INTEL_DMIC_NHLT
    nhlt ssp

denominator DAI_INTEL_HDA_NHLT
    nhlt Intel HD/A

denominator DAI_INTEL_ALH_NHLT
    nhlt Intel ALH

denom dai_dir
    Dai Direction.
    Values:

  denominator DAI_DIR_RX = 1
      Receive data

  denominator DAI_DIR_TX
      Transmit data

  denominator DAI_DIR_BOTH
      Both receive and transmit data

denom dai_state
    Interface state
    Values:

  denominator DAI_STATE_NOT_READY = 0
      The interface is not ready.

      The interface was initialized but is not yet ready to receive / transmit data. Call dai_config_set() to configure interface and change its state to READY.

  denominator DAI_STATE_READY
      The interface is ready to receive / transmit data.

  denominator DAI_STATE_RUNNING
      The interface is receiving / transmitting data.
enumerator DAI_STATE_PRE_RUNNING
The interface is clocking but not receiving / transmitting data.

enumerator DAI_STATE_PAUSED
The interface paused

enumerator DAI_STATE_STOPPING
The interface is draining its transmit queue.

enumerator DAI_STATE_ERROR
TX buffer underrun or RX buffer overrun has occurred.

enum dai_trigger_cmd
Trigger command
Values:

enumerator DAI_TRIGGER_START = 0
Start the transmission / reception of data.

If DAI_DIR_TX is set some data has to be queued for transmission by the dai_write() function. This trigger can be used in READY state only and changes the interface state to RUNNING.

enumerator DAI_TRIGGER_PRE_START
Optional - Pre Start the transmission / reception of data.

Allows the DAI and downstream codecs to prepare for audio Tx/Rx by starting any required clocks for downstream PLL/FLL locking.

enumerator DAI_TRIGGER_STOP
Stop the transmission / reception of data.

Stop the transmission / reception of data at the end of the current memory block. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When the current TX / RX block is transmitted / received the state is changed to READY. Subsequent START trigger will resume transmission / reception where it stopped.

enumerator DAI_TRIGGER_PAUSE
Pause the transmission / reception of data.

Pause the transmission / reception of data at the end of the current memory block. Behavior is implementation specific but usually this state doesn’t completely stop the clocks or transmission. The dai_
could be transmitting 0's (silence), but it is not consuming data from outside.

enumerator DAI_TRIGGER_POST_STOP
Optional - Post Stop the transmission / reception of data.

Allows the DAI and downstream codecs to shutdown cleanly after audio Tx/Rx by stopping any required clocks for downstream audio completion.

enumerator DAI_TRIGGER_DRAIN
Empty the transmit queue.

Send all data in the transmit queue and stop the transmission. If the trigger is applied to the RX queue it has the same effect as DAI_TRIGGER_STOP. This trigger can be used in RUNNING state only and at first changes the interface state to STOPPING. When all TX blocks are transmitted the state is changed to READY.

enumerator DAI_TRIGGER_DROP
Discard the transmit / receive queue.

Stop the transmission / reception immediately and discard the contents of the respective queue. This trigger can be used in any state other than NOT_READY and changes the interface state to READY.

enumerator DAI_TRIGGER_PREPARE
Prepare the queues after underrun/overrun error has occurred.

This trigger can be used in ERROR state only and changes the interface state to READY.

enumerator DAI_TRIGGER_RESET
Reset.

This trigger frees resources and moves the driver back to initial state.

enumerator DAI_TRIGGER_COPY
Copy.

This trigger prepares for data copying.
Functions

static inline int dai_probe(const struct device *dev)

Probe operation of DAI driver.

The function will be called to power up the device and update for example possible reference count of the users. It can be used also to initialize internal variables and memory allocation.

Parameters

• dev – Pointer to the device structure for the driver instance.

Return values

0 – If successful.

static inline int dai_remove(const struct device *dev)

Remove operation of DAI driver.

The function will be called to unregister/unbind the device, for example to power down the device or decrease the usage reference count.

Parameters

• dev – Pointer to the device structure for the driver instance.

Return values

0 – If successful.

static inline int dai_config_set(const struct device *dev, const struct dai_config *cfg, const void *bespoke_cfg)

Configure operation of a DAI driver.

The dir parameter specifies if Transmit (TX) or Receive (RX) direction will be configured by data provided via cfg parameter.

The function can be called in NOT_READY or READY state only. If executed successfully the function will change the interface state to READY.

If the function is called with the parameter cfg->frame_clk_freq set to 0 the interface state will be changed to NOT_READY.

Parameters

• dev – Pointer to the device structure for the driver instance.

• cfg – Pointer to the structure containing configuration parameters.

• bespoke_cfg – Pointer to the structure containing bespoke config.

Return values

• 0 – If successful.

• -EINVAL – Invalid argument.

• -ENOSYS – DAI_DIR_BOTH value is not supported.

static inline const struct dai_config *dai_config_get(const struct device *dev, enum dai_dir dir)

Fetch configuration information of a DAI driver.

Parameters

• dev – Pointer to the device structure for the driver instance.

• dir – Stream direction: RX or TX as defined by DAI_DIR_*

Return values

Pointer – to the structure containing configuration parameters, or NULL if un-configured.
static inline const struct \textit{dai\_properties} *\textit{dai\_get\_properties}(const struct \textit{device} *\textit{dev}, enum \textit{dai\_dir} \textit{dir}, int \textit{stream\_id})

Fetch properties of a DAI driver.

\textbf{Parameters}

- \textit{dev} – Pointer to the device structure for the driver instance.
- \textit{dir} – Stream direction: RX or TX as defined by DAI\_DIR\_\*.
- \textit{stream\_id} – Stream id: some drivers may have stream specific properties, this id specifies the stream.

\textbf{Return values}

Pointer to the structure containing properties, or NULL if error or no properties.

static inline int \textit{dai\_trigger}(const struct \textit{device} *\textit{dev}, enum \textit{dai\_dir} \textit{dir}, enum \textit{dai\_trigger\_cmd} \textit{cmd})

Send a trigger command.

\textbf{Parameters}

- \textit{dev} – Pointer to the device structure for the driver instance.
- \textit{dir} – Stream direction: RX, TX, or both, as defined by DAI\_DIR\_\*.
  The DAI\_DIR\_\* value may not be supported by some drivers. For those, triggering need to be done separately for the RX and TX streams.
- \textit{cmd} – Trigger command.

\textbf{Return values}

- 0 – If successful.
- -EINVAL – Invalid argument.
- -EIO – The trigger cannot be executed in the current state or a DMA channel cannot be allocated.
- -ENOMEM – RX/TX memory block not available.
- -ENOSYS – DAI\_DIR\_\* value is not supported.

static inline int \textit{dai\_ts\_config}(const struct \textit{device} *\textit{dev}, struct \textit{dai\_ts\_cfg} *\textit{cfg})

Configures timestamping in attached DAI.

Optional method.

\textbf{Parameters}

- \textit{dev} – Component device.
- \textit{cfg} – Timestamp config.

\textbf{Return values}

0 – If successful.

static inline int \textit{dai\_ts\_start}(const struct \textit{device} *\textit{dev}, struct \textit{dai\_ts\_cfg} *\textit{cfg})

Starts timestamping.

Optional method.

\textbf{Parameters}

- \textit{dev} – Component device.
- \textit{cfg} – Timestamp config.
Return values
0 – If successful.

static inline int dai_ts_stop(const struct device *dev, struct dai_ts_cfg *cfg)

Stops timestamping.
Optional method.

Parameters
• dev – Component device.
• cfg – Timestamp config.

Return values
0 – If successful.

static inline int dai_ts_get(const struct device *dev, struct dai_ts_cfg *cfg, struct dai_ts_data *tsd)

Gets timestamp.
Optional method.

Parameters
• dev – Component device.
• cfg – Timestamp config.
• tsd – Receives timestamp data.

Return values
0 – If successful.

struct dai_properties
#include <dai.h> Properties of DAI.

This struct is used with APIs get_properties function to query DAI properties like fifo address and dma handshake. These are needed for example to setup dma outside the driver code.

Param fifo_address
Fifo hw address for e.g. when connecting to dma.

Param fifo_depth
Fifo depth.

Param dma_hs_id
Dma handshake id.

Param reg_init_delay
Delay for initializing registers.

Param stream_id
Stream ID.

struct dai_config
#include <dai.h> Generic Dai interface configuration options.

Main dai config struct

Param dai_type
Type of the dai.

Param dai_index
Index of the dai.
Param channels
   Number of audio channels, words in frame.

Param rate
   Frame clock (WS) frequency, sampling rate.

Param format
   Dai specific data stream format.

Param options
   Dai specific configuration options.

Param word_size
   Number of bits representing one data word.

Param block_size
   Size of one RX/TX memory block (buffer) in bytes.

struct dai_ts_cfg
   #include <dai.h>

struct dai_ts_data
   #include <dai.h>

7.3.3 Controller Area Network (CAN)

CAN Controller

- Overview
- Sending
- Receiving
- Setting the bitrate
- SocketCAN
- Samples
- CAN Controller API Reference
- CAN Transceiver API Reference

Overview
   Controller Area Network is a two-wire serial bus specified by the Bosch CAN Specification, Bosch CAN with Flexible Data-Rate specification and the ISO 11898-1:2003 standard. CAN is mostly known for its application in the automotive domain. However, it is also used in home and industrial automation and other products.

A CAN transceiver is an external device that converts the logic level signals from the CAN controller to the bus-levels. The bus lines are called CAN High (CAN H) and CAN Low (CAN L). The transmit wire from the controller to the transceiver is called CAN TX, and the receive wire is called CAN RX. These wires use the logic levels whereas the bus-level is interpreted differentially between CAN H and CAN L. The bus can be either in the recessive (logical one) or dominant (logical zero) state. The recessive state is when both lines, CAN H and CAN L, are roughly at the same voltage level. This state is also the idle state. To write a dominant bit to the bus, open-drain transistors tie CAN H to Vdd and CAN L to ground. The first and last node use a 120-ohm resistor between CAN H and CAN L to terminate the bus. The dominant state always overrides the recessive state. This structure is called a wired-AND.
**Warning:** CAN controllers can only initialize when the bus is in the idle (recessive) state for at least 11 recessive bits. Therefore you have to make sure that CAN RX is high, at least for a short time. This is also necessary for loopback mode.

The bit-timing as defined in ISO 11898-1:2003 looks as following:

A single bit is split into four segments.

- **Sync_Seg:** The nodes synchronize at the edge of the Sync_Seg. It is always one time quantum in length.
- **Prop_Seg:** The signal propagation delay of the bus and other delays of the transceiver and node.
- **Phase_Seg1 and Phase_Seg2:** Define the sampling point. The bit is sampled at the end of Phase_Seg1.

The bit-rate is calculated from the time of a time quantum and the values defined above. A bit has the length of Sync_Seg plus Prop_Seg plus Phase_Seg1 plus Phase_Seg2 multiplied by the time of single time quantum. The bit-rate is the inverse of the length of a single bit.

A bit is sampled at the sampling point. The sample point is between Phase_Seg1 and Phase_Seg2 and therefore is a parameter that the user needs to choose. The CiA recommends setting the sample point to 87.5% of the bit.

The resynchronization jump width (SJW) defines the amount of time quantum the sample point can be moved. The sample point is moved when resynchronization is needed.

The timing parameters (SJW, bitrate and sampling point, or bitrate, Prop_Seg, Phase_Seg1 and Phase_Seg2) are initially set from the device-tree and can be changed at run-time from the timing-API.

CAN uses so-called identifiers to identify the frame instead of addresses to identify a node. This identifier can either have 11-bit width (Standard or Basic Frame) or 29-bit in case of an Extended Frame. The Zephyr CAN API supports both Standard and Extended identifiers concurrently. A CAN frame starts with a dominant Start Of Frame bit. After that, the identifiers follow. This phase is called the arbitration phase. During the arbitration phase, write collisions are allowed. They resolve by the fact that dominant bits override recessive bits. Nodes monitor the bus and notice when their transmission is being overridden and in case, abort their transmission. This effectively gives lower number identifiers priority over higher number identifiers.
Filters are used to whitelist identifiers that are of interest for the specific node. An identifier that doesn’t match any filter is ignored. Filters can either match exactly or a specified part of the identifier. This method is called masking. As an example, a mask with 11 bits set for standard or 29 bits set for extended identifiers must match perfectly. Bits that are set to zero in the mask are ignored when matching an identifier. Most CAN controllers implement a limited number of filters in hardware. The number of filters is also limited in Kconfig to save memory.

Errors may occur during transmission. In case a node detects an erroneous frame, it partially overrides the current frame with an error-frame. Error-frames can either be error passive or error active, depending on the state of the controller. In case the controller is in error active state, it sends six consecutive dominant bits, which is a violation of the stuffing rule that all nodes can detect. The sender may resend the frame right after.

An initialized node can be in one of the following states:

- Error-active
- Error-passive
- Bus-off

After initialization, the node is in the error-active state. In this state, the node is allowed to send active error frames, ACK, and overload frames. Every node has a receive- and transmit-error counter. If either the receive- or the transmit-error counter exceeds 127, the node changes to error-passive state. In this state, the node is not allowed to send error-active frames anymore. If the transmit-error counter increases further to 255, the node changes to the bus-off state. In this state, the node is not allowed to send any dominant bits to the bus. Nodes in the bus-off state may recover after receiving 128 occurrences of 11 concurrent recessive bits.

You can read more about CAN bus in this CAN Wikipedia article.

Zephyr supports following CAN features:

- Standard and Extended Identifiers
- Filters with Masking
- Loopback and Silent mode
- Remote Request

Sending  The following code snippets show how to send data.

This basic sample sends a CAN frame with standard identifier 0x123 and eight bytes of data. When passing NULL as the callback, as shown in this example, the send function blocks until the frame is sent and acknowledged by at least one other node or an error occurred. The timeout only takes effect on acquiring a mailbox. When a transmitting mailbox is assigned, sending cannot be canceled.

```c
struct can_frame frame = {
    .flags = 0,
    .id = 0x123,
    .dlc = 8,
    .data = {1,2,3,4,5,6,7,8}
};
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));
int ret;
ret = can_send(can_dev, &frame, K_MSEC(100), NULL, NULL);
if (ret != 0) {
    LOG_ERR("Sending failed [%d]", ret);
}
```

This example shows how to send a frame with extended identifier 0x1234567 and two bytes of data. The provided callback is called when the message is sent, or an error occurred. Passing \texttt{K\_FOREVER} to
the timeout causes the function to block until a transfer mailbox is assigned to the frame or an error occurred. It does not block until the message is sent like the example above.

```c
void tx_callback(const struct device *dev, int error, void *user_data)
{
    char *sender = (char *)user_data;
    if (error != 0) {
        LOG_ERR("Sending failed [%d]\nSender: %s\n", error, sender);
    }
}

int send_function(const struct device *can_dev)
{
    struct can_frame frame = {
        .flags = CAN_FRAME_IDE,
        .id = 0x1234567,
        .dlc = 2
    };
    frame.data[0] = 1;
    frame.data[1] = 2;
    return can_send(can_dev, &frame, K_FOREVER, tx_irq_callback, "Sender 1");
}
```

Receiving Frames are only received when they match a filter. The following code snippets show how to receive frames by adding filters.

Here we have an example for a receiving callback as used for `can_add_rx_filter()`. The user data argument is passed when the filter is added.

```c
void rx_callback_function(const struct device *dev, struct can_frame *frame, void *user_data)
{
    ... do something with the frame ...
}
```

The following snippet shows how to add a filter with a callback function. It is the most efficient but also the most critical way to receive messages. The callback function is called from an interrupt context, which means that the callback function should be as short as possible and must not block. Adding callback functions is not allowed from userspace context.

The filter for this example is configured to match the identifier 0x123 exactly.

```c
const struct can_filter my_filter = {
    .flags = CAN_FILTER_DATA,
    .id = 0x123,
    .id_mask = CAN_STD_ID_MASK
};
int filter_id;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));
filter_id = can_add_rx_filter(can_dev, rx_callback_function, callback_arg, &my_filter);
if (filter_id < 0) {
    LOG_ERR("Unable to add rx filter [%d]", filter_id);
}
```
Here an example for `can_add_rx_filter_msgq()` is shown. With this function, it is possible to receive frames synchronously. This function can be called from userspace context. The size of the message queue should be as big as the expected backlog.

The filter for this example is configured to match the extended identifier 0x1234567 exactly.

```c
const struct can_filter my_filter = {
    .flags = CAN_FILTER_DATA | CAN_FILTER_IDE,
    .id = 0x1234567,
    .id_mask = CAN_EXT_ID_MASK
};
CAN_MSGQ_DEFINE(my_can_msgq, 2);
struct can_frame rx_frame;
int filter_id;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));

filter_id = can_add_rx_filter_msgq(can_dev, &my_can_msgq, &my_filter);
if (filter_id < 0) {
    LOG_ERR("Unable to add rx msgq [%d]", filter_id);
    return;
}

while (true) {
    k_msgq_get(&my_can_msgq, &rx_frame, K_FOREVER);
    ... do something with the frame ...
}

`can_remove_rx_filter()` removes the given filter.

`can_remove_rx_filter(can_dev, filter_id);`
```

Setting the bitrate  The bitrate and sampling point is initially set at runtime. To change it from the application, one can use the `can_set_timing()` API. The `can_calc_timing()` function can calculate timing from a bitrate and sampling point in permille. The following example sets the bitrate to 250k baud with the sampling point at 87.5%.

```c
struct can_timing timing;
const struct device *const can_dev = DEVICE_DT_GET(DT_CHOSEN(zephyr_canbus));
int ret;

ret = can_calc_timing(can_dev, &timing, 250000, 875);
if (ret > 0) {
    LOG_INF("Sample-Point error: %d", ret);
}
if (ret < 0) {
    LOG_ERR("Failed to calc a valid timing");
    return;
}

ret = can_stop(can_dev);
if (ret != 0) {
    LOG_ERR("Failed to stop CAN controller");
}

ret = can_set_timing(can_dev, &timing);
if (ret != 0) {
```
A similar API exists for calculating and setting the timing for the data phase for CAN-FD capable controllers. See `can_set_timing_data()` and `can_calc_timing_data()`.

**SocketCAN**  Zephyr additionally supports SocketCAN, a BSD socket implementation of the Zephyr CAN API. SocketCAN brings the convenience of the well-known BSD Socket API to Controller Area Networks. It is compatible with the Linux SocketCAN implementation, where many other high-level CAN projects build on top. Note that frames are routed to the network stack instead of passed directly, which adds some computation and memory overhead.

**Samples**  We have two ready-to-build samples demonstrating use of the Zephyr CAN API Zephyr CAN counter sample and SocketCAN sample.

**CAN Controller API Reference**

**group can_interface**

**CAN Interface.**

**CAN controller configuration**

```c
int can_get_core_clock(const struct device *dev, uint32_t *rate)
```

Get the CAN core clock rate.

Returns the CAN core clock rate. One time quantum is 1/(core clock rate).

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `rate` – [out] CAN core clock rate in Hz.

**Returns**

0 on success, or a negative error code on error

```c
int can_get_max_bitrate(const struct device *dev, uint32_t *max_bitrate)
```

Get maximum supported bitrate.

Get the maximum supported bitrate for the CAN controller/transceiver combination.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `max_bitrate` – [out] Maximum supported bitrate in bits/s

**Return values**

- -EIO – General input/output error.
- -ENOSYS – If this function is not implemented by the driver.
const struct can_timing *can_get_timing_min(const struct device *dev)
Get the minimum supported timing parameter values.

Parameters
• dev – Pointer to the device structure for the driver instance.

Returns
Pointer to the minimum supported timing parameter values.

const struct can_timing *can_get_timing_max(const struct device *dev)
Get the maximum supported timing parameter values.

Parameters
• dev – Pointer to the device structure for the driver instance.

Returns
Pointer to the maximum supported timing parameter values.

int can_calc_timing(const struct device *dev, struct can_timing *res, uint32_t bitrate, uint16_t sample_pnt)
Calculate timing parameters from bitrate and sample point.
Calculate the timing parameters from a given bitrate in bits/s and the sampling point in per-mill (1/1000) of the entire bit time. The bitrate must always match perfectly. If no result can be reached for the given parameters, EINVAL is returned.

Parameters
• dev – Pointer to the device structure for the driver instance.
• res – [out] Result is written into the can_timing struct provided.
• bitrate – Target bitrate in bits/s.
• sample_pnt – Sampling point in permill of the entire bit time.

Return values
• 0 – or positive sample point error on success.
• -EINVAL – if the requested bitrate or sample point is out of range.
• -ENOTSUP – if the requested bitrate is not supported.
• -EIO – if can_get_core_clock() is not available.

const struct can_timing *can_get_timing_data_min(const struct device *dev)
Get the minimum supported timing parameter values for the data phase.
Same as can_get_timing_min() but for the minimum values for the data phase.

Note: CONFIG_CAN_FD_MODE must be selected for this function to be available.
const struct can_timing *can_get_timing_data_max(const struct device *dev)
Get the maximum supported timing parameter values for the data phase.
Same as can_get_timing_max() but for the maximum values for the data phase.

Note: CONFIG_CAN_FD_MODE must be selected for this function to be available.

Parameters
• dev – Pointer to the device structure for the driver instance.

Returns
Pointer to the maximum supported timing parameter values, or NULL if CAN-FD support is not implemented by the driver.

int can_calc_timing_data(const struct device *dev, struct can_timing *res, uint32_t bitrate, uint16_t sample_pnt)
Calculate timing parameters for the data phase.
Same as can_calc_timing() but with the maximum and minimum values from the data phase.

Note: CONFIG_CAN_FD_MODE must be selected for this function to be available.

Parameters
• dev – Pointer to the device structure for the driver instance.
• res – [out] Result is written into the can_timing struct provided.
• bitrate – Target bitrate for the data phase in bits/s
• sample_pnt – Sampling point for the data phase in permille of the entire bit time.

Return values
• 0 – or positive sample point error on success.
• -EINVAL – if the requested bitrate or sample point is out of range.
• -ENOTSUP – if the requested bitrate is not supported.
• -EIO – if can_get_core_clock() is not available.

int can_set_timing_data(const struct device *dev, const struct can_timing *timing_data)
Configure the bus timing for the data phase of a CAN-FD controller.
If the sjw equals CAN_SJW_NO_CHANGE, the sjw parameter is not changed.

See also:
can_set_timing()

Note: CONFIG_CAN_FD_MODE must be selected for this function to be available.

Parameters
• dev – Pointer to the device structure for the driver instance.
• timing_data – Bus timings for data phase
Return values

- 0 – If successful.
- -EBUSY – if the CAN controller is not in stopped state.
- -EIO – General input/output error, failed to configure device.
- -ENOSYS – if CAN-FD support is not implemented by the driver.

```
int can_set_bitrate_data(const struct device *dev, uint32_t bitrate_data)
```

Set the bitrate for the data phase of the CAN-FD controller.

CAN in Automation (CiA) 301 v4.2.0 recommends a sample point location of 87.5% percent for all bitrates. However, some CAN controllers have difficulties meeting this for higher bitrates.

This function defaults to using a sample point of 75.0% for bitrates over 800 kbit/s, 80.0% for bitrates over 500 kbit/s, and 87.5% for all other bitrates. This is in line with the sample point locations used by the Linux kernel.

See also:

*can_set_bitrate()

Note: CONFIG_CAN_FD_MODE must be selected for this function to be available.

Parameters

- dev – Pointer to the device structure for the driver instance.
- bitrate_data – Desired data phase bitrate.

Return values

- 0 – If successful.
- -EBUSY – if the CAN controller is not in stopped state.
- -EINVAL – if the requested bitrate is out of range.
- -ENOTSUP – if the requested bitrate not supported by the CAN controller/transceiver combination.
- -ERANGE – if the resulting sample point is off by more than +/- 5%.
- -EIO – General input/output error, failed to set bitrate.

```
int can_calc_prescaler(const struct device *dev, struct can_timing *timing, uint32_t bitrate)
```

Fill in the prescaler value for a given bitrate and timing.

Fill the prescaler value in the timing struct. The *sjw*, *prop_seg*, *phase_seg1* and *phase_seg2* must be given.

The returned bitrate error is remainder of the division of the clock rate by the bitrate times the timing segments.

Parameters

- dev – Pointer to the device structure for the driver instance.
- timing – Result is written into the *can_timing* struct provided.
- bitrate – Target bitrate.

Return values
int can_set_timing(const struct device *dev, const struct can_timing *timing)
Configure the bus timing of a CAN controller.
If the sjw equals CAN_SJW_NO_CHANGE, the sjw parameter is not changed.

See also:
can_set_timing_data()

Parameters
• dev – Pointer to the device structure for the driver instance.
• timing – Bus timings.

Return values
• 0 – If successful.
• -EBUSY – if the CAN controller is not in stopped state.
• -EIO – General input/output error, failed to configure device.

int can_get_capabilities(const struct device *dev, can_mode_t *cap)
Get the supported modes of the CAN controller.
The returned capabilities may not necessarily be supported at the same time (e.g. some CAN controllers support both CAN_MODE_LOOPBACK and CAN_MODE_LISTENONLY, but not at the same time).

Parameters
• dev – Pointer to the device structure for the driver instance.
• cap – [out] Supported capabilities.

Return values
• 0 – If successful.
• -EIO – General input/output error, failed to get capabilities.

int can_start(const struct device *dev)
Start the CAN controller.
Bring the CAN controller out of CAN_STATE_STOPPED. This will reset the RX/TX error counters, enable the CAN controller to participate in CAN communication, and enable the CAN tranceiver, if supported.

See also:
can_stop()
See also:
can_transceiver_enable()

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – if successful.
• -EALREADY – if the device is already started.
• -EIO – General input/output error, failed to start device.

```c
int can_stop(const struct device *dev)
```

Stop the CAN controller.

Bring the CAN controller into CAN_STATE_STOPPED. This will disallow the CAN controller from participating in CAN communication, abort any pending CAN frame transmissions, and disable the CAN transceiver, if supported.

**See also:**

- `can_start()`
- `can_transceiver_disable()`

### Parameters

- `dev` – Pointer to the device structure for the driver instance.

### Return values

- 0 – if successful.
- -EALREADY – if the device is already stopped.
- -EIO – General input/output error, failed to stop device.

```c
int can_set_mode(const struct device *dev, can_mode_t mode)
```

Set the CAN controller to the given operation mode.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `mode` – Operation mode.

### Return values

- 0 – If successful.
- -EBUSY – if the CAN controller is not in stopped state.
- -EIO – General input/output error, failed to configure device.

```c
int can_set_bitrate(const struct device *dev, uint32_t bitrate)
```

Set the bitrate of the CAN controller.

CAN in Automation (CiA) 301 v4.2.0 recommends a sample point location of 87.5% percent for all bitrates. However, some CAN controllers have difficulties meeting this for higher bitrates.

This function defaults to using a sample point of 75.0% for bitrates over 800 kbit/s, 80.0% for bitrates over 500 kbit/s, and 87.5% for all other bitrates. This is in line with the sample point locations used by the Linux kernel.

**See also:**

- `can_set_bitrate_data()`

#### Parameters

- `dev` – Pointer to the device structure for the driver instance.
bitrate – Desired arbitration phase bitrate.

**Return values**

- **0** – If successful.
- **-EBUSY** – if the CAN controller is not in stopped state.
- **-EINVAL** – if the requested bitrate is out of range.
- **-ENOTSUP** – if the requested bitrate not supported by the CAN controller/transceiver combination.
- **-ERANGE** – if the resulting sample point is off by more than +/- 5%.
- **-EIO** – General input/output error, failed to set bitrate.

**CAN_SJW_NO_CHANGE**

Synchronization Jump Width (SJW) value to indicate that the SJW should not be changed by the timing calculation.

### Transmitting CAN frames

```c
int can_send(const struct device *dev, const struct can_frame *frame, k_timeout_t timeout,
             can_tx_callback_t callback, void *user_data)
```

Queue a CAN frame for transmission on the CAN bus.

Queue a CAN frame for transmission on the CAN bus with optional timeout and completion callback function.

Queued CAN frames are transmitted in order according to the their priority:

- The lower the CAN-ID, the higher the priority.
- Data frames have higher priority than Remote Transmission Request (RTR) frames with identical CAN-IDs.
- Frames with standard (11-bit) identifiers have higher priority than frames with extended (29-bit) identifiers with identical base IDs (the higher 11 bits of the extended identifier).
- Transmission order for queued frames with the same priority is hardware dependent.

By default, the CAN controller will automatically retry transmission in case of lost bus arbitration or missing acknowledge. Some CAN controllers support disabling automatic retransmissions via **CAN_MODE_ONE_SHOT**.

**Note:** If transmitting segmented messages spanning multiple CAN frames with identical CAN-IDs, the sender must ensure to only queue one frame at a time if FIFO order is required.

**Parameters**

- **dev** – Pointer to the device structure for the driver instance.
- **frame** – CAN frame to transmit.
- **timeout** – Timeout waiting for a empty TX mailbox or **K_FOREVER**.
- **callback** – Optional callback for when the frame was sent or a transmission error occurred. If **NULL**, this function is blocking until frame is sent. The callback must be **NULL** if called from user mode.
- **user_data** – User data to pass to callback function.
Return values

- 0 – if successful.
- -EINVAL – if an invalid parameter was passed to the function.
- -ENOTSUP – if an unsupported parameter was passed to the function.
- -ENETDOWN – if the CAN controller is in stopped state.
- -ENETUNREACH – if the CAN controller is in bus-off state.
- -EBUSY – if CAN bus arbitration was lost (only applicable if automatic retransmissions are disabled).
- -EIO – if a general transmit error occurred (e.g. missing ACK if automatic retransmissions are disabled).
- -EAGAIN – on timeout.

Receiving CAN frames

static inline int can_add_rx_filter(const struct device *dev, can_rx_callback_t callback, void *user_data, const struct can_filter *filter)

Add a callback function for a given CAN filter.

Add a callback to CAN identifiers specified by a filter. When a received CAN frame matching the filter is received by the CAN controller, the callback function is called in interrupt context.

If a frame matches more than one attached filter, the priority of the match is hardware dependent.

The same callback function can be used for multiple filters.

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback – This function is called by the CAN controller driver whenever a frame matching the filter is received.
- user_data – User data to pass to callback function.
- filter – Pointer to a can_filter structure defining the filter.

Return values

- filter_id – on success.
- -ENOMEM – if there are no free filters.
- -EINVAL – if the requested filter type is invalid.
- -ENOTSUP – if the requested filter type is not supported.

int can_add_rx_filter_msgq(const struct device *dev, struct k_msgq *msgq, const struct can_filter *filter)

Wrapper function for adding a message queue for a given filter.

Wrapper function for can_add_rx_filter() which puts received CAN frames matching the filter in a message queue instead of calling a callback.

If a frame matches more than one attached filter, the priority of the match is hardware dependent.

The same message queue can be used for multiple filters.
**Note:** The message queue must be initialized before calling this function and the caller must have appropriate permissions on it.

### Parameters
- `dev` – Pointer to the device structure for the driver instance.
- `msgq` – Pointer to the already initialized `k_msgq` struct.
- `filter` – Pointer to a `can_filter` structure defining the filter.

### Return values
- `filter_id` – on success.
- `-ENOSPC` – if there are no free filters.
- `-ENOTSUP` – if the requested filter type is not supported.

```c
void can_remove_rx_filter(const struct device *dev, int filter_id)
```

Remove a CAN RX filter.

This routine removes a CAN RX filter based on the filter ID returned by `can_add_rx_filter()` or `can_add_rx_filter_msgq()`.

### Parameters
- `dev` – Pointer to the device structure for the driver instance.
- `filter_id` – Filter ID

```c
int can_get_max_filters(const struct device *dev, bool ide)
```

Get maximum number of RX filters.

Get the maximum number of concurrent RX filters for the CAN controller.

### Parameters
- `dev` – Pointer to the device structure for the driver instance.
- `ide` – Get the maximum standard (11-bit) CAN ID filters if false, or extended (29-bit) CAN ID filters if true.

### Return values
- Positive – number of maximum concurrent filters.
- `-EIO` – General input/output error.
- `-ENOSYS` – If this function is not implemented by the driver.

```c
CAN_MSGQ_DEFINE(name, max_frames)
```

Statically define and initialize a CAN RX message queue.

The message queue's ring buffer contains space for `max_frames` CAN frames.

### See also:
- `can_add_rx_filter_msgq()`

### Parameters
- `name` – Name of the message queue.
- `max_frames` – Maximum number of CAN frames that can be queued.
CAN bus error reporting and handling

int can_get_state(const struct device *dev, enum can_state *state, struct can_bus_err_cnt *err_cnt)

Get current CAN controller state.

Returns the current state and optionally the error counter values of the CAN controller.

Parameters

- dev – Pointer to the device structure for the driver instance.
- state – [out] Pointer to the state destination enum or NULL.
- err_cnt – [out] Pointer to the err_cnt destination structure or NULL.

Return values

- 0 – If successful.
- -EIO – General input/output error, failed to get state.

int can_recover(const struct device *dev, k_timeout_t timeout)

Recover from bus-off state.

Recover the CAN controller from bus-off state to error-active state.

Note: CONFIG_CAN_AUTO_BUS_OFF_RECOVERY must be deselected for this function to be available.

Parameters

- dev – Pointer to the device structure for the driver instance.
- timeout – Timeout for waiting for the recovery or K_FOREVER.

Return values

- 0 – on success.
- -ENETDOWN – if the CAN controller is in stopped state.
- -EAGAIN – on timeout.

static inline void can_set_state_change_callback(const struct device *dev, can_state_change_callback_t callback, void *user_data)

Set a callback for CAN controller state change events.

Set the callback for CAN controller state change events. The callback function will be called in interrupt context.

Only one callback can be registered per controller. Calling this function again overrides any previously registered callback.

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback – Callback function.
- user_data – User data to pass to callback function.
CAN utility functions

static inline uint8_t can_dlc_to_bytes(uint8_t dlc)
Convert from Data Length Code (DLC) to the number of data bytes.

**Parameters**
- dlc – Data Length Code (DLC).

**Return values**
Number – of bytes.

static inline uint8_t can_bytes_to_dlc(uint8_t num_bytes)
Convert from number of bytes to Data Length Code (DLC)

**Parameters**
- num_bytes – Number of bytes.

**Return values**
Data – Length Code (DLC).

CAN frame definitions

CAN_STD_ID_MASK
Bit mask for a standard (11-bit) CAN identifier.

CAN_MAX_STD_ID
Maximum value for a standard (11-bit) CAN identifier.

CAN_EXT_ID_MASK
Bit mask for an extended (29-bit) CAN identifier.

CAN_MAX_EXT_ID
Maximum value for an extended (29-bit) CAN identifier.

CAN_MAX_DLC
Maximum data length code for CAN 2.0A/2.0B.

CANFD_MAX_DLC
Maximum data length code for CAN-FD.

CAN controller mode flags

CAN_MODE_NORMAL
Normal mode.

CAN_MODE_LOOPBACK
Controller is in loopback mode (receives own frames).

CAN_MODE_LISTENONLY
Controller is not allowed to send dominant bits.
CAN_MODE_FD
Controller allows transmitting/receiving CAN-FD frames.

CAN_MODE_ONE_SHOT
Controller does not retransmit in case of lost arbitration or missing ACK

CAN_MODE_3_SAMPLES
Controller uses triple sampling mode

CAN frame flags

CAN_FRAME_IDE
Frame uses extended (29-bit) CAN ID

CAN_FRAME_RTR
Frame is a Remote Transmission Request (RTR)

CAN_FRAME_FDF
Frame uses CAN-FD format (FDF)

CAN_FRAME_BRS
Frame uses CAN-FD Baud Rate Switch (BRS). Only valid in combination with CAN_FRAME_FDF.

CAN filter flags

CAN_FILTER_IDE
Filter matches frames with extended (29-bit) CAN IDs

CAN_FILTER_RTR
Filter matches Remote Transmission Request (RTR) frames

CAN_FILTER_DATA
Filter matches data frames

Defines

CAN_STATS_BIT0_ERROR_INC(dev_)
Increment the bit0 error counter for a CAN device.
The bit0 error counter is incremented when the CAN controller is unable to transmit a dominant bit.

Parameters

- dev_ – Pointer to the device structure for the driver instance.
CAN_STATS_BIT1_ERROR_INC(dev_
)  
Increment the bit1 (recessive) error counter for a CAN device. 
The bit1 error counter is incremented when the CAN controller is unable to transmit a recessive bit.

Parameters 
• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_STUFF_ERROR_INC(dev_
)  
Increment the stuffing error counter for a CAN device. 
The stuffing error counter is incremented when the CAN controller detects a bit stuffing error.

Parameters 
• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_CRC_ERROR_INC(dev_
)  
Increment the CRC error counter for a CAN device. 
The CRC error counter is incremented when the CAN controller detects a frame with an invalid CRC.

Parameters 
• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_FORM_ERROR_INC(dev_
)  
Increment the form error counter for a CAN device. 
The form error counter is incremented when the CAN controller detects a fixed-form bit field containing illegal bits.

Parameters 
• dev_ – Pointer to the device structure for the driver instance.

CAN_STATS_ACK_ERROR_INC(dev_
)  
Increment the acknowledge error counter for a CAN device. 
The acknowledge error counter is incremented when the CAN controller does not monitor a dominant bit in the ACK slot.

Parameters 
• dev_ – Pointer to the device structure for the driver instance.

CAN_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)  
Like DEVICE_DT_DEFINE() with CAN device specifics.

Defines a device which implements the CAN API. May generate a custom device_state container struct and init_fn wrapper when needed depending on CONFIG_CAN_STATS.

Parameters 
• node_id – The devicetree node identifier. 
• init_fn – Name of the init function of the driver. 
• pm – PM device resources reference (NULL if device does not use PM). 
• data – Pointer to the device’s private data. 
• config – The address to the structure containing the configuration information for this instance of the driver. 
• level – The initialization level. See SYS_INIT() for details.
• `prio` – Priority within the selected initialization level. See `SYS_INIT()` for details.

• `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

`CAN_DEVICE_DT_INST_DEFINE(inst, ...)`

Like `CAN_DEVICE_DT_DEFINE()` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

• `inst` – Instance number. This is replaced by `DT_DRV_COMPAT(inst)` in the call to `CAN_DEVICE_DT_DEFINE()`.

• `...` – Other parameters as expected by `CAN_DEVICE_DT_DEFINE()`.

**Typedefs**

typedef `uint32_t can_mode_t`

Provides a type to hold CAN controller configuration flags.

The lower 24 bits are reserved for common CAN controller mode flags. The upper 8 bits are reserved for CAN controller/driver specific flags.

**See also:**

`CAN_MODE_FLAGS`.

typedef `void (*can_tx_callback_t)(const struct device *dev, int error, void *user_data)`

Defines the application callback handler function signature.

**Param dev**

Pointer to the device structure for the driver instance.

**Param error**

Status of the performed send operation. See the list of return values for `can_send()` for value descriptions.

**Param user_data**

User data provided when the frame was sent.

typedef `void (*can_rx_callback_t)(const struct device *dev, struct can_frame *frame, void *user_data)`

Defines the application callback handler function signature for receiving.

**Param dev**

Pointer to the device structure for the driver instance.

**Param frame**

Received frame.

**Param user_data**

User data provided when the filter was added.

typedef `void (*can_state_change_callback_t)(const struct device *dev, enum can_state state, struct can_bus_err_cnt err_cnt, void *user_data)`

Defines the state change callback handler function signature.

**Param dev**

Pointer to the device structure for the driver instance.
**Param state**  
State of the CAN controller.

**Param err_cnt**  
CAN controller error counter values.

**Param user_data**  
User data provided the callback was set.

**Enums**

```c
enum can_state

    Defines the state of the CAN controller.

    **Values:**

    enumerator CAN_STATE_ERROR_ACTIVE  
    Error-active state (RX/TX error count < 96).

    enumerator CAN_STATE_ERROR_WARNING  
    Error-warning state (RX/TX error count < 128).

    enumerator CAN_STATE_ERROR_PASSIVE  
    Error-passive state (RX/TX error count < 256).

    enumerator CAN_STATE_BUS_OFF  
    Bus-off state (RX/TX error count >= 256).

    enumerator CAN_STATE_STOPPED  
    CAN controller is stopped and does not participate in CAN communication.
```

**Public Members**

```c
struct can_frame

    #include <can.h> CAN frame structure.
```

**See also:**

`CAN_FRAME_FLAGS`
uint16_t timestamp
    Captured value of the free-running timer in the CAN controller when this frame was received. The timer is incremented every bit time and captured at the start of frame bit (SOF).

Note: CONFIG_CAN_RX_TIMESTAMP must be selected for this field to be available.

union can_frame [anonymous] [anonymous]
    The frame payload data.

struct can_filter
    #include <can.h> CAN filter structure.

Public Members

uint32_t id
    CAN identifier to match.

uint32_t mask
    CAN identifier matching mask. If a bit in this mask is 0, the value of the corresponding bit in the id field is ignored by the filter.

uint8_t flags
    Flags.
    See also:
    CAN_FILTER_FLAGS.

struct can_bus_err_cnt
    #include <can.h> CAN controller error counters.

Public Members

uint8_t tx_err_cnt
    Value of the CAN controller transmit error counter.

uint8_t rx_err_cnt
    Value of the CAN controller receive error counter.

struct can_timing
    #include <can.h> CAN bus timing structure.

This struct is used to pass bus timing values to the configuration and bitrate calculation functions.

The propagation segment represents the time of the signal propagation. Phase segment 1 and phase segment 2 define the sampling point. The prop_seg and phase_seg1 values affect the sampling point in the same way and some controllers only have a register for the sum of those two. The sync segment always has a length of 1 time quantum (see below).
1 time quantum (tq) has the length of $1/(\text{core}\_\text{clock} / \text{prescaler})$. The bitrate is defined by the core clock divided by the prescaler and the sum of the segments:

$$br = \frac{\text{core}\_\text{clock} / \text{prescaler}}{1 + \text{prop}\_\text{seg} + \text{phase}\_\text{seg1} + \text{phase}\_\text{seg2}}$$

The Synchronization Jump Width (SJW) defines the amount of time quanta the sample point can be moved. The sample point is moved when resynchronization is needed.

### Public Members

- **uint16_t sjw**
  
  Synchronisation jump width.

- **uint16_t prop_seg**
  
  Propagation segment.

- **uint16_t phase_seg1**
  
  Phase segment 1.

- **uint16_t phase_seg2**
  
  Phase segment 2.

- **uint16_t prescaler**
  
  Prescaler value.

- **struct can_device_state**

  #include <can.h> CAN specific device state which allows for CAN device class specific additions.

### CAN Transceiver API Reference

#### group can_transceiver

CAN Transceiver Driver APIs.

#### Functions

- **static inline int can_transceiver_enable(const struct device *dev)**

  Enable CAN transceiver.

  Enable the CAN transceiver.

  **See also:**

  `can_start()`
Note: The CAN transceiver is controlled by the CAN controller driver and should not normally be controlled by the application.

Parameters

• dev – Pointer to the device structure for the driver instance.

Return values

• 0 – If successful.
• -EIO – General input/output error, failed to enable device.

```c
static inline int can_transceiver_disable(const struct device *dev)
```

Disable CAN transceiver.

Disable the CAN transceiver.

See also:

can_stop()

Note: The CAN transceiver is controlled by the CAN controller driver and should not normally be controlled by the application.

Parameters

• dev – Pointer to the device structure for the driver instance.

Return values

• 0 – If successful.
• -EIO – General input/output error, failed to disable device.

ISO-TP Transport Protocol

Overview  ISO-TP is a transport protocol defined in the ISO-Standard ISO15765-2 Road vehicles - Diagnostic communication over Controller Area Network (DoCAN). Part2: Transport protocol and network layer services. As its name already implies, it is originally designed, and still used in road vehicle diagnostic over Controller Area Networks. Nevertheless, it’s not limited to applications in road vehicles or the automotive domain.

This transport protocol extends the limited payload data size for classical CAN (8 bytes) and CAN-FD (64 bytes) to theoretically four gigabytes. Additionally, it adds a flow control mechanism to influence the sender’s behavior. ISO-TP segments packets into small fragments depending on the payload size of the CAN frame. The header of those segments is called Protocol Control Information (PCI).

Packets smaller or equal to seven bytes on Classical CAN are called single-frames (SF). They don’t need to fragment and do not have any flow-control.

Packets larger than that are segmented into a first-frame (FF) and as many consecutive-frames as required. The FF contains information about the length of the entire payload data and additionally, the
first few bytes of payload data. The receiving peer sends back a flow-control-frame (FC) to either deny, postpone, or accept the following consecutive frames. The FC also defines the conditions of sending, namely the block-size (BS) and the minimum separation time between frames (STmin). The block size defines how many CF the sender is allowed to send, before he has to wait for another FC.

API Reference

**group can_isotp**

CAN ISO-TP Interface.

**Defines**

- **ISOTP_N_OK**
  Completed successfully

- **ISOTP_N_TIMEOUT_A**
  Ar/As has timed out

- **ISOTP_N_TIMEOUT_BS**
  Reception of next FC has timed out

- **ISOTP_N_TIMEOUT_CR**
  Cr has timed out

- **ISOTP_N_WRONG_SN**
  Unexpected sequence number

- **ISOTP_N_INVALID_FS**
  Invalid flow status received

- **ISOTP_N_UNEXP_PDU**
  Unexpected PDU received

- **ISOTP_N_WAIT_OVRN**
  Maximum number of WAIT flowStatus PDUs exceeded

- **ISOTP_N_BUFFER_OVERFLW**
  FlowStatus OVFLW PDU was received

- **ISOTP_N_ERROR**
  General error

7.3. Peripherals
ISOTP_NO_FREE_FILTER
    Implementation specific errors Can't bind or send because the CAN device has no filter left

ISOTP_NO_NET_BUF_LEFT
    No net buffer left to allocate

ISOTP_NO_BUF_DATA_LEFT
    Not sufficient space in the buffer left for the data

ISOTP_NO_CTX_LEFT
    No context buffer left to allocate

ISOTP_RECV_TIMEOUT
    Timeout for recv

ISOTP_FIXED_ADDR_SA_POS
    Position of fixed source address (SA)

ISOTP_FIXED_ADDR_SA_MASK
    Mask to obtain fixed source address (SA)

ISOTP_FIXED_ADDR_TA_POS
    Position of fixed target address (TA)

ISOTP_FIXED_ADDR_TA_MASK
    Mask to obtain fixed target address (TA)

ISOTP_FIXED_ADDR_PRIO_POS
    Position of priority in fixed addressing mode

ISOTP_FIXED_ADDR_PRIO_MASK
    Mask for priority in fixed addressing mode

ISOTP_FIXED_ADDR_RX_MASK

Typedefs

typedef void (*isotp_tx_callback_t)(int error_nr, void *arg)

Functions

int isotp_bind(struct isotp_recv_ctx *ctx, const struct device *can_dev, const struct isotp_msg_id *rx_addr, const struct isotp_msg_id *tx_addr, const struct isotp_fc_opts *opts, k_timeout_t timeout)

Bind an address to a receiving context.

This function binds an RX and TX address combination to an RX context. When data arrives from the specified address, it is buffered and can be read by calling isotp_recv. When calling this routine, a filter is applied in the CAN device, and the context is initialized. The context must be valid until calling unbind.
Parameters

- `ctx` – Context to store the internal states.
- `can_dev` – The CAN device to be used for sending and receiving.
- `rx_addr` – Identifier for incoming data.
- `tx_addr` – Identifier for FC frames.
- `opts` – Flow control options.
- `timeout` – Timeout for FF SF buffer allocation.

Return values

- ISOTP_N_OK – on success
- ISOTP_NO_FREE_FILTER – if CAN device has no filters left.

```c
void isotp_unbind(struct isotp_recv_ctx *ctx)
```

Unbind a context from the interface.

This function removes the binding from isotp_bind. The filter is detached from the CAN device, and if a transmission is ongoing, buffers are freed. The context can be discarded safely after calling this function.

Parameters

- `ctx` – Context that should be unbound.

```c
int isotp_recv(struct isotp_recv_ctx *ctx, uint8_t *data, size_t len, k_timeout_t timeout)
```

Read out received data from fifo.

This function reads the data from the receive FIFO of the context. It blocks if the FIFO is empty. If an error occurs, the function returns a negative number and leaves the data buffer unchanged.

Parameters

- `ctx` – Context that is already bound.
- `data` – Pointer to a buffer where the data is copied to.
- `len` – Size of the buffer.
- `timeout` – Timeout for incoming data.

Return values

- Number – of bytes copied on success
- ISOTP_WAIT_TIMEOUT – when “timeout” timed out
- ISOTP_N_* – on error

```c
int isotp_recv_net(struct isotp_recv_ctx *ctx, struct net_buf **buffer, k_timeout_t timeout)
```

Get the net buffer on data reception.

This function reads incoming data into net-buffers. It blocks until the entire packet is received, BS is reached, or an error occurred. If BS was zero, the data is in a single `net_buf`. Otherwise, the data is fragmented in chunks of BS size. The net-buffers are referenced and must be freed with net_buf_unref after the data is processed.

Parameters

- `ctx` – Context that is already bound.
- `buffer` – Pointer where the `net_buf` pointer is written to.
- `timeout` – Timeout for incoming data.

Return values
int isotp_send(struct isotp_send_ctx *ctx, const struct device *can_dev, const uint8_t *data, size_t len, const struct isotp_msg_id *tx_addr, const struct isotp_msg_id *rx_addr, isotp_tx_callback_t complete_cb, void *cb_arg)

Send data.

This function is used to send data to a peer that listens to the tx_addr. An internal work-queue is used to transfer the segmented data. Data and context must be valid until the transmission has finished. If a complete_cb is given, this function is non-blocking, and the callback is called on completion with the return value as a parameter.

**Parameters**

- `ctx` – Context to store the internal states.
- `can_dev` – The CAN device to be used for sending and receiving.
- `data` – Data to be sent.
- `len` – Length of the data to be sent.
- `rx_addr` – Identifier for FC frames.
- `tx_addr` – Identifier for outgoing frames the receiver listens on.
- `complete_cb` – Function called on completion or NULL.
- `cb_arg` – Argument passed to the complete callback.

**Return values**

- `ISOTP_N_OK` – on success
- `ISOTP_N_*` – on error

`struct isotp_msg_id`

```c
#include <isotp.h>
```

ISO-TP message id struct.

Used to pass addresses to the bind and send functions.

**Public Members**

```c
union isotp_msg_id.[anonymous] [anonymous]
```

CAN identifier

If ISO-TP fixed addressing is used, isotp_bind ignores SA and priority sections and modifies TA section in flow control frames.

```c
uint8_t ext_addr
```

ISO-TP extended address (if used)

```c
uint8_t ide
```

Indicates the CAN identifier type (0 for standard or 1 for extended)

```c
uint8_t use_ext_addr
```

Indicates if ISO-TP extended addressing is used
### Public Members

- **uint8_t bs**
  
  Block size. Number of CF PDUs before next CF is sent

- **uint8_t stmin**
  
  Minimum separation time. Min time between frames

### 7.3.4 Coredump Device

**Overview**

The coredump device is a pseudo-device driver with two types. A COREDUMP_TYPE_MEMCPY type exposes device tree bindings for memory address/size values to be included in any dump. And the driver exposes an API to add/remove dump memory regions at runtime. A COREDUMP_TYPE_CALLBACK device requires exactly one entry in the memory-regions array with a size of 0 and a desired size. The driver will statically allocate memory of the desired size and provide an API to register a callback function to fill that memory when a dump occurs.

**Configuration Options**

Related configuration options:

- CONFIG_COREDUMP_DEVICE

**API Reference**

*group coredump_device_interface*

Coredump pseudo-device driver APIs.

**Typedefs**

typedef void (*coredump_dump_callback_t)(uintptr_t dump_area, size_t dump_area_size)

Callback that occurs at dump time, data copied into dump_area will be included in the dump that is generated.

**Param dump_area**

Pointer to area to copy data into for inclusion in dump

**Param dump_area_size**

Size of available memory at dump_area
Functions

static inline bool coredump_device_register_memory(const struct device *dev, struct coredump_mem_region_node *region)

Register a region of memory to be stored in core dump at the time it is generated.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `region` – Struct describing memory to be collected

**Returns**

true if registration succeeded

false if registration failed

static inline bool coredump_device_unregister_memory(const struct device *dev, struct coredump_mem_region_node *region)

Unregister a region of memory to be stored in core dump at the time it is generated.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `region` – Struct describing memory to be collected

**Returns**

true if unregistration succeeded

false if unregistration failed

static inline bool coredump_device_register_callback(const struct device *dev, coredump_dump_callback_t callback)

Register a callback to be invoked at dump time.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `callback` – Callback to be invoked at dump time

**Returns**

true if registration succeeded

false if registration failed

```
struct coredump_mem_region_node
#include <coredump.h> Structure describing a region in memory that may be stored in core dump at the time it is generated.

Instances of this are passed to the coredump_device_register_memory() and coredump_device_unregister_memory() functions to indicate addition and removal of memory regions to be captured
```

Public Members

```
sys_snodet node
Node of single-linked list, do not modify
```
uintptr_t start
Address of start of memory region

size_t size
Size of memory region

7.3.5 Counter

Overview

API Reference

group counter_interface
Counter Interface.

typedef void (*counter_alarm_callback_t)(const struct device *dev, uint8_t chan_id, uint32_t ticks, void *user_data)
Alarm callback.

    Param dev
    Pointer to the device structure for the driver instance.

    Param chan_id
    Channel ID.

    Param ticks
    Counter value that triggered the alarm.

    Param user_data
    User data.

typedef void (*counter_top_callback_t)(const struct device *dev, void *user_data)
Callback called when counter turns around.

    Param dev
    Pointer to the device structure for the driver instance.

    Param user_data
    User data provided in counter_set_top_value.

typedef int (*counter_api_start)(const struct device *dev)

typedef int (*counter_api_stop)(const struct device *dev)

typedef int (*counter_api_get_value)(const struct device *dev, uint32_t *ticks)

typedef int (*counter_api_get_value_64)(const struct device *dev, uint64_t *ticks)

typedef int (*counter_api_set_alarm)(const struct device *dev, uint8_t chan_id, const struct counter_alarm_cfg *alarm_cfg)
typedef int (*counter_api_cancel_alarm)(const struct device *dev, uint8_t chan_id)

typedef int (*counter_api_set_top_value)(const struct device *dev, const struct counter_top_cfg *cfg)

typedef uint32_t (*counter_api_get_pending_int)(const struct device *dev)

typedef uint32_t (*counter_api_get_top_value)(const struct device *dev)

typedef uint32_t (*counter_api_get_guard_period)(const struct device *dev, uint32_t flags)

typedef int (*counter_api_set_guard_period)(const struct device *dev, uint32_t ticks, uint32_t flags)

typedef uint32_t (*counter_api_get_freq)(const struct device *dev)

Functions

bool counter_is_counting_up(const struct device *dev)

Function to check if counter is counting up.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.

Return values

• true – if counter is counting up.
• false – if counter is counting down.

uint8_t counter_get_num_of_channels(const struct device *dev)

Function to get number of alarm channels.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.

Returns

Number of alarm channels.

uint32_t counter_get_frequency(const struct device *dev)

Function to get counter frequency.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.

Returns

Frequency of the counter in Hz, or zero if the counter does not have a fixed frequency.

uint32_t counter_us_to_ticks(const struct device *dev, uint64_t us)

Function to convert microseconds to ticks.

Parameters

• dev – [in] Pointer to the device structure for the driver instance.
Returns
Converted ticks. Ticks will be saturated if exceed 32 bits.

uint64_t counter_ticks_to_us(const struct device *dev, uint32_t ticks)
Function to convert ticks to microseconds.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• ticks – [in] Ticks.

Returns
Converted microseconds.

uint32_t counter_get_max_top_value(const struct device *dev)
Function to retrieve maximum top value that can be set.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Returns
Max top value.

int counter_start(const struct device *dev)
Start counter device in free running mode.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• Negative – errno code if failure.

int counter_stop(const struct device *dev)
Stop counter device.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• -ENOTSUP – if the device doesn’t support stopping the counter.

int counter_get_value(const struct device *dev, uint32_t *ticks)
Get current counter value.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ticks – Pointer to where to store the current counter value

Return values
• 0 – If successful.
• Negative – error code on failure getting the counter value

int counter_get_value_64(const struct device *dev, uint64_t *ticks)
Get current counter 64-bit value.

Parameters
• dev – Pointer to the device structure for the driver instance.
ticks – Pointer to where to store the current counter value

Return values
• 0 – If successful.
• Negative – error code on failure getting the counter value

int counter_set_channel_alarm(const struct device *dev, uint8_t chan_id, const struct counter_alarm_cfg *alarm_cfg)

Set a single shot alarm on a channel.
After expiration alarm can be set again, disabling is not needed. When alarm expiration handler is called, channel is considered available and can be set again in that context.

Note: API is not thread safe.

Parameters
• dev – Pointer to the device structure for the driver instance.
• chan_id – Channel ID.
• alarm_cfg – Alarm configuration.

Return values
• 0 – If successful.
• -ENOTSUP – if request is not supported (device does not support interrupts or requested channel).
• -EINVAL – if alarm settings are invalid.
• -ETIME – if absolute alarm was set too late.
• -EBUSY – if alarm is already active.

int counter_cancel_channel_alarm(const struct device *dev, uint8_t chan_id)

Cancel an alarm on a channel.

Note: API is not thread safe.

Parameters
• dev – Pointer to the device structure for the driver instance.
• chan_id – Channel ID.

Return values
• 0 – If successful.
• -ENOTSUP – if request is not supported or the counter was not started yet.

int counter_set_top_value(const struct device *dev, const struct counter_top_cfg *cfg)

Set counter top value.
Function sets top value and optionally resets the counter to 0 or top value depending on counter direction. On turnaround, counter can be reset and optional callback is periodically called. Top value can only be changed when there is no active channel alarm.

COUNTER_TOP_CFG_DONT_RESET prevents counter reset. When counter is running while top value is updated, it is possible that counter progresses outside the new top value.

Note: API is not thread safe.
value. In that case, error is returned and optionally driver can reset the counter (see COUNTER_TOP_CFG_RESET_WHEN_LATE).

Parameters
• dev – Pointer to the device structure for the driver instance.
• cfg – Configuration. Cannot be NULL.

Return values
• 0 – If successful.
• -ENOTSUP – if request is not supported (e.g. top value cannot be changed or counter cannot/must be reset during top value update).
• -EBUSY – if any alarm is active.
• -ETIME – if COUNTER_TOP_CFG_DONT_RESET was set and new top value is smaller than current counter value (counter counting up).

int counter_get_pending_int(const struct device *dev)
Function to get pending interrupts.

The purpose of this function is to return the interrupt status register for the device. This is especially useful when waking up from low power states to check the wake up source.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 1 – if any counter interrupt is pending.
• 0 – if no counter interrupt is pending.

uint32_t counter_get_top_value(const struct device *dev)
Function to retrieve current top value.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Returns
Top value.

int counter_set_guard_period(const struct device *dev, uint32_t ticks, uint32_t flags)
Set guard period in counter ticks.

Setting non-zero guard period enables detection of setting absolute alarm too late. It limits how far in the future absolute alarm can be set. Detection of too late setting is vital since if it is not detected alarm is delayed by full period of the counter (up to 32 bits). Because of the wrapping, it is impossible to distinguish alarm which is short in the past from alarm which is targeted to expire after full counter period. In order to detect too late setting, longest possible alarm is limited. Absolute value cannot exceed: (now + top_value - guard_period) % top_value.

Guard period depends on application and counter frequency. If it is expected that absolute alarms setting might be delayed then guard period should exceed maximal potential delay. If use case allows, guard period can be set very high (e.g. half of the counter top value).

After initialization guard period is set to 0 and late detection is disabled.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ticks – Guard period in counter ticks.
• flags – See Counter guard period flags.

Return values
• 0 – if successful.
• -ENOTSUP – if function or flags are not supported.
• -EINVAL – if ticks value is invalid.

uint32_t counter_get_guard_period(const struct device *dev, uint32_t flags)

Return guard period.
See counter_set_guard_period.

Parameters
• dev – Pointer to the device structure for the driver instance.
• flags – See Counter guard period flags.

Returns
Guard period given in counter ticks or 0 if function or flags are not supported.

struct counter_alarm_cfg
#include <counter.h> Alarm callback structure.

Param callback
Callback called on alarm (cannot be NULL).

Param ticks
Number of ticks that triggers the alarm. It can be relative (to now) or absolute value (see COUNTER_ALARM_CFG_ABSOLUTE). Absolute alarm cannot be set further in future than top value decremented by the guard period. Relative alarm ticks cannot exceed current top value (see counter_get_top_value). If counter is clock driven then ticks can be converted to microseconds (see counter_ticks_to_us). Alternatively, counter implementation may count asynchronous events.

Param user_data
User data returned in callback.

Param flags
Alarm flags. See Alarm configuration flags.

struct counter_top_cfg
#include <counter.h> Top value configuration structure.

Param ticks
Top value.

Param callback
Callback function. Can be NULL.

Param user_data
User data passed to callback function. Not valid if callback is NULL.

Param flags
Flags. See Flags used by.

struct counter_config_info
#include <counter.h> Structure with generic counter features.

Param max_top_value
Maximal (default) top value on which counter is reset (cleared or reloaded).
**Param freq**
Frequency of the source clock if synchronous events are counted.

**Param flags**
Flags. See Counter device capabilities.

**Param channels**
Number of channels that can be used for setting alarm, see `counter_set_channel_alarm`.

```
struct counter_driver_api
#include <counter.h>
```

### 7.3.6 Clock Control

**Overview**

The clock control API provides access to clocks in the system, including the ability to turn them on and off.

**Configuration Options**

Related configuration options:
- `CONFIG_CLOCK_CONTROL`

**API Reference**

```
group clock_control_interface
    Clock Control Interface.

Defines

CLOCK_CONTROL_SUBSYS_ALL

Typedefs

typedef void *clock_control_subsys_t
clock_control_subsys_t is a type to identify a clock controller sub-system. Such data pointed is opaque and relevant only to the clock controller driver instance being used.

typedef void *clock_control_subsys_rate_t
clock_control_subsys_rate_t is a type to identify a clock controller sub-system rate. Such data pointed is opaque and relevant only to set the clock controller rate of the driver instance being used.

typedef void (*clock_control_cb_t)(const struct device *dev, clock_control_subsys_t subsys, void *user_data)
Callback called on clock started.
```
**Param dev**
- Device structure whose driver controls the clock.

**Param subsys**
- Opaque data representing the clock.

**Param user_data**
- User data.

```c
typedef int (*clock_control)(const struct device *dev, clock_control_subsys_t sys)
```

```c
typedef int (*clock_control_get)(const struct device *dev, clock_control_subsys_t sys, uint32_t *rate)
```

```c
typedef int (*clock_control_async_on_fn)(const struct device *dev, clock_control_subsys_t sys, clock_control_cb_t cb, void *user_data)
```

```c
typedef enum clock_control_status (*clock_control_get_status_fn)(const struct device *dev, clock_control_subsys_t sys)
```

```c
typedef int (*clock_control_set)(const struct device *dev, clock_control_subsys_t sys, clock_control_subsys_rate_t rate)
```

```c
typedef int (*clock_control_configure_fn)(const struct device *dev, clock_control_subsys_t sys, void *data)
```

### Enums

**enum clock_control_status**
- Current clock status.

**Values:**

- enumerator CLOCK_CONTROL_STATUS_STARTING
- enumerator CLOCK_CONTROL_STATUS_OFF
- enumerator CLOCK_CONTROL_STATUS_ON
- enumerator CLOCK_CONTROL_STATUS_UNKNOWN

### Functions

```c
static inline int clock_control_on(const struct device *dev, clock_control_subsys_t sys)
```

Enable a clock controlled by the device.

On success, the clock is enabled and ready when this function returns. This function may sleep, and thus can only be called from thread context.

Use `clock_control_async_on()` for non-blocking operation.

#### Parameters

- dev – Device structure whose driver controls the clock.
sys – Opaque data representing the clock.

Returns
0 on success, negative errno on failure.

static inline int clock_control_off(const struct device *dev, clock_control_subsys_t sys)
Disable a clock controlled by the device.
This function is non-blocking and can be called from any context. On success, the clock is
disabled when this function returns.

Parameters
• dev – Device structure whose driver controls the clock
• sys – Opaque data representing the clock

Returns
0 on success, negative errno on failure.

static inline int clock_control_async_on(const struct device *dev, clock_control_subsys_t sys,
clock_control_cb_t cb, void *user_data)
Request clock to start with notification when clock has been started.
Function is non-blocking and can be called from any context. User callback is called when
clock is started.

Parameters
• dev – Device.
• sys – A pointer to an opaque data representing the sub-system.
• cb – Callback.
• user_data – User context passed to the callback.

Return values
• 0 – if start is successfully initiated.
• -EALREADY – if clock was already started and is starting or running.
• -ENOTSUP – If the requested mode of operation is not supported.
• -ENOSYS – if the interface is not implemented.
• other – negative errno on vendor specific error.

static inline enum clock_control_status clock_control_get_status(const struct device *dev,
clock_control_subsys_t sys)
Get clock status.

Parameters
• dev – Device.
• sys – A pointer to an opaque data representing the sub-system.

Returns
Status.

static inline int clock_control_get_rate(const struct device *dev, clock_control_subsys_t sys,
uint32_t *rate)
Obtain the clock rate of given sub-system.

Parameters
• dev – Pointer to the device structure for the clock controller driver instance
• sys – A pointer to an opaque data representing the sub-system
rate – [out] Subsystem clock rate

Return values
• 0 – on successful rate reading.
• -EAGAIN – if rate cannot be read. Some drivers do not support returning the rate when the clock is off.
• -ENOTSUP – if reading the clock rate is not supported for the given sub-system.
• -ENOSYS – if the interface is not implemented.

static inline int clock_control_set_rate(const struct device *dev, clock_control_subsys_t sys, clock_control_subsys_rate_t rate)

Set the rate of the clock controlled by the device.
On success, the new clock rate is set and ready when this function returns. This function may sleep, and thus can only be called from thread context.

Parameters
• dev – Device structure whose driver controls the clock.
• sys – Opaque data representing the clock.
• rate – Opaque data representing the clock rate to be used.

Return values
• -EALREADY – if clock was already in the given rate.
• -ENOTSUP – If the requested mode of operation is not supported.
• -ENOSYS – if the interface is not implemented.
• other – negative errno on vendor specific error.

static inline int clock_control_configure(const struct device *dev, clock_control_subsys_t sys, void *data)

Configure a source clock.
This function is non-blocking and can be called from any context. On success, the selected clock is configured as per caller's request.
It is caller's responsibility to ensure that subsequent calls to the API provide the right information to allows clock_control driver to perform the right action (such as using the right clock source on clock_control_get_rate call).
data is implementation specific and could be used to convey supplementary information required for expected clock configuration.

Parameters
• dev – Device structure whose driver controls the clock
• sys – Opaque data representing the clock
• data – Opaque data providing additional input for clock configuration

Return values
• 0 – On success
• -ENOSYS – If the device driver does not implement this call
• -errno – Other negative errno on failure.

struct clock_control_driver_api
#include <clock_control.h>
7.3.7 DAC

Overview

The DAC API provides access to Digital-to-Analog Converter (DAC) devices.

Configuration Options

Related configuration options:

- CONFIG_DAC

API Reference

**group dac_interface**

DAC driver APIs.

**Functions**

```c
int dac_channel_setup(const struct device *dev, const struct dac_channel_cfg *channel_cfg)
```

Configure a DAC channel.

It is required to call this function and configure each channel before it is selected for a write request.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- channel_cfg – Channel configuration.

**Return values**

- 0 – On success.
- -EINVAL – If a parameter with an invalid value has been provided.
- -ENOTSUP – If the requested resolution is not supported.

```c
int dac_write_value(const struct device *dev, uint8_t channel, uint32_t value)
```

Write a single value to a DAC channel.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- channel – Number of the channel to be used.
- value – Data to be written to DAC output registers.

**Return values**

- 0 – On success.
- -EINVAL – If a parameter with an invalid value has been provided.

```c
struct dac_channel_cfg
```

#include <dac.h> Structure for specifying the configuration of a DAC channel.

**Param channel_id**

Channel identifier of the DAC that should be configured.
Param resolution
Desired resolution of the DAC (depends on device capabilities).

7.3.8 Display Interface

API Reference

Generic Display Interface
group display_interface
   Display Interface.

Typedefs

typedef int (*display_blanking_on_api)(const struct device *dev)
   Callback API to turn on display blanking See display_blanking_on() for argument description.

typedef int (*display_blanking_off_api)(const struct device *dev)
   Callback API to turn off display blanking See display_blanking_off() for argument description.

typedef int (*display_write_api)(const struct device *dev, const uint16_t x, const uint16_t y,
                         const struct display_buffer_descriptor *desc, const void *buf)
   Callback API for writing data to the display See display_write() for argument description.

typedef int (*display_read_api)(const struct device *dev, const uint16_t x, const uint16_t y,
                         const struct display_buffer_descriptor *desc, void *buf)
   Callback API for reading data from the display See display_read() for argument description.

typedef void *(*display_get_framebuffer_api)(const struct device *dev)
   Callback API to get framebuffer pointer See display_get_framebuffer() for argument description.

typedef int (*display_set_brightness_api)(const struct device *dev, const uint8_t brightness)
   Callback API to set display brightness See display_set_brightness() for argument description.

typedef int (*display_set_contrast_api)(const struct device *dev, const uint8_t contrast)
   Callback API to set display contrast See display_set_contrast() for argument description.

typedef void (*display_get_capabilities_api)(const struct device *dev, struct display_capabilities *capabilities)
   Callback API to get display capabilities See display_get_capabilities() for argument description.

typedef int (*display_set_pixel_format_api)(const struct device *dev, const enum display_pixel_format pixel_format)
   Callback API to set pixel format used by the display See display_set_pixel_format() for argument description.

typedef int (*display_set_orientation_api)(const struct device *dev, const enum display_orientation orientation)
   Callback API to set orientation used by the display See display_set_orientation() for argument description.
Enums

display_pixel_format

Display pixel formats.
Display pixel format enumeration.
In case a pixel format consists out of multiple bytes the byte order is big endian.

Values:

- enumerator PIXEL_FORMAT_RGB_888 = BIT(0)
- enumerator PIXEL_FORMAT_MONO01 = BIT(1)
- enumerator PIXEL_FORMAT_MONO10 = BIT(2)
- enumerator PIXEL_FORMAT_ARGB_8888 = BIT(3)
- enumerator PIXEL_FORMAT_RGB_565 = BIT(4)
- enumerator PIXEL_FORMAT_BGR_565 = BIT(5)

display_screen_info

Values:

- enumerator SCREEN_INFO_MONO_VTILED = BIT(0)
  If selected, one octet represents 8 pixels ordered vertically, otherwise ordered horizontally.
- enumerator SCREEN_INFO_MONO_MSB_FIRST = BIT(1)
  If selected, the MSB represents the first pixel, otherwise MSB represents the last pixel.
- enumerator SCREEN_INFO_EPD = BIT(2)
  Electrophoretic Display.
- enumerator SCREEN_INFO_DOUBLE_BUFFER = BIT(3)
  Screen has two alternating ram buffers
- enumerator SCREEN_INFO_X_ALIGNMENT_WIDTH = BIT(4)
  Screen has x alignment constrained to width.

display_orientation

Enumeration with possible display orientation.

Values:

- enumerator DISPLAY_ORIENTATION_NORMAL
- enumerator DISPLAY_ORIENTATION_ROTATED_90
Functions

static inline int display_write(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, const void *buf)

Write data to display.

Parameters

• dev – Pointer to device structure
• x – x Coordinate of the upper left corner where to write the buffer
• y – y Coordinate of the upper left corner where to write the buffer
• desc – Pointer to a structure describing the buffer layout
• buf – Pointer to buffer array

Return values

0 – on success else negative errno code.

static inline int display_read(const struct device *dev, const uint16_t x, const uint16_t y, const struct display_buffer_descriptor *desc, void *buf)

Read data from display.

Parameters

• dev – Pointer to device structure
• x – x Coordinate of the upper left corner where to read from
• y – y Coordinate of the upper left corner where to read from
• desc – Pointer to a structure describing the buffer layout
• buf – Pointer to buffer array

Return values

0 – on success else negative errno code.

static inline void *display_get_framebuffer(const struct device *dev)

Get pointer to framebuffer for direct access.

Parameters

• dev – Pointer to device structure

Return values

Pointer – to frame buffer or NULL if direct framebuffer access is not supported

static inline int display_blanking_on(const struct device *dev)

Turn display blanking on.

This function blanks the complete display. The content of the frame buffer will be retained while blanking is enabled and the frame buffer will be accessible for read and write operations.

In case backlight control is supported by the driver the backlight is turned off. The backlight configuration is retained and accessible for configuration.

In case the driver supports display blanking the initial state of the driver would be the same as if this function was called.

Parameters
• dev – Pointer to device structure

**Return values**
0 – on success else negative errno code.

static inline int display_blanking_off(const struct device *dev)

Turn display blanking off.

Restore the frame buffer content to the display. In case backlight control is supported by the driver the backlight configuration is restored.

**Parameters**
• dev – Pointer to device structure

**Return values**
0 – on success else negative errno code.

static inline int display_set_brightness(const struct device *dev, uint8_t brightness)

Set the brightness of the display.

Set the brightness of the display in steps of 1/256, where 255 is full brightness and 0 is minimal.

**Parameters**
• dev – Pointer to device structure
• brightness – Brightness in steps of 1/256

**Return values**
0 – on success else negative errno code.

static inline int display_set_contrast(const struct device *dev, uint8_t contrast)

Set the contrast of the display.

Set the contrast of the display in steps of 1/256, where 255 is maximum difference and 0 is minimal.

**Parameters**
• dev – Pointer to device structure
• contrast – Contrast in steps of 1/256

**Return values**
0 – on success else negative errno code.

static inline void display_get_capabilities(const struct device *dev, struct display_capabilities *capabilities)

Get display capabilities.

**Parameters**
• dev – Pointer to device structure
• capabilities – Pointer to capabilities structure to populate

static inline int display_set_pixel_format(const struct device *dev, const enum display_pixel_format pixel_format)

Set pixel format used by the display.

**Parameters**
• dev – Pointer to device structure
• pixel_format – Pixel format to be used by display

**Return values**
0 – on success else negative errno code.
static inline int display_set_orientation(const struct device *dev, const enum display_orientation orientation)

Set display orientation.

**Parameters**

- dev – Pointer to device structure
- orientation – Orientation to be used by display

**Return values**

0 – on success else negative errno code.

struct display_capabilities

#include <display.h> Structure holding display capabilities.

**Public Members**

- uint16_t x_resolution
  - Display resolution in the X direction
- uint16_t y_resolution
  - Display resolution in the Y direction
- uint32_t supported_pixel_formats
  - Bitwise or of pixel formats supported by the display
- uint32_t screen_info
  - Information about display panel
- enum display_pixel_format current_pixel_format
  - Currently active pixel format for the display
- enum display_orientation current_orientation
  - Current display orientation

struct display_buffer_descriptor

#include <display.h> Structure to describe display data buffer layout.

**Public Members**

- uint32_t buf_size
  - Data buffer size in bytes
- uint16_t width
  - Data buffer row width in pixels
- uint16_t height
  - Data buffer column height in pixels
```c
uint16_t pitch
    Number of pixels between consecutive rows in the data buffer

struct display_driver_api
    #include <display.h> Display driver API API which a display driver should expose.

Grove LCD Display

group grove_display
    Grove display APIs.

Defines

GLCD_DS_DISPLAY_ON

GLCD_DS_DISPLAY_OFF

GLCD_DS_CURSOR_ON

GLCD_DS_CURSOR_OFF

GLCD_DS_BLINK_ON

GLCD_DS_BLINK_OFF

GLCD_IS_SHIFT_INCREMENT

GLCD_IS_SHIFT_DECREMENT

GLCD_IS_ENTRY_LEFT

GLCD_IS_ENTRY_RIGHT

GLCD_FS_8BIT_MODE

GLCD_FS_ROWS_2

GLCD_FS_ROWS_1

GLCD_FS_DOT_SIZE_BIG

GLCD_FS_DOT_SIZE_LITTLE

GROVE_RGB_WHITE
```

7.3. Peripherals
Functions

void glcd_print(const struct device *dev, char *data, uint32_t size)
Send text to the screen.

Parameters
• dev - Pointer to device structure for driver instance.
• data - the ASCII text to display
• size - the length of the text in bytes

void glcd_cursor_pos_set(const struct device *dev, uint8_t col, uint8_t row)
Set text cursor position for next additions.

Parameters
• dev - Pointer to device structure for driver instance.
• col - the column for the cursor to be moved to (0-15)
• row - the row it should be moved to (0 or 1)

void glcd_clear(const struct device *dev)
Clear the current display.

Parameters
• dev - Pointer to device structure for driver instance.

void glcd_display_state_set(const struct device *dev, uint8_t opt)
Function to change the display state.
This function provides the user the ability to change the state of the display as per needed. Controlling things like powering on or off the screen, the option to display the cursor or not, and the ability to blink the cursor.

Parameters
• dev - Pointer to device structure for driver instance.
• opt - An 8bit bitmask of GLCD_DS_ * options.

uint8_t glcd_display_state_get(const struct device *dev)
return the display feature set associated with the device

Parameters
• dev - the Grove LCD to get the display features set

Returns
the display feature set associated with the device.

void glcd_input_state_set(const struct device *dev, uint8_t opt)
Function to change the input state.
This function provides the user the ability to change the state of the text input. Controlling things like text entry from the left or right side, and how far to increment on new text
Parameters

- **dev** – Pointer to device structure for driver instance.
- **opt** – A bitmask of GLCD_IS_* options

```c
uint8_t glcd_input_state_get(const struct device *dev)
```

return the input set associated with the device

Parameters

- **dev** – the Grove LCD to get the input features set

Returns

the input set associated with the device.

```c
void glcd_function_set(const struct device *dev, uint8_t opt)
```

Function to set the functional state of the display.

This function provides the user the ability to change the state of the display as per needed. Controlling things like the number of rows, dot size, and text display quality.

Parameters

- **dev** – Pointer to device structure for driver instance.
- **opt** – A bitmask of GLCD_FS_* options

```c
uint8_t glcd_function_get(const struct device *dev)
```

return the function set associated with the device

Parameters

- **dev** – the Grove LCD to get the functions set

Returns

the function features set associated with the device.

```c
void glcd_color_select(const struct device *dev, uint8_t color)
```

Set LCD background to a predefined color.

Parameters

- **dev** – Pointer to device structure for driver instance.
- **color** – One of the predefined color options

```c
void glcd_color_set(const struct device *dev, uint8_t r, uint8_t g, uint8_t b)
```

Set LCD background to custom RGB color value.

Parameters

- **dev** – Pointer to device structure for driver instance.
- **r** – A numeric value for the red color (max is 255)
- **g** – A numeric value for the green color (max is 255)
- **b** – A numeric value for the blue color (max is 255)

### BBC micro:bit Display

**group mb_display**

BBC micro:bit display APIs.
Defines

MB_IMAGE(_rows...)  
Generate an image object from a given array rows/columns.

This helper takes an array of 5 rows, each consisting of 5 0/1 values which correspond to the columns of that row. The value 0 means the pixel is disabled whereas a 1 means the pixel is enabled.

The pixels go from left to right and top to bottom, i.e. top-left corner is the first row's first value, top-right is the first row's last value, and bottom-right corner is the last value of the last (5th) row. As an example, the following would create a smiley face image:

Parameters

- _rows – Each of the 5 rows represented as a 5-value column array.

Returns

Image bitmap that can be passed e.g. to mb_display_image().

Enums

enum mb_display_mode

Display mode.

First 16 bits are reserved for modes, last 16 for flags.

Values:

enumerator MB_DISPLAY_MODE_DEFAULT

Default mode (“single” for images, “scroll” for text).

enumerator MB_DISPLAY_MODE_SINGLE

Display images sequentially, one at a time.

enumerator MB_DISPLAY_MODE_SCROLL

Display images by scrolling.

enumerator MB_DISPLAY_FLAG_LOOP = BIT(16)

Loop back to the beginning when reaching the last image.

Functions

struct mb_display *mb_display_get(void)

Get a pointer to the BBC micro:bit display object.

Returns

Pointer to display object.

void mb_display_image(struct mb_display *disp, uint32_t mode, int32_t duration, const struct mb_image *img, uint8_t img_count)

Display one or more images on the BBC micro:bit LED display.

This function takes an array of one or more images and renders them sequentially on the micro:bit display. The call is asynchronous, i.e. the processing of the display happens in the background. If there is another image being displayed it will be canceled and the new one takes over.
Parameters

- disp – Display object.
- mode – One of the MB_DISPLAY_MODE_* options.
- duration – Duration how long to show each image (in milliseconds), or SYS_FOREVER_MS.
- img – Array of image bitmaps (struct mb_image objects).
- img_count – Number of images in ‘img’ array.

```c
void mb_display_print(struct mb_display *disp, uint32_t mode, int32_t duration, const char *fmt, ...)
```

Print a string of characters on the BBC micro:bit LED display.

This function takes a printf-style format string and outputs it in a scrolling fashion to the display.

The call is asynchronous, i.e. the processing of the display happens in the background. If there is another image or string being displayed it will be canceled and the new one takes over.

Parameters

- disp – Display object.
- mode – One of the MB_DISPLAY_MODE_* options.
- duration – Duration how long to show each character (in milliseconds), or SYS_FOREVER_MS.
- fmt – printf-style format string
- ... – Optional list of format arguments.

```c
void mb_display_stop(struct mb_display *disp)
```

Stop the ongoing display of an image.

Parameters

- disp – Display object.

```c
struct mb_image
```

```c
#include <mb_display.h> Representation of a BBC micro:bit display image.
```

This struct should normally not be used directly, rather created using the MB_IMAGE() macro.

Monochrome Character Framebuffer

```c
#include <mb_display.h> Representation of a BBC micro:bit display image.
```

```c
```

This struct should normally not be used directly, rather created using the MB_IMAGE() macro.

Monochrome Character Framebuffer

```c
```

Public Monochrome Character Framebuffer API.

Defines

```c
FONT_ENTRY_DEFINE(_name, _width, _height, _caps, _data, _fc, _lc)
```

Macro for creating a font entry.

Parameters

- _name – Name of the font entry.
- _width – Width of the font in pixels
- _height – Height of the font in pixels.
• `_caps` – Font capabilities.
• `_data` – Raw data of the font.
• `_fc` – Character mapped to first font element.
• `_lc` – Character mapped to last font element.

**Enums**

enum cfb_display_param

Values:

enumerator CFB_DISPLAY_HEIGH = 0
enumerator CFB_DISPLAY_WIDTH
enumerator CFB_DISPLAY_PPT
enumerator CFB_DISPLAY_ROWS
enumerator CFB_DISPLAY_COLS

denum cfb_font_caps

Values:

enumerator CFB_FONT_MONO_VPACKED = BIT(0)
enumerator CFB_FONT_MONO_HPACKED = BIT(1)
enumerator CFB_FONT_MSB_FIRST = BIT(2)

**Functions**

int cfb_print(const struct device *dev, char *str, uint16_t x, uint16_t y)
Print a string into the framebuffer.

**Parameters**

• `dev` – Pointer to device structure for driver instance
• `str` – String to print
• `x` – Position in X direction of the beginning of the string
• `y` – Position in Y direction of the beginning of the string

**Returns**

0 on success, negative value otherwise

int cfb_framebuffer_clear(const struct device *dev, bool clear_display)
Clear framebuffer.

**Parameters**

• `dev` – Pointer to device structure for driver instance
• clear_display – Clear the display as well

Returns
0 on success, negative value otherwise

int cfb_framebuffer_invert(const struct device *dev)
Invert Pixels.

Parameters
• dev – Pointer to device structure for driver instance

Returns
0 on success, negative value otherwise

int cfb_invArea(const struct device *dev, uint16_t x, uint16_t y, uint16_t width, uint16_t height)
Invert Pixels in selected area.

Parameters
• dev – Pointer to device structure for driver instance
• x – Position in X direction of the beginning of area
• y – Position in Y direction of the beginning of area
• width – Width of area in pixels
• height – Height of area in pixels

Returns
0 on success, negative value otherwise

int cfb_framebuffer_finalize(const struct device *dev)
Finalize framebuffer and write it to display RAM, invert or reorder pixels if necessary.

Parameters
• dev – Pointer to device structure for driver instance

Returns
0 on success, negative value otherwise

int cfb_get_display_parameter(const struct device *dev, enum cfb_display_param)
Get display parameter.

Parameters
• dev – Pointer to device structure for driver instance
• cfb_display_param – One of the display parameters

Returns
Display parameter value

int cfb_framebuffer_set_font(const struct device *dev, uint8_t idx)
Set font.

Parameters
• dev – Pointer to device structure for driver instance
• idx – Font index

Returns
0 on success, negative value otherwise
int cfb_get_font_size(const struct device *dev, uint8_t idx, uint8_t *width, uint8_t *height)
  Get font size.

  Parameters
  • dev – Pointer to device structure for driver instance
  • idx – Font index
  • width – Pointers to the variable where the font width will be stored.
  • height – Pointers to the variable where the font height will be stored.

  Returns
  0 on success, negative value otherwise

int cfb_get_numof_fonts(const struct device *dev)
  Get number of fonts.

  Parameters
  • dev – Pointer to device structure for driver instance

  Returns
  number of fonts

int cfb_framebuffer_init(const struct device *dev)
  Initialize Character Framebuffer.

  Parameters
  • dev – Pointer to device structure for driver instance

  Returns
  0 on success, negative value otherwise

struct cfb_font
#include <cfb.h>

### 7.3.9 DMA

**Overview**

**API Reference**

`group dma_interface`

DMA Interface.

**Defines**

`DMA_MAGIC`

`DMA_BUF_ADDR_ALIGNMENT(node)`

Get the device tree property describing the buffer address alignment.

Useful when statically defining or allocating buffers for DMA usage where memory alignment often matters.

**Parameters**

• node – Node identifier, e.g. `DT_NODELABEL(dma_0)`
Returns
alignment Memory byte alignment required for DMA buffers

`DMA_BUF_SIZE_ALIGNMENT(node)`
Get the device tree property describing the buffer size alignment
Useful when statically defining or allocating buffers for DMA usage where memory alignment often matters.

Parameters
- `node` – Node identifier, e.g. `DT_NODENAME(dma_0)`

Returns
alignment Memory byte alignment required for DMA buffers

`DMA_COPY_ALIGNMENT(node)`
Get the device tree property describing the minimal chunk of data possible to be copied

Parameters
- `node` – Node identifier, e.g. `DT_NODENAME(dma_0)`

Returns
minimal Minimal chunk of data possible to be copied

Typedefs

typedef void (*`dma_callback_t`)(const struct `device` *dev, void *user_data, uint32_t channel, int status)
Callback function for DMA transfer completion.

If enabled, callback function will be invoked at transfer completion or when error happens.

Param `dev`
Pointer to the DMA device calling the callback.

Param `user_data`
A pointer to some user data or NULL

Param `channel`
The channel number

Param `status`
0 on success, a negative errno otherwise

Enums

enum `dma_channel_direction`
Values:

enumerator `MEMORY_TO_MEMORY` = 0x0
enumerator `MEMORY_TO_PERIPHERAL`
enumerator `PERIPHERAL_TO_MEMORY`
enumerator `PERIPHERAL_TO_PERIPHERAL`
enumerator HOST_TO_MEMORY
enumerator MEMORY_TO_HOST
enumerator DMA_CHANNEL_DIRECTION_COMMON_COUNT
   Number of all common channel directions.
enumerator DMA_CHANNEL_DIRECTION_PRIV_START = DMA_CHANNEL_DIRECTION_COMMON_COUNT
   This and higher values are dma controller or soc specific. Refer to the specified dma driver
   header file.
enumerator DMA_CHANNEL_DIRECTION_MAX = 0x7
   Maximum allowed value (3 bit field!)

enum dma_addr_adj
   Valid values for source_addr_adj and dest_addr_adj
   Values:
       enumerator DMA_ADDR_ADJ_INCREMENT
       enumerator DMA_ADDR_ADJ_DECREMENT
       enumerator DMA_ADDR_ADJ_NO_CHANGE

enum dma_channel_filter
   Values:
       enumerator DMA_CHANNEL_NORMAL
       enumerator DMA_CHANNEL_PERIODIC

enum dma_attribute_type
   Values:
       enumerator DMA_ATTR_BUFFER_ADDRESS_ALIGNMENT
       enumerator DMA_ATTR_BUFFER_SIZE_ALIGNMENT
       enumerator DMA_ATTR_COPY_ALIGNMENT

Functions

static inline int dma_config(const struct device *dev, uint32_t channel, struct dma_config *config)
   Configure individual channel for DMA transfer.

Parameters
   • dev – Pointer to the device structure for the driver instance.
- channel – Numeric identification of the channel to configure
- config – Data structure containing the intended configuration for the selected channel

**Return values**
- 0 – if successful.
- Negative – errno code if failure.

```c
static inline int dma_reload(const struct device *dev, uint32_t channel, uint32_t src, uint32_t dst, size_t size)
```
Reload buffer(s) for a DMA channel.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- channel – Numeric identification of the channel to configure.
- src – source address for the DMA transfer
- dst – destination address for the DMA transfer
- size – size of DMA transfer

**Return values**
- 0 – if successful.
- Negative – errno code if failure.

```c
int dma_start(const struct device *dev, uint32_t channel)
```
Enables DMA channel and starts the transfer, the channel must be configured beforehand.
Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- channel – Numeric identification of the channel where the transfer will be processed

**Return values**
- 0 – if successful.
- Negative – errno code if failure.

```c
int dma_stop(const struct device *dev, uint32_t channel)
```
Stops the DMA transfer and disables the channel.
Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- channel – Numeric identification of the channel where the transfer was being processed

**Return values**
- 0 – if successful.
- Negative – errno code if failure.
int dma_suspend(const struct device *dev, uint32_t channel)
Suspend a DMA channel transfer.
Implementations must check the validity of the channel state and ID passed in and return -EINVAL if either are invalid.

Parameters
• dev – Pointer to the device structure for the driver instance.
• channel – Numeric identification of the channel to suspend

Return values
• 0 – If successful.
• -ENOSYS – If not implemented.
• -EINVAL – If invalid channel id or state.
• -errno – Other negative errno code failure.

int dma_resume(const struct device *dev, uint32_t channel)
Resume a DMA channel transfer.
Implementations must check the validity of the channel state and ID passed in and return -EINVAL if either are invalid.

Parameters
• dev – Pointer to the device structure for the driver instance.
• channel – Numeric identification of the channel to resume

Return values
• 0 – If successful.
• -ENOSYS – If not implemented
• -EINVAL – If invalid channel id or state.
• -errno – Other negative errno code failure.

int dma_request_channel(const struct device *dev, void *filter_param)
request DMA channel.
request DMA channel resources return -EINVAL if there is no valid channel available.

Parameters
• dev – Pointer to the device structure for the driver instance.
• filter_param – filter function parameter

Return values
• dma – channel if successful.
• Negative – errno code if failure.

void dma_release_channel(const struct device *dev, uint32_t channel)
release DMA channel.
release DMA channel resources

Parameters
• dev – Pointer to the device structure for the driver instance.
• channel – channel number
int dma_chan_filter(const struct device *dev, int channel, void *filter_param)

DMA channel filter.

filter channel by attribute

Parameters
- dev – Pointer to the device structure for the driver instance.
- channel – channel number
- filter_param – filter attribute

Return values
- Negative – errno code if not support

static inline int dma_get_status(const struct device *dev, uint32_t channel, struct dma_status *stat)

get current runtime status of DMA transfer

Implementations must check the validity of the channel ID passed in and return -EINVAL if it is invalid or -ENOSYS if not supported.

Parameters
- dev – Pointer to the device structure for the driver instance.
- channel – Numeric identification of the channel where the transfer was being processed
- stat – a non-NULL dma_status object for storing DMA status

Return values
- non-negative – if successful.
- Negative – errno code if failure.

static inline int dma_get_attribute(const struct device *dev, uint32_t type, uint32_t *value)

get attribute of a dma controller

This function allows to get a device specific static or runtime attribute like required address and size alignment of a buffer. Implementations must check the validity of the type passed in and return -EINVAL if it is invalid or -ENOSYS if not supported.

Parameters
- dev – Pointer to the device structure for the driver instance.
- type – Numeric identification of the attribute
- value – A non-NULL pointer to the variable where the read value is to be placed

Return values
- non-negative – if successful.
- Negative – errno code if failure.

static inline uint32_t dma_width_index(uint32_t size)

Look-up generic width index to be used in registers.

WARNING: This look-up works for most controllers, but may not work for yours. Ensure your controller expects the most common register bit values before using this convenience function. If your controller does not support these values, you will have to write your own look-up inside the controller driver.

Parameters
- size – width of bus (in bytes)
Return values
common – DMA index to be placed into registers.

static inline uint32_t dma_burst_index(uint32_t burst)
Look-up generic burst index to be used in registers.

WARNING: This look-up works for most controllers, but may not work for yours. Ensure
your controller expects the most common register bit values before using this convenience
function. If your controller does not support these values, you will have to write your own
look-up inside the controller driver.

Parameters
• burst – number of bytes to be sent in a single burst

Return values
common – DMA index to be placed into registers.

struct dma_block_config
#include <dma.h> DMA block configuration structure.

Param source_address
is block starting address at source

Param source_gather_interval
is the address adjustment at gather boundary

Param dest_address
is block starting address at destination

Param dest_scatter_interval
is the address adjustment at scatter boundary

Param dest_scatter_count
is the continuous transfer count between scatter boundaries

Param source_gather_count
is the continuous transfer count between gather boundaries

Param block_size
is the number of bytes to be transferred for this block.

Param config
is a bit field with the following parts:

<table>
<thead>
<tr>
<th>Field</th>
<th>Value</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>source_gather_en</td>
<td>[ 0 ]</td>
<td>0-disable, 1-enable.</td>
</tr>
<tr>
<td>source_addr_adj</td>
<td>[ 2 : 3 ]</td>
<td>00-increment, 01-decrement, 10-no change.</td>
</tr>
<tr>
<td>dest_addr_adj</td>
<td>[ 4 : 5 ]</td>
<td>00-increment, 01-decrement, 10-no change.</td>
</tr>
<tr>
<td>source_reload_en</td>
<td>[ 6 ]</td>
<td>reload source address at the end of block transfer</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0-disable, 1-enable.</td>
</tr>
<tr>
<td>dest_reload_en</td>
<td>[ 7 ]</td>
<td>reload destination address at the end of block transfer</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0-disable, 1-enable.</td>
</tr>
<tr>
<td>fifo_mode_control</td>
<td>[ 8 : 11 ]</td>
<td>How full of the fifo before block transfer start. HW specific.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>0-disable, 1-enable.</td>
</tr>
<tr>
<td>flow_control_mode</td>
<td>[ 12 ]</td>
<td>0-source request served upon data</td>
</tr>
</tbody>
</table>

(continues on next page)
struct dma_config

#include <dma.h> DMA configuration structure.

**Param dma_slot**

[0:7] - which peripheral and direction (HW specific)

**Param channel_direction**

[8:10] - 000-memory to memory, 001-memory to peripheral, 010-peripheral to memory, 011-peripheral to peripheral, 100-host to memory 101-memory to host...

**Param complete_callback_en**

[11] - 0-callback invoked at completion only 1-callback invoked at completion of each block

**Param error_callback_en**

[12] - 0-error callback enabled 1-error callback disabled

**Param source_handshake**


**Param dest_handshake**

[14] - 0-HW, 1-SW

**Param channel_priority**

[15:18] - DMA channel priority

**Param source_chaining_en**

[19] - enable/disable source block chaining 0-disable, 1-enable

**Param dest_chaining_en**

[20] - enable/disable destination block chaining. 0-disable, 1-enable

**Param linked_channel**

[21:27] - after channel count exhaust will initiate a channel service request at this channel

**Param cyclic**

[28] - enable/disable cyclic buffer 0-disable, 1-enable

**Param reserved**

[29:31]

**Param source_data_size**

[0:15] - width of source data (in bytes)

**Param dest_data_size**

[16:31] - width of dest data (in bytes)

**Param source_burst_length**

[0:15] - number of source data units

**Param dest_burst_length**

[16:31] - number of destination data units

**Param block_count**

is the number of blocks used for block chaining, this depends on availability of the DMA controller.

7.3. Peripherals
**Param user_data**
private data from DMA client.

**Param dma_callback**
see dma_callback_t for details

```c
struct dma_status
#include <dma.h> DMA runtime status structure
busy - is current DMA transfer busy or idle
dir - DMA transfer direction
pending_length - data length pending to be transferred in bytes or platform dependent.
free - free buffer space
write_position - write position in a circular dma buffer
read_position - read position in a circular dma buffer
```

```c
struct dma_context
#include <dma.h> DMA context structure Note: the dma_context shall be the first member of
DMA client driver Data, got by dev->data
magic - magic code to identify the context
dma_channels - dma channels
atomic - driver atomic_t pointer
```

## 7.3.10 EC Host Command

### Overview

### API Reference

```c
#include <dma.h>
```

**Define**

```c
EC_HOST_CMD_HANDLER(_id, _function, _version_mask, _request_type, _response_type)
```

Statically define and register a host command handler.

Helper macro to statically define and register a host command handler that has a compile-time-fixed sizes for its both request and response structures.

**Parameters**

- **_id** – Id of host command to handle request for.
- **_function** – Name of handler function.
- **_version_mask** – The bitfield of all versions that the _function supports. E.g. `BIT(0)` corresponds to version 0.
- **_request_type** – The datatype of the request parameters for _function.
- **_response_type** – The datatype of the response parameters for _function.

```c
EC_HOST_CMD_HANDLER_UNBOUND(_id, _function, _version_mask)
```

Statically define and register a host command handler without sizes.

Helper macro to statically define and register a host command handler whose request or response structure size is not known as compile time.

**Parameters**

- **_id** – Id of host command to handle request for.
• _function – Name of handler function.

• _version_mask – The bitfield of all versions that the _function supports. E.g. BIT(0) corresponds to version 0.

Typedefs

typedef enum ec_host_cmd_status (*ec_host_cmd_handler_cb)(struct ec_host_cmd_handler_args *args)

Enums

enum ec_host_cmd_status

Values:

enumerator EC_HOST_CMD_SUCCESS = 0
   Host command was successful.

enumerator EC_HOST_CMD_INVALID_COMMAND = 1
   The specified command id is not recognized or supported.

enumerator EC_HOST_CMD_ERROR = 2
   Generic Error.

enumerator EC_HOST_CMD_INVALID_PARAM = 3
   One of more of the input request parameters is invalid.

enumerator EC_HOST_CMD_ACCESS_DENIED = 4
   Host command is not permitted.

enumerator EC_HOST_CMD_INVALID_RESPONSE = 5
   Response was invalid (e.g. not version 3 of header).

enumerator EC_HOST_CMD_INVALID_VERSION = 6
   Host command id version unsupported.

enumerator EC_HOST_CMD_INVALID_CHECKSUM = 7
   Checksum did not match.

enumerator EC_HOST_CMD_IN_PROGRESS = 8
   A host command is currently being processed.

enumerator EC_HOST_CMD_UNAVAILABLE = 9
   Requested information is currently unavailable.

enumerator EC_HOST_CMD_TIMEOUT = 10
   Timeout during processing.
enumerator EC_HOST_CMD_OVERFLOW = 11
    Data or table overflow.

enumerator EC_HOST_CMD_INVALID_HEADER = 12
    Header is invalid or unsupported (e.g. not version 3 of header).

enumerator EC_HOST_CMD_REQUEST_TRUNCATED = 13
    Did not receive all expected request data.

enumerator EC_HOST_CMD_RESPONSE_TOO_BIG = 14
    Response was too big to send within one response packet.

enumerator EC_HOST_CMD_BUS_ERROR = 15
    Error on underlying communication bus.

enumerator EC_HOST_CMD_BUSY = 16
    System busy. Should retry later.

enumerator EC_HOST_CMD_INVALID_HEADER_VERSION = 17
    Header version invalid.

enumerator EC_HOST_CMD_INVALID_HEADER_CRC = 18
    Header CRC invalid.

enumerator EC_HOST_CMD_INVALID_DATA_CRC = 19
    Data CRC invalid.

enumerator EC_HOST_CMD_DUP_UNAVAILABLE = 20
    Can’t resend response.

enumerator EC_HOST_CMD_MAX = UINT16_MAX

struct ec_host_cmd_handler_args
    #include <ec_host_cmd.h> Arguments passed into every installed host command handler.

Public Members

void *reserved
    Reserved for compatibility.

uint16_t command
    Command identifier.

const uint8_t version
    The version of the host command that is being requested. This will be a value that has
    been static registered as valid for the handler.
const void *const input_buf
    The incoming data that can be cast to the handlers request type.

const uint16_t input_buf_size
    The number of valid bytes that can be read from input_buf.

void *const output_buf
    The data written to this buffer will be send to the host.

uint16_t output_buf_max
    Maximum number of bytes that can be written to the output_buf.

uint16_t output_buf_size
    Number of bytes of output_buf to send to the host.

struct ec_host_cmd_handler
    #include <ec_host_cmd.h> Structure use for statically registering host command handlers.

Public Members

ec_host_cmd_handler_cb handler
    Callback routine to process commands that match id.

uint16_t id
    The numerical command id used as the lookup for commands.

uint16_t version_mask
    The bitfield of all versions that the handler supports, where each bit value represents that
    the handler supports that version. E.g. BIT(0) corresponds to version 0.

uint16_t min_rqt_size
    The minimum input_buf_size enforced by the framework before passing to the handler.

uint16_t min_rsp_size
    The minimum output_buf_size enforced by the framework before passing to the handler.

struct ec_host_cmd_request_header
    #include <ec_host_cmd.h> Header for requests from host to embedded controller.

Represent the over-the-wire header in LE format for host command requests. This represent
version 3 of the host command header. The requests are always sent from host to embedded
controller.

Public Members

uint8_t prtcl_ver
    Should be 3. The EC will return EC_HOST_CMD_INVALID_HEADER if it receives a header
    with a version it doesn’t know how to parse.
Zephyr Project Documentation, Release 3.2.99

uint8_t checksum
    Checksum of response and data; sum of all bytes including checksum. Should total to 0.

uint16_t cmd_id
    Id of command that is being sent.

uint8_t cmd_ver
    Version of the specific cmd_id being requested. Valid versions start at 0.

uint8_t reserved
    Unused byte in current protocol version; set to 0.

uint16_t data_len
    Length of data which follows this header.

struct ec_host_cmd_response_header
#include <ec_host_cmd.h> Header for responses from embedded controller to host.
Represent the over-the-wire header in LE format for host command responses. This represent version 3 of the host command header. Responses are always sent from embedded controller to host.

Public Members

uint8_t prtcl_ver
    Should be 3.

uint8_t checksum
    Checksum of response and data; sum of all bytes including checksum. Should total to 0.

uint16_t result
    A ec_host_cmd_status response code for specific command.

uint16_t data_len
    Length of data which follows this header.

uint16_t reserved
    Unused bytes in current protocol version; set to 0.

7.3.11 Error Detection And Correction (EDAC)

API Reference

group edac
Enums

enum edac_error_type
    EDAC error type.
    Values:

    enumerator EDAC_ERROR_TYPE_DRAM_COR = \textit{BIT}(0)
        Correctable error type

    enumerator EDAC_ERROR_TYPE_DRAM_UC = \textit{BIT}(1)
        Uncorrectable error type

Functions

static inline int edac_inject_set_param1(const struct device *dev, uint64_t value)
    Set injection parameter param1.
    Set first error injection parameter value.
    Parameters
        • dev – Pointer to the device structure
        • value – First injection parameter
    Return values
        • -ENOSYS – if the optional interface is not implemented
        • 0 – on success, other error code otherwise

static inline int edac_inject_get_param1(const struct device *dev, uint64_t *value)
    Get injection parameter param1.
    Get first error injection parameter value.
    Parameters
        • dev – Pointer to the device structure
        • value – Pointer to the first injection parameter
    Return values
        • -ENOSYS – if the optional interface is not implemented
        • 0 – on success, error code otherwise

static inline int edac_inject_set_param2(const struct device *dev, uint64_t value)
    Set injection parameter param2.
    Set second error injection parameter value.
    Parameters
        • dev – Pointer to the device structure
        • value – Second injection parameter
    Return values
        • -ENOSYS – if the optional interface is not implemented
        • 0 – on success, error code otherwise
static inline int edac_inject_get_param2(const struct device *dev, uint64_t *value)
Get injection parameter param2.

Parameters
• dev – Pointer to the device structure
• value – Pointer to the second injection parameter

Return values
• -ENOSYS – if the optional interface is not implemented
• 0 – on success, error code otherwise

static inline int edac_inject_set_error_type(const struct device *dev, uint32_t error_type)
Set error type value.

Set the value of error type to be injected

Parameters
• dev – Pointer to the device structure
• error_type – Error type value

Return values
• -ENOSYS – if the optional interface is not implemented
• 0 – on success, error code otherwise

static inline int edac_inject_get_error_type(const struct device *dev, uint32_t *error_type)
Get error type value.

Get the value of error type to be injected

Parameters
• dev – Pointer to the device structure
• error_type – Pointer to error type value

Return values
• -ENOSYS – if the optional interface is not implemented
• 0 – on success, error code otherwise

static inline int edac_inject_error_trigger(const struct device *dev)
Set injection control.

Trigger error injection.

Parameters
• dev – Pointer to the device structure

Return values
• -ENOSYS – if the optional interface is not implemented
• 0 – on success, error code otherwise

static inline int edac_ecc_error_log_get(const struct device *dev, uint64_t *value)
Get ECC Error Log.

Read value of ECC Error Log.

Parameters
• dev – Pointer to the device structure
• value – Pointer to the ECC Error Log value
Return values
• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

static inline int edac_ecc_error_log_clear(const struct device *dev)
Clear ECC Error Log.

Parameters
• dev – Pointer to the device structure

Return values
• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

Get Parity Error Log.

Parameters
• dev – Pointer to the device structure
• value – Pointer to the parity Error Log value

Return values
• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

Clear Parity Error Log.

Parameters
• dev – Pointer to the device structure

Return values
• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

Get number of correctable errors.

Parameters
• dev – Pointer to the device structure

Return values
• num – Number of correctable errors
• -ENOSYS – if the mandatory interface is not implemented

Get number of uncorrectable errors.

Parameters
• dev – Pointer to the device structure

Return values
• num – Number of uncorrectable errors
• -ENOSYS – if the mandatory interface is not implemented

static inline int edac_notify_callback_set(const struct device *dev, edac_notify_callback_f cb)

Register callback function for memory error exception

This callback runs in interrupt context

**Parameters**

• dev – EDAC driver device to install callback
• cb – Callback function pointer

**Return values**

• 0 – on success, error code otherwise
• -ENOSYS – if the mandatory interface is not implemented

```
struct edac_driver_api
#include <edac.h> EDAC driver API.
This is the mandatory API any EDAC driver needs to expose.
```

### 7.3.12 EEPROM

**Overview**

The EEPROM API provides read and write access to Electrically Erasable Programmable Read-Only Memory (EEPROM) devices.

EEPROMs have an erase block size of 1 byte, a long lifetime, and allow overwriting data on byte-by-byte access.

**Configuration Options**

Related configuration options:

• CONFIG_EEPROM

**API Reference**

```
group eeprom_interface
    EEPROM Interface.

    **Typedefs**

typedef int (*eeprom_api_read)(const struct device *dev, off_t offset, void *data, size_t len)
typedef int (*eeprom_api_write)(const struct device *dev, off_t offset, const void *data, size_t len)
typedef size_t (*eeprom_api_size)(const struct device *dev)
```
Functions

```c
int eeprom_read(const struct device *dev, off_t offset, void *data, size_t len)
Read data from EEPROM.

Parameters
• dev – EEPROM device
• offset – Address offset to read from.
• data – Buffer to store read data.
• len – Number of bytes to read.

Returns
0 on success, negative errno code on failure.
```

```c
int eeprom_write(const struct device *dev, off_t offset, const void *data, size_t len)
Write data to EEPROM.

Parameters
• dev – EEPROM device
• offset – Address offset to write data to.
• data – Buffer with data to write.
• len – Number of bytes to write.

Returns
0 on success, negative errno code on failure.
```

```c
size_t eeprom_get_size(const struct device *dev)
Get the size of the EEPROM in bytes.

Parameters
• dev – EEPROM device.

Returns
EEPROM size in bytes.
```

```c
struct eeprom_driver_api
#include <eeprom.h>
```

7.3.13 Entropy

Overview

The entropy API provides functions to retrieve entropy values from entropy hardware present on the platform. The entropy APIs are provided for use by the random subsystem and cryptographic services. They are not suitable to be used as random number generation functions.

API Reference

```c
group entropy_interface
    Entropy Interface.
```
Defines

ENTROPY_BUSYWAIT

Typedefs

typedef int (*entropy_get_entropy_t)(const struct device *dev, uint8_t *buffer, uint16_t length)
   Callback API to get entropy.
   See \texttt{entropy_get_entropy()} for argument description

typedef int (*entropy_get_entropy_isr_t)(const struct device *dev, uint8_t *buffer, uint16_t length, uint32_t flags)
   Callback API to get entropy from an ISR.
   See \texttt{entropy_get_entropy_isr()} for argument description

Functions

int entropy_get_entropy(const struct device *dev, uint8_t *buffer, uint16_t length)
   Fills a buffer with entropy. Blocks if required in order to generate the necessary random data.
   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{dev} – Pointer to the entropy device.
   \item \texttt{buffer} – Buffer to fill with entropy.
   \item \texttt{length} – Buffer length.
   \end{itemize}

   \textbf{Return values}
   \begin{itemize}
   \item 0 – on success.
   \item -ERRNO – errno code on error.
   \end{itemize}

static inline int entropy_get_entropy_isr(const struct device *dev, uint8_t *buffer, uint16_t length, uint32_t flags)
   Fills a buffer with entropy in a non-blocking or busy-wait manner. Callable from ISRs.
   \textbf{Parameters}
   \begin{itemize}
   \item \texttt{dev} – Pointer to the device structure.
   \item \texttt{buffer} – Buffer to fill with entropy.
   \item \texttt{length} – Buffer length.
   \item \texttt{flags} – Flags to modify the behavior of the call.
   \end{itemize}

   \textbf{Return values}
   \begin{itemize}
   \item number – of bytes filled with entropy or -error.
   \end{itemize}

\begin{verbatim}
#include <entropy.h>
\end{verbatim}
7.3.14 Flash

Overview

Flash offset concept
Offsets used by the user API are expressed in relation to the flash memory beginning address. This rule shall be applied to all flash controller regular memory that layout is accessible via API for retrieving the layout of pages (see CONFIG_FLASH_PAGE_LAYOUT).

An exception from the rule may be applied to a vendor-specific flash dedicated-purpose region (such a region obviously can’t be covered under API for retrieving the layout of pages).

User API Reference

group flash_interface
   FLASH Interface.

Typedefs

typedef bool (*flash_page_cb)(const struct flash_pages_info *info, void *data)
   Callback type for iterating over flash pages present on a device.
   The callback should return true to continue iterating, and false to halt.

See also:
   flash_page_foreach()

   Param info
      Information for current page

   Param data
      Private data for callback

   Return
      True to continue iteration, false to halt iteration.

Functions

int flash_read(const struct device *dev, off_t offset, void *data, size_t len)
   Read data from flash.
   All flash drivers support reads without alignment restrictions on the read offset, the read size, or the destination address.

   Parameters
      • dev – : flash dev
      • offset – : Offset (byte aligned) to read
      • data – : Buffer to store read data
      • len – : Number of bytes to read.

   Returns
      0 on success, negative errno code on fail.
int flash_write(const struct device *dev, off_t offset, const void *data, size_t len)
Write buffer into flash memory.

All flash drivers support a source buffer located either in RAM or SoC flash, without alignment restrictions on the source address. Write size and offset must be multiples of the minimum write block size supported by the driver.

Any necessary write protection management is performed by the driver write implementation itself.

Parameters
• dev – flash device
• offset – starting offset for the write
• data – data to write
• len – Number of bytes to write

Returns
0 on success, negative errno code on fail.

int flash_erase(const struct device *dev, off_t offset, size_t size)
Erase part or all of a flash memory.

Acceptable values of erase size and offset are subject to hardware-specific multiples of page size and offset. Please check the API implemented by the underlying sub driver, for example by using flash_get_page_info_by_offs() if that is supported by your flash driver.

Any necessary erase protection management is performed by the driver erase implementation itself.

See also:
flash_get_page_info_by_offs()

See also:
flash_get_page_info_by_idx()

Parameters
• dev – flash device
• offset – erase area starting offset
• size – size of area to be erased

Returns
0 on success, negative errno code on fail.

int flash_get_page_info_by_offs(const struct device *dev, off_t offset, struct flash_pages_info *info)
Get the size and start offset of flash page at certain flash offset.

Parameters
• dev – flash device
• offset – Offset within the page
• info – Page Info structure to be filled

Returns
0 on success, -EINVAL if page of the offset doesn't exist.
Get the size and start offset of flash page of certain index.

**Parameters**

- `dev` – flash device
- `page_index` – Index of the page. Index are counted from 0.
- `info` – Page Info structure to be filled

**Returns**

0 on success, -EINVAL if page of the index doesn’t exist.

Get the total number of flash pages.

**Parameters**

- `dev` – flash device

**Returns**

Number of flash pages.

Iterate over all flash pages on a device.

This routine iterates over all flash pages on the given device, ordered by increasing start offset. For each page, it invokes the given callback, passing it the page’s information and a private data object.

**Parameters**

- `dev` – Device whose pages to iterate over
- `cb` – Callback to invoke for each flash page
- `data` – Private data for callback function

Read data from Serial Flash Discoverable Parameters.

This routine reads data from a serial flash device compatible with the JEDEC JESD216 standard for encoding flash memory characteristics.

Availability of this API is conditional on selecting `CONFIG_FLASH_JESD216_API` and support of that functionality in the driver underlying `dev`.

**Parameters**

- `dev` – device from which parameters will be read
- `offset` – address within the SFDP region containing data of interest
- `data` – where the data to be read will be placed
- `len` – the number of bytes of data to be read

**Return values**

- 0 – on success
- -ENOTSUP – if the flash driver does not support SFDP access
- negative – values for other errors.

Read the JEDEC ID from a compatible flash device.

**Parameters**
• `dev` – device from which id will be read
• `id` – pointer to a buffer of at least 3 bytes into which id will be stored

**Return values**
• `0` – on successful store of 3-byte JEDEC id
• `-ENOTSUP` – if flash driver doesn’t support this function
• Negative values for other errors

```c
size_t flash_get_write_block_size(const struct device *dev)
```

Get the minimum write block size supported by the driver.

The write block size supported by the driver might differ from the write block size of memory used because the driver might implements write-modify algorithm.

**Parameters**
• `dev` – flash device

**Returns**
write block size in bytes.

```c
const struct flash_parameters *flash_get_parameters(const struct device *dev)
```

Get pointer to `flash_parameters` structure.

Returned pointer points to a structure that should be considered constant through a runtime, regardless if it is defined in RAM or Flash. Developer is free to cache the structure pointer or copy its contents.

**Returns**
pointer to `flash_parameters` structure characteristic for the device.

```c
#include <flash.h>
```

Flash memory parameters. Contents of this structure suppose to be filled in during flash device initialization and stay constant through a runtime.

```c
struct flash_pages_info
#include <flash.h>
```

**Implementation interface API Reference**

**group flash_internal_interface**
FLASH internal Interface.

**Typedefs**

typedef int (*flash_api_read)(const struct device *dev, off_t offset, void *data, size_t len)

Flash write implementation handler type.

**Note:** Any necessary write protection management must be performed by the driver, with the driver responsible for ensuring the “write-protect” after the operation completes (successfully or not) matches the write-protect state when the operation was started.
typedef int (*flash_api_erase)(const struct device *dev, off_t offset, size_t size)

Flash erase implementation handler type.

**Note:** Any necessary erase protection management must be performed by the driver, with the
driver responsible for ensuring the “erase-protect” after the operation completes (successfully
or not) matches the erase-protect state when the operation was started.

typedef const struct flash_parameters *(*flash_api_get_parameters)(const struct device *dev)

typedef void (*flash_api_pages_layout)(const struct device *dev, const struct flash_pages_layout **layout, size_t *layout_size)

Retrieve a flash device’s layout.

A flash device layout is a run-length encoded description of the pages on the device. (Here,
“page” means the smallest erasable area on the flash device.)

For flash memories which have uniform page sizes, this routine returns an array of length 1,
which specifies the page size and number of pages in the memory.

Layouts for flash memories with nonuniform page sizes will be returned as an array with
multiple elements, each of which describes a group of pages that all have the same size. In
this case, the sequence of array elements specifies the order in which these groups occur on
the device.

**Param dev**
Flash device whose layout to retrieve.

**Param layout**
The flash layout will be returned in this argument.

**Param layout_size**
The number of elements in the returned layout.

typedef int (*flash_api_sfdp_read)(const struct device *dev, off_t offset, void *data, size_t len)

typedef int (*flash_api_read_jedec_id)(const struct device *dev, uint8_t *id)

The fuel gauge subsystem exposes an API to uniformly access battery fuel gauge devices. Currently, only
reading data is supported.

**Note:** This API is currently experimental and this doc will be significantly changed as new features are
added to the API.

### 7.3.15 Fuel Gauges (Experimental API Stub Doc)

The fuel gauge subsystem exposes an API to uniformly access battery fuel gauge devices. Currently, only
reading data is supported.

**Note:** This API is currently experimental and this doc will be significantly changed as new features are
added to the API.

---

7.3. Peripherals 2175
Basic Operation

Properties  Fundamentally, a property is a quantity that a fuel gauge device can measure. Fuel gauges typically support multiple properties, such as temperature readings of the battery-pack or present-time current/voltage.

Properties are fetched using a client allocated array of `fuel_gauge_get_property`. This array is then populated by values as according to its `property_type` field.

Caching  The Fuel Gauge API explicitly provides no caching for its clients.

API Reference

group fuel_gauge_interface
   Fuel Gauge Interface.

Defines

`FUEL_GAUGE_AVG_CURRENT`
   Runtime Dynamic Battery Parameters Provide a 1 minute average of the current on the battery. Does not check for flags or whether those values are bad readings. See driver instance header for details on implementation and how the average is calculated. Units in uA negative=discharging

`FUEL_GAUGE_CURRENT`
   Battery current (uA); negative=discharging

`FUEL_GAUGE_CHARGE_CUTOFF`
   Whether the battery underlying the fuel-gauge is cut off from charge

`FUEL_GAUGE_CYCLE_COUNT`
   Cycle count in 1/100ths (number of charge/discharge cycles)

`FUEL_GAUGE_CONNECT_STATE`
   Connect state of battery

`FUEL_GAUGE_FLAGS`
   General Error/Runtime Flags

`FUEL_GAUGE_FULL_CHARGE_CAPACITY`
   Full Charge Capacity in uAh (might change in some implementations to determine wear)

`FUEL_GAUGE_PRESENT_STATE`
   Is the battery physically present

`FUEL_GAUGE_REMAINING_CAPACITY`
   Remaining capacity in uAh
FUEL_GAUGE_RUNTIME_TO_EMPTY
  Remaining battery life time in minutes

FUEL_GAUGE_RUNTIME_TO_FULL
  Remaining time in minutes until battery reaches full charge

FUEL_GAUGE_STATE_OF_CHARGE
  Absolute state of charge (percent, 0-100) - expressed as % of design capacity

FUEL_GAUGE_TEMPERATURE
  Temperature in 0.1 K

FUEL_GAUGE_VOLTAGE
  Battery voltage (uV)

FUEL_GAUGE_COMMON_COUNT
  Reserved to demark end of common fuel gauge properties

FUEL_GAUGE_CUSTOM_BEGIN
  Reserved to demark downstream custom properties - use this value as the actual value may change over future versions of this API

FUEL_GAUGE_PROP_MAX
  Reserved to demark end of valid enum properties

**Typedefs**

typedef int (*fuel_gauge_get_property_t)(const struct device *dev, struct fuel_gauge_get_property *props, size_t props_len)
  Fetch a battery fuel-gauge property.

  **Param dev**
  Pointer to the battery fuel-gauge device

  **Param props**
  pointer to array of fuel_gauge_get_property struct where the property struct field is set by the caller to determine what property is read from the fuel gauge device into the fuel_gauge_get_property struct's value field.

  **Param props_len**
  number of properties in props array

  **Return**
  return=0 if successful, return < 0 if getting all properties failed, return > 0 if some properties failed where return=number of failing properties.

  struct fuel_gauge_get_property
    #include <fuel_gauge.h>

  **Public Members**


```c
uint16_t property_type
    Battery fuel gauge property to get

int status
    Negative error status set by callee e.g. -ENOTSUP for an unsupported property

int avg_current
    FUEL_GAUGE_AVG_CURRENT

bool cutoff
    FUEL_GAUGE_CUTOFF

int current
    FUEL_GAUGE_CURRENT

uint32_t cycle_count
    FUEL_GAUGE_CYCLE_COUNT

uint32_t flags
    FUEL_GAUGE_FLAGS

uint32_t full_charge_capacity
    FUEL_GAUGE_FULL_CHARGE_CAPACITY

uint32_t remaining_capacity
    FUEL_GAUGE_REMAINING_CAPACITY

uint32_t runtime_to_empty
    FUEL_GAUGE_RUNTIME_TO_EMPTY

uint32_t runtime_to_full
    FUEL_GAUGE_RUNTIME_TO_FULL

uint8_t state_of_charge
    FUEL_GAUGE_STATE_OF_CHARGE

uint16_t temperature
    FUEL_GAUGE_TEMPERATURE

int voltage
    FUEL_GAUGE_VOLTAGE

union fuel_gauge_get_property.[anonymous] value
    Property field for getting

struct battery_driver_api
    #include <fuel_gauge.h>
```
7.3.16 GNA

Overview

The GNA API provides access to Intel's Gaussian Mixture Model and Neural Network Accelerator (GNA).

Configuration Options

Related configuration options:

- CONFIG_INTEL_GNA

API Reference

```markdown
group gna_interface

This file contains the driver APIs for Intel's Gaussian Mixture Model and Neural Network Accelerator (GNA)
```

Enums

```markdown
enum gna_result

Result of an inference operation

Values:

- GNA_RESULT_INFERENCE_COMPLETE
- GNA_RESULT_SATURATION_OCCURRED
- GNA_RESULT_OUTPUT_BUFFER_FULL_ERROR
- GNA_RESULT_PARAM_OUT_OF_RANGE_ERROR
- GNA_RESULT_GENERIC_ERROR
```

Functions

```c
static inline int gna_configure(const struct device *dev, struct gna_config *cfg)

Configure the GNA device.

Configure the GNA device. The GNA device must be configured before registering a model or performing inference

Parameters

- dev – Pointer to the device structure for the driver instance.
- cfg – Device configuration information

Return values

- 0 – If the configuration is successful
- A – negative error code in case of a failure.
```
static inline int gna_register_model(const struct device *dev, struct gna_model_info *model, void **model_handle)

Register a neural network model.

Register a neural network model with the GNA device. A model needs to be registered before it can be used to perform inference.

Parameters
- dev – Pointer to the device structure for the driver instance.
- model – Information about the neural network model
- model_handle – Handle to the registered model if registration succeeds

Return values
- 0 – If registration of the model is successful.
- A – Negative error code in case of a failure.

static inline int gna_deregister_model(const struct device *dev, void *model)

De-register a previously registered neural network model.

De-register a previously registered neural network model from the GNA device. De-registration may be done to free up memory for registering another model. Once de-registered, the model can no longer be used to perform inference.

Parameters
- dev – Pointer to the device structure for the driver instance.
- model – Model handle output by gna_register_model API

Return values
- 0 – If de-registration of the model is successful.
- A – Negative error code in case of a failure.

static inline int gna_infer(const struct device *dev, struct gna_inference_req *req, gna_callback callback)

Perform inference on a model with input vectors.

Make an inference request on a previously registered model with an input data vector. A callback is provided for notification of inference completion.

Parameters
- dev – Pointer to the device structure for the driver instance.
- req – Information required to perform inference on a neural network
- callback – A callback function to notify inference completion

Return values
- 0 – If the request is accepted
- A – Negative error code in case of a failure.

#include <gna.h>

GNA driver configuration structure. Currently empty.

#include <gna.h>

GNA Neural Network model header. Describes the key parameters of the neural network model.
struct gna_model_info
#include <gna.h> GNA Neural Network model information to be provided by application during model registration

struct gna_inference_req
#include <gna.h> Request to perform inference on the given neural network model

struct gna_inference_stats
#include <gna.h> Statistics of the inference operation returned after completion

struct gna_inference_resp
#include <gna.h> Structure containing a response to the inference request

7.3.17 GPIO

Overview

Configuration Options

Related configuration options:
- CONFIG_GPIO

API Reference

group gpio_interface
GPIO Driver APIs.

GPIO input/output configuration flags

GPIO_INPUT
Enables pin as input.

GPIO_OUTPUT
Enables pin as output, no change to the output state.

GPIO_DISCONNECTED
Disables pin for both input and output.

GPIO_OUTPUT_LOW
Configures GPIO pin as output and initializes it to a low state.

GPIO_OUTPUT_HIGH
Configures GPIO pin as output and initializes it to a high state.

GPIO_OUTPUT_INACTIVE
Configures GPIO pin as output and initializes it to a logic 0.
GPIO_OUTPUT_ACTIVE
Configures GPIO pin as output and initializes it to a logic 1.

**GPIO interrupt configuration flags**

The GPIO_INT_* flags are used to specify how input GPIO pins will trigger interrupts. The interrupts can be sensitive to pin physical or logical level. Interrupts sensitive to pin logical level take into account GPIO_ACTIVE_LOW flag. If a pin was configured as Active Low, physical level low will be considered as logical level 1 (an active state), physical level high will be considered as logical level 0 (an inactive state).

**GPIO_INT_DISABLE**
Disables GPIO pin interrupt.

**GPIO_INT_EDGE_RISING**
Configures GPIO interrupt to be triggered on pin rising edge and enables it.

**GPIO_INT_EDGE_FALLING**
Configures GPIO interrupt to be triggered on pin falling edge and enables it.

**GPIO_INT_EDGE_BOTH**
Configures GPIO interrupt to be triggered on pin rising or falling edge and enables it.

**GPIO_INT_LEVEL_LOW**
Configures GPIO interrupt to be triggered on pin physical level low and enables it.

**GPIO_INT_LEVEL_HIGH**
Configures GPIO interrupt to be triggered on pin physical level high and enables it.

**GPIO_INT_EDGE_TO_INACTIVE**
Configures GPIO interrupt to be triggered on pin state change to logical level 0 and enables it.

**GPIO_INT_EDGE_TO_ACTIVE**
Configures GPIO interrupt to be triggered on pin state change to logical level 1 and enables it.

**GPIO_INT_LEVEL_INACTIVE**
Configures GPIO interrupt to be triggered on pin logical level 0 and enables it.

**GPIO_INT_LEVEL_ACTIVE**
Configures GPIO interrupt to be triggered on pin logical level 1 and enables it.

**GPIO pin active level flags**

**GPIO_ACTIVE_LOW**
GPIO pin is active (has logical value ‘1’) in low state.

**GPIO_ACTIVE_HIGH**
GPIO pin is active (has logical value ‘1’) in high state.
GPIO pin drive flags

**GPIO_OPEN_DRAIN**
Configures GPIO output in open drain mode (wired AND).

**Note:** ’Open Drain’ mode also known as ’Open Collector’ is an output configuration which behaves like a switch that is either connected to ground or disconnected.

**GPIO_OPEN_SOURCE**
Configures GPIO output in open source mode (wired OR).

**Note:** ’Open Source' is a term used by software engineers to describe output mode opposite to ’Open Drain’. It behaves like a switch that is either connected to power supply or disconnected. There exist no corresponding hardware schematic and the term is generally unknown to hardware engineers.

GPIO pin bias flags

**GPIO_PULL_UP**
Enables GPIO pin pull-up.

**GPIO_PULL_DOWN**
Enable GPIO pin pull-down.

Defines

**GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, idx)**
Static initializer for a *gpio_dt_spec*.

This returns a static initializer for a *gpio_dt_spec* structure given a devicetree node identifier, a property specifying a GPIO and an index.

Example devicetree fragment:

```markdown
n: node {
  foo-gpios = <&gpio0 1 GPIO_ACTIVE_LOW>,
               <&gpio1 2 GPIO_ACTIVE_LOW>;
}
```

Example usage:

```c
const struct gpio_dt_spec spec = GPIO_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n),
                                                          foo_gpios, 1);
// Initializes 'spec' to:
// {
//   .port = DEVICE_DT_GET(DT_NODELABEL(gpio1)),
//   .pin = 2,
//   .dt_flags = GPIO_ACTIVE_LOW
// }
```
The ‘gpio’ field must still be checked for readiness, e.g. using `device_is_ready()`. It is an error to use this macro unless the node exists, has the given property, and that property specifies a GPIO controller, pin number, and flags as shown above.

**Parameters**
- `node_id` – devicetree node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – logical index into “prop”

**Returns**
- static initializer for a struct `gpio_dt_spec` for the property

`GPIO_DT_SPEC_GET_BY_IDX_OR(node_id, prop, idx, default_value)`

Like `GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, idx)`, with a fallback to a default value.

If the devicetree node identifier ‘node_id’ refers to a node with a property ‘prop’, this expands to `GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, idx)`. The `default_value` parameter is not expanded in this case.

Otherwise, this expands to `default_value`.

**Parameters**
- `node_id` – devicetree node identifier
- `prop` – lowercase-and-underscores property name
- `idx` – logical index into “prop”
- `default_value` – fallback value to expand to

**Returns**
- static initializer for a struct `gpio_dt_spec` for the property, or `default_value` if the node or property do not exist

`GPIO_DT_SPEC_GET(node_id, prop)`

Equivalent to `GPIO_DT_SPEC_GET_BY_IDX(node_id, prop, 0)`.

**See also:**
`GPIO_DT_SPEC_GET_BY_IDX()`

**Parameters**
- `node_id` – devicetree node identifier
- `prop` – lowercase-and-underscores property name

**Returns**
- static initializer for a struct `gpio_dt_spec` for the property

`GPIO_DT_SPEC_GET_OR(node_id, prop, default_value)`

Equivalent to `GPIO_DT_SPEC_GET_BY_IDX_OR(node_id, prop, 0, default_value)`.

**See also:**
`GPIO_DT_SPEC_GET_BY_IDX_OR()`
• default_value – fallback value to expand to

Returns
static initializer for a struct gpio_dt_spec for the property

GPIO_DT_SPEC_INST_GET_BY_IDX(inst, prop, idx)
Static initializer for a gpio_dt_spec from a DT_DRV_COMPAT instance's GPIO property at an index.

See also:
GPIO_DT_SPEC_GET_BY_IDX() parameters

Returns
static initializer for a struct gpio_dt_spec for the property

GPIO_DT_SPEC_INST_GET_BY_IDX_OR(inst, prop, idx, default_value)
Static initializer for a gpio_dt_spec from a DT_DRV_COMPAT instance's GPIO property at an index, with fallback.

See also:
GPIO_DT_SPEC_GET_BY_IDX() parameters

Returns
static initializer for a struct gpio_dt_spec for the property

GPIO_DT_SPEC_INST_GET(inst, prop)
Equivalent to GPIO_DT_SPEC_INST_GET_BY_IDX(inst, prop, 0).

See also:
GPIO_DT_SPEC_INST_GET_BY_IDX() parameters

Returns
static initializer for a struct gpio_dt_spec for the property

7.3. Peripherals
GPIO_DT_SPEC_INST_GET_OR(inst, prop, default_value)
    Equivalent to GPIO_DT_SPEC_INST_GET_BY_IDX_OR(inst, prop, 0, default_value).

See also:
    GPIO_DT_SPEC_INST_GET_BY_IDX()

Parameters
    • inst – DT_DRV_COMPAT instance number
    • prop – lowercase-and-underscores property name
    • default_value – fallback value to expand to

Returns
    static initializer for a struct gpio_dt_spec for the property

GPIO_MAX_PINS_PER_PORT
    Maximum number of pins that are supported by gpio_port_pins_t.

Typedefs

typedef uint32_t gpio_port_pins_t
    Identifies a set of pins associated with a port.
    The pin with index n is present in the set if and only if the bit identified by (1U << n) is set.

typedef uint32_t gpio_port_value_t
    Provides values for a set of pins associated with a port.
    The value for a pin with index n is high (physical mode) or active (logical mode) if and only if
    the bit identified by (1U << n) is set. Otherwise the value for the pin is low (physical mode)
    or inactive (logical mode).
    Values of this type are often paired with a gpio_port_pins_t value that specifies which en-
    coded pin values are valid for the operation.

typedef uint8_t gpio_pin_t
    Provides a type to hold a GPIO pin index.
    This reduced-size type is sufficient to record a pin number, e.g. from a devicetree GPIOS
    property.

typedef uint16_t gpio_dt_flags_t
    Provides a type to hold GPIO devicetree flags.
    All GPIO flags that can be expressed in devicetree fit in the low 16 bits of the full flags field,
    so use a reduced-size type to record that part of a GPIOS property.
    The lower 8 bits are used for standard flags. The upper 8 bits are reserved for SoC specific
    flags.

typedef uint32_t gpio_flags_t
    Provides a type to hold GPIO configuration flags.
    This type is sufficient to hold all flags used to control GPIO configuration, whether pin or
    interrupt.
typedef void (*gpio_callback_handler_t)(const struct device *port, struct gpio_callback *cb, gpio_port_pins_t pins)

Define the application callback handler function signature.

Note: cb pointer can be used to retrieve private data through CONTAINER_OF() if original struct gpio_callback is stored in another private structure.

Param port
Device struct for the GPIO device.

Param cb
Original struct gpio_callback owning this handler

Param pins
Mask of pins that triggers the callback handler

Functions

int gpio_pin_interrupt_configure(const struct device *port, gpio_pin_t pin, gpio_flags_t flags)
Configure pin interrupt.

Note: This function can also be used to configure interrupts on pins not controlled directly by the GPIO module. That is, pins which are routed to other modules such as I2C, SPI, UART.

Parameters

• port – Pointer to device structure for the driver instance.
• pin – Pin number.
• flags – Interrupt configuration flags as defined by GPIO_INT_.*

Return values

• 0 – If successful.
• -ENOTSUP – If any of the configuration options is not supported (unless otherwise directed by flag documentation).
• -EINVAL – Invalid argument.
• -EBUSY – Interrupt line required to configure pin interrupt is already in use.
• -E10 – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_interrupt_configure_dt(const struct gpio_dt_spec *spec, gpio_flags_t flags)
Configure pin interrupts from a gpio_dt_spec.
This is equivalent to:
gpio_pin_interrupt_configure(spec->port, spec->pin, flags);
The spec->dt_flags value is not used.

Parameters

• spec – GPIO specification from devicetree
• flags – interrupt configuration flags

7.3. Peripherals
int gpio_pin_configure(const struct device *port, gpio_pin_t pin, gpio_flags_t flags)

Configure a single pin.

Parameters
- port – Pointer to device structure for the driver instance.
- pin – Pin number to configure.

Return values
- 0 – If successful.
- -ENOTSUP – if any of the configuration options is not supported (unless otherwise directed by flag documentation).
- -EINVAL – Invalid argument.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_configure_dt(const struct gpio_dt_spec *spec, gpio_flags_t extra_flags)

Configure a single pin from a gpio_dt_spec and some extra flags.

This is equivalent to:

```c
gpio_pin_configure(spec->port, spec->pin, spec->dt_flags | extra_flags);
```

Parameters
- spec – GPIO specification from devicetree
- extra_flags – additional flags

Returns
- a value from gpio_pin_configure()

int gpio_port_get_direction(const struct device *port, gpio_port_pins_t map, gpio_port_pins_t *inputs, gpio_port_pins_t *outputs)

static inline int gpio_pin_is_input(const struct device *port, gpio_pin_t pin)

Check if pin is configured for input.

Parameters
- port – Pointer to device structure for the driver instance.
- pin – Pin number to query the direction of

Return values
- 1 – if pin is configured as GPIO_INPUT.
- 0 – if pin is not configured as GPIO_INPUT.
- -ENOSYS – if the underlying driver does not support this call.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.
static inline int gpio_pin_is_output(const struct device *port, gpio_pin_t pin)
Check if pin is configured for output.

Parameters

• port – Pointer to device structure for the driver instance.
• pin – Pin number to query the direction of

Return values

• 1 – if pin is configured as GPIO_OUTPUT.
• 0 – if pin is not configured as GPIO_OUTPUT.
• -ENOSYS – if the underlying driver does not support this call.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

int gpio_pin_get_config(const struct device *port, gpio_pin_t pin, gpio_flags_t *flags)
Get a configuration of a single pin.

Parameters

• port – Pointer to device structure for the driver instance.
• pin – Pin number which configuration is get.
• flags – Pointer to variable in which the current configuration will be stored if function is successful.

Return values

• 0 – If successful.
• -ENOSYS – if getting current pin configuration is not implemented by the driver.
• -EINVAL – Invalid argument.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get_config_dt(const struct gpio_dt_spec *spec, gpio_flags_t *flags)
Get a configuration of a single pin from a gpio_dt_spec.
This is equivalent to:

```
gpio_pin_get_config(spec->port, spec->pin, flags);
```

Parameters

• spec – GPIO specification from devicetree
• flags – Pointer to variable in which the current configuration will be stored if function is successful.

Returns

a value from gpio_pin_configure()

int gpio_port_get_raw(const struct device *port, gpio_port_value_t *value)
Get physical level of all input pins in a port.
A low physical level on the pin will be interpreted as value 0. A high physical level will be interpreted as value 1. This function ignores GPIO_ACTIVE_LOW flag.

Value of a pin with index n will be represented by bit n in the returned port value.

Parameters
• port – Pointer to the device structure for the driver instance.
• value – Pointer to a variable where pin values will be stored.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_port_get(const struct device *port, gpio_port_value_t *value)

Get logical level of all input pins in a port.

Get logical level of an input pin taking into account GPIO_ACTIVE_LOW flag. If pin is configured as Active High, a low physical level will be interpreted as logical value 0. If pin is configured as Active Low, a low physical level will be interpreted as logical value 1.

Value of a pin with index n will be represented by bit n in the returned port value.

**Parameters**
• port – Pointer to the device structure for the driver instance.
• value – Pointer to a variable where pin values will be stored.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

int gpio_port_set_masked_raw(const struct device *port, gpio_port_pins_t mask, gpio_port_value_t value)

Set physical level of output pins in a port.

Writing value 0 to the pin will set it to a low physical level. Writing value 1 will set it to a high physical level. This function ignores GPIO_ACTIVE_LOW flag.

Pin with index n is represented by bit n in mask and value parameter.

**Parameters**
• port – Pointer to the device structure for the driver instance.
• mask – Mask indicating which pins will be modified.
• value – Value assigned to the output pins.

**Return values**
• 0 – If successful.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_port_set_masked(const struct device *port, gpio_port_pins_t mask, gpio_port_value_t value)

Set logical level of output pins in a port.

Set logical level of an output pin taking into account GPIO_ACTIVE_LOW flag. Value 0 sets the pin in logical 0 / inactive state. Value 1 sets the pin in logical 1 / active state. If pin is configured as Active High, the default, setting it in inactive state will force the pin to a low physical level. If pin is configured as Active Low, setting it in inactive state will force the pin to a high physical level.

Pin with index n is represented by bit n in mask and value parameter.
Parameters

- **port** – Pointer to the device structure for the driver instance.
- **mask** – Mask indicating which pins will be modified.
- **value** – Value assigned to the output pins.

Return values

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
int gpio_port_set_bits_raw(const struct device *port, gpio_port_pins_t pins)
```

Set physical level of selected output pins to high.

Parameters

- **port** – Pointer to the device structure for the driver instance.
- **pins** – Value indicating which pins will be modified.

Return values

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
static inline int gpio_port_set_bits(const struct device *port, gpio_port_pins_t pins)
```

Set logical level of selected output pins to active.

Parameters

- **port** – Pointer to the device structure for the driver instance.
- **pins** – Value indicating which pins will be modified.

Return values

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
int gpio_port_clear_bits_raw(const struct device *port, gpio_port_pins_t pins)
```

Set physical level of selected output pins to low.

Parameters

- **port** – Pointer to the device structure for the driver instance.
- **pins** – Value indicating which pins will be modified.

Return values

- **0** – If successful.
- **-EIO** – I/O error when accessing an external GPIO chip.
- **-EWOULDBLOCK** – if operation would block.

```c
static inline int gpio_port_clear_bits(const struct device *port, gpio_port_pins_t pins)
```

Set logical level of selected output pins to inactive.

Parameters

- **port** – Pointer to the device structure for the driver instance.
- **pins** – Value indicating which pins will be modified.
Return values

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

```c
int gpio_port_toggle_bits(const struct device *port, gpio_port_pins_t pins)
```

Toggle level of selected output pins.

**Parameters**

- *port* – Pointer to the device structure for the driver instance.
- *pins* – Value indicating which pins will be modified.

**Return values**

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

```c
static inline int gpio_port_set_clr_bits_raw(const struct device *port, gpio_port_pins_t set_pins, gpio_port_pins_t clear_pins)
```

Set physical level of selected output pins.

**Parameters**

- *port* – Pointer to the device structure for the driver instance.
- *set_pins* – Value indicating which pins will be set to high.
- *clear_pins* – Value indicating which pins will be set to low.

**Return values**

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

```c
static inline int gpio_port_set_clr_bits(const struct device *port, gpio_port_pins_t set_pins, gpio_port_pins_t clear_pins)
```

Set logical level of selected output pins.

**Parameters**

- *port* – Pointer to the device structure for the driver instance.
- *set_pins* – Value indicating which pins will be set to active.
- *clear_pins* – Value indicating which pins will be set to inactive.

**Return values**

- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

```c
static inline int gpio_pin_get_raw(const struct device *port, gpio_pin_t pin)
```

Get physical level of an input pin.

A low physical level on the pin will be interpreted as value 0. A high physical level will be interpreted as value 1. This function ignores GPIO_ACTIVE_LOW flag.

**Parameters**
• port – Pointer to the device structure for the driver instance.
• pin – Pin number.

Return values
• 1 – If pin physical level is high.
• 0 – If pin physical level is low.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get(const struct device *port, gpio_pin_t pin)
Get logical level of an input pin.

Get logical level of an input pin taking into account GPIO_ACTIVE_LOW flag. If pin is configured as Active High, a low physical level will be interpreted as logical value 0. If pin is configured as Active Low, a low physical level will be interpreted as logical value 1.

Note: If pin is configured as Active High, the default, gpio_pin_get() function is equivalent to gpio_pin_get_raw().

Parameters
• port – Pointer to the device structure for the driver instance.
• pin – Pin number.

Return values
• 1 – If pin logical value is 1 / active.
• 0 – If pin logical value is 0 / inactive.
• -EIO – I/O error when accessing an external GPIO chip.
• -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_get_dt(const struct gpio_dt_spec *spec)
Get logical level of an input pin from a gpio_dt_spec.

This is equivalent to:

gpio_pin_get(spec->port, spec->pin);

Parameters
• spec – GPIO specification from devicetree

Returns
a value from gpio_pin_get()

static inline int gpio_pin_set_raw(const struct device *port, gpio_pin_t pin, int value)
Set physical level of an output pin.

Writing value 0 to the pin will set it to a low physical level. Writing any value other than 0 will set it to a high physical level. This function ignores GPIO_ACTIVE_LOW flag.

Parameters
• port – Pointer to the device structure for the driver instance.
• pin – Pin number.
• value – Value assigned to the pin.

Return values
• 0 – If successful.
static inline int gpio_pin_set(const struct device *port, gpio_pin_t pin, int value)
Set logical level of an output pin.

Set logical level of an output pin taking into account GPIO_ACTIVE_LOW flag. Value 0 sets the pin in logical 0 / inactive state. Any value other than 0 sets the pin in logical 1 / active state. If pin is configured as Active High, the default, setting it in inactive state will force the pin to a low physical level. If pin is configured as Active Low, setting it in inactive state will force the pin to a high physical level.

Note: If pin is configured as Active High, gpio_pin_set() function is equivalent to gpio_pin_set_raw().

Parameters
- port – Pointer to the device structure for the driver instance.
- pin – Pin number.
- value – Value assigned to the pin.

Return values
- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.

static inline int gpio_pin_set_dt(const struct gpio_dt_spec *spec, int value)
Set logical level of a output pin from a gpio_dt_spec.

This is equivalent to:

gpio_pin_set(spec->port, spec->pin, value);

Parameters
- spec – GPIO specification from devicetree
- value – Value assigned to the pin.

Returns
- a value from gpio_pin_set()

static inline int gpio_pin_toggle(const struct device *port, gpio_pin_t pin)
Toggle pin level.

Parameters
- port – Pointer to the device structure for the driver instance.
- pin – Pin number.

Return values
- 0 – If successful.
- -EIO – I/O error when accessing an external GPIO chip.
- -EWOULDBLOCK – if operation would block.
```c
gpio_pin_toggle(spec->port, spec->pin);
```

### Parameters
- `spec` – GPIO specification from devicetree

### Returns
A value from `gpio_pin_toggle()`

---

```c
static inline void gpio_init_callback(struct gpio_callback *callback, gpio_callback_handler_t handler, gpio_port_pins_t pin_mask)
```

Helper to initialize a struct `gpio_callback` properly.

### Parameters
- `callback` – A valid Application's callback structure pointer.
- `handler` – A valid handler function pointer.
- `pin_mask` – A bit mask of relevant pins for the handler

---

```c
static inline int gpio_add_callback(const struct device *port, struct gpio_callback *callback)
```

Add an application callback.

**Note:** enables to add as many callbacks as needed on the same port.

---

**Note:** Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current GPIO event is not specified.

---

```c
static inline int gpio_remove_callback(const struct device *port, struct gpio_callback *callback)
```

Remove an application callback.

**Note:** enables to remove as many callbacks as added through `gpio_add_callback()`.

---

**Warning:** It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. `callback`. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

### Parameters
- `port` – Pointer to the device structure for the driver instance.
- `callback` – A valid Application's callback structure pointer.

### Returns
0 if successful, negative errno code on failure.
int gpio_get_pending_int(const struct device *dev)

Function to get pending interrupts.

The purpose of this function is to return the interrupt status register for the device. This is especially useful when waking up from low power states to check the wake up source.

Parameters

• dev – Pointer to the device structure for the driver instance.

Return values

• status – != 0 if at least one gpio interrupt is pending.
• 0 – if no gpio interrupt is pending.

struct gpio_dt_spec

#include <gpio.h> Container for GPIO pin information specified in devicetree.

This type contains a pointer to a GPIO device, pin number for a pin controlled by that device, and the subset of pin configuration flags which may be given in devicetree.

See also:

GPIO_DT_SPEC_GET_BY_IDX

See also:

GPIO_DT_SPEC_GET_BY_IDX_OR

See also:

GPIO_DT_SPEC_GET

See also:

GPIO_DT_SPEC_GET_OR

Public Members

const struct device *port

GPIO device controlling the pin

gpio_pin_t pin

The pin's number on the device

gpio_dt_flags_t dt_flags

The pin's configuration flags as specified in devicetree

struct gpio_driver_config

#include <gpio.h> This structure is common to all GPIO drivers and is expected to be the first element in the object pointed to by the config field in the device structure.

struct gpio_driver_data

#include <gpio.h> This structure is common to all GPIO drivers and is expected to be the first element in the driver's struct driver_data declaration.
struct gpio_callback

#include <gpio.h> GPIO callback structure.

Used to register a callback in the driver instance callback list. As many callbacks as needed can be added as long as each of them are unique pointers of struct gpio_callback. Beware such structure should not be allocated on stack.

Note: To help setting it, see gpio_init_callback() below

Public Members

sys_snode_t node
This is meant to be used in the driver and the user should not mess with it (see drivers/gpio/gpio_utils.h)

gpio_callback_handler_t handler
Actual callback function being called when relevant.

gpio_port_pins_t pin_mask
A mask of pins the callback is interested in, if 0 the callback will never be called. Such pin_mask can be modified whenever necessary by the owner, and thus will affect the handler being called or not. The selected pins must be configured to trigger an interrupt.

7.3.18 Hardware Information

Overview

The HW Info API provides access to hardware information such as device identifiers and reset cause flags.

Reset cause flags can be used to determine why the device was reset; for example due to a watchdog timeout or due to power cycling. Different devices support different subset of flags. Use hwinfo_get_supported_reset_cause() to retrieve the flags that are supported by that device.

Configuration Options

Related configuration options:

• CONFIG_HWINFO

API Reference

group hwinfo_interface
Hardware Information Interface.

Defines

RESET_PIN
RESET_SOFTWARE
RESET_BROWNOUT
RESET_POR
RESET_WATCHDOG
RESET_DEBUG
RESET_SECURITY
RESET_LOW_POWER_WAKE
RESET_CPU_LOCKUP
RESET_PARITY
RESET_PLL
RESET_CLOCK
RESET_HARDWARE
RESET_USER
RESET_TEMPERATURE

Functions

ssize_t hwinfo_get_device_id(uint8_t *buffer, size_t length)

Copy the device id to a buffer.

This routine copies “length” number of bytes of the device ID to the buffer. If the device ID is smaller then length, the rest of the buffer is left unchanged. The ID depends on the hardware and is not guaranteed unique.

Drivers are responsible for ensuring that the ID data structure is a sequence of bytes. The returned ID value is not supposed to be interpreted based on vendor-specific assumptions of byte order. It should express the identifier as a raw byte sequence, doing any endian conversion necessary so that a hex representation of the bytes produces the intended serial number.

Parameters

• buffer – Buffer to write the ID to.
• length – Max length of the buffer.

Return values

• size – of the device ID copied.
-ENOSYS – if there is no implementation for the particular device.

any – negative value on driver specific errors.

### `int hwinfo_get_reset_cause(uint32_t *cause)`

Retrieve cause of device reset.

This routine retrieves the flags that indicate why the device was reset.

On some platforms the reset cause flags accumulate between successive resets and this routine may return multiple flags indicating all reset causes since the device was powered on. If you need to retrieve the cause only for the most recent reset call `hwinfo_clear_reset_cause` after calling this routine to clear the hardware flags before the next reset event.

Successive calls to this routine will return the same value, unless `hwinfo_clear_reset_cause` has been called.

**Parameters**

- cause – OR'd reset_cause flags

**Return values**

- zero – if successful.
- -ENOSYS – if there is no implementation for the particular device.
- any – negative value on driver specific errors.

### `int hwinfo_clear_reset_cause(void)`

Clear cause of device reset.

Clears reset cause flags.

**Return values**

- zero – if successful.
- -ENOSYS – if there is no implementation for the particular device.
- any – negative value on driver specific errors.

### `int hwinfo_get_supported_reset_cause(uint32_t *supported)`

Get supported reset cause flags.

Retrieves all reset_cause flags that are supported by this device.

**Parameters**

- supported – OR'd reset_cause flags that are supported

**Return values**

- zero – if successful.
- -ENOSYS – if there is no implementation for the particular device.
- any – negative value on driver specific errors.

### 7.3.19 I2C EEPROM Target

#### Overview

#### API Reference
I2C EEPROM Target Driver API.

### Functions

```c
int eeprom_target_program(const struct device *dev, const uint8_t *eeprom_data, unsigned int length)
```

Program memory of the virtual EEPROM.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `eeprom_data` – Pointer of data to program into the virtual eeprom memory
- `length` – Length of data to program into the virtual eeprom memory

**Return values**

- `0` – If successful.
- `-EINVAL` – Invalid data size

```c
int eeprom_target_read(const struct device *dev, uint8_t *eeprom_data, unsigned int offset)
```

Read single byte of virtual EEPROM memory.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `eeprom_data` – Pointer of byte where to store the virtual eeprom memory
- `offset` – Offset into EEPROM memory where to read the byte

**Return values**

- `0` – If successful.
- `-EINVAL` – Invalid data pointer or offset

### 7.3.20 I2C

#### Overview

**Note:** The terminology used in Zephyr I2C APIs follows that of the NXP I2C Bus Specification Rev 7.0. These changed from previous revisions as of its release October 1, 2021.

I2C (Inter-Integrated Circuit, pronounced “eye squared see”) is a commonly-used two-signal shared peripheral interface bus. Many system-on-chip solutions provide controllers that communicate on an I2C bus. Devices on the bus can operate in two roles: as a “controller” that initiates transactions and controls the clock, or as a “target” that responds to transaction commands. An I2C controller on a given SoC will generally support the controller role, and some will also support the target mode. Zephyr has API for both roles.

**I2C Controller API** Zephyr's I2C controller API is used when an I2C peripheral controls the bus, in particularly the start and stop conditions and the clock. This is the most common mode, used to interact with I2C devices like sensors and serial memory.

This API is supported in all in-tree I2C peripheral drivers and is considered stable.
**I2C Target API**  Zephyr’s I2C target API is used when an I2C peripheral responds to transactions initiated by a different controller on the bus. It might be used for a Zephyr application with transducer roles that are controlled by another device such as a host processor.

This API is supported in very few in-tree I2C peripheral drivers. The API is considered experimental, as it is not compatible with the capabilities of all I2C peripherals supported in controller mode.

**Configuration Options**

Related configuration options:
- `CONFIG_I2C`

**API Reference**

```c

group i2c_interface

I2C Interface.

Defines

I2C_SPEED_STANDARD
    I2C Standard Speed: 100 kHz

I2C_SPEED_FAST
    I2C Fast Speed: 400 kHz

I2C_SPEED_FAST_PLUS
    I2C Fast Plus Speed: 1 MHz

I2C_SPEED_HIGH
    I2C High Speed: 3.4 MHz

I2C_SPEED_ULTRA
    I2C Ultra Fast Speed: 5 MHz

I2C_SPEED_DT
    Device Tree specified speed

I2C_SPEED_SHIFT

I2C_SPEED_SET(speed)

I2C_SPEED_MASK

I2C_SPEED_GET(cfg)

I2C_ADDR_10_BITS
    Use 10-bit addressing. DEPRECATED - Use I2C_MSG_ADDR_10_BITS instead.
```

7.3. Peripherals
I2C_MODE_CONTROLLER
Peripheral to act as Controller.

I2C_MODE_MASTER

Deprecated:
Use I2C_MODE_CONTROLLER instead.

I2C_DT_SPEC_GET_ON_I3C(node_id)
Structure initializer for i2c_dt_spec from devicetree (on I3C bus)
This helper macro expands to a static initializer for a struct i2c_dt_spec by reading the relevant bus and address data from the devicetree.

Parameters
• node_id – Devicetree node identifier for the I2C device whose struct i2c_dt_spec to create an initializer for

I2C_DT_SPEC_GET_ON_I2C(node_id)
Structure initializer for i2c_dt_spec from devicetree (on I2C bus)
This helper macro expands to a static initializer for a struct i2c_dt_spec by reading the relevant bus and address data from the devicetree.

Parameters
• node_id – Devicetree node identifier for the I2C device whose struct i2c_dt_spec to create an initializer for

I2C_DT_SPEC_GET(node_id)
Structure initializer for i2c_dt_spec from devicetree.
This helper macro expands to a static initializer for a struct i2c_dt_spec by reading the relevant bus and address data from the devicetree.

Parameters
• node_id – Devicetree node identifier for the I2C device whose struct i2c_dt_spec to create an initializer for

I2C_DT_SPEC_INST_GET(inst)
Structure initializer for i2c_dt_spec from devicetree instance.
This is equivalent to I2C_DT_SPEC_GET(DT_DRV_INST(inst)).

Parameters
• inst – Devicetree instance number

I2C_MSG_WRITE
Write message to I2C bus.

I2C_MSG_READ
Read message from I2C bus.

I2C_MSG_STOP
Send STOP after this message.
I2C_MSG_RESTART

RESTART I2C transaction for this message.

**Note:** Not all I2C drivers have or require explicit support for this feature. Some drivers require this be present on a read message that follows a write, or vice-versa. Some drivers will merge adjacent fragments into a single transaction using this flag; some will not.

I2C_MSG_ADDR_10_BITS

Use 10-bit addressing for this message.

**Note:** Not all SoC I2C implementations support this feature.

I2C_TARGET_FLAGS_ADDR_10_BITS

Target device responds to 10-bit addressing.

I2C_DEVICE_DT_DEFINE(node_id, init_fn, pm, data, config, level, prio, api, ...)

Like `DEVICE_DT_DEFINE()` with I2C specifics.

Defines a device which implements the I2C API. May generate a custom `device_state` container struct and `init_fn` wrapper when needed depending on I2C CONFIG_I2C_STATS.

**Parameters**

- `node_id` – The devicetree node identifier.
- `init_fn` – Name of the init function of the driver.
- `pm` – PM device resources reference (NULL if device does not use PM).
- `data` – Pointer to the device's private data.
- `config` – The address to the structure containing the configuration information for this instance of the driver.
- `level` – The initialization level. See SYS_INIT() for details.
- `prio` – Priority within the selected initialization level. See SYS_INIT() for details.
- `api` – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

I2C_DEVICE_DT_INST_DEFINE(inst, ...)

Like `I2C_DEVICE_DT_DEFINE()` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

- `inst` – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to `I2C_DEVICE_DT_DEFINE()`.
- `...` – other parameters as expected by `I2C_DEVICE_DT_DEFINE()`.

**Typedefs**

typedef void (*i2c_callback_t)(const struct device *dev, int result, void *data)

I2C callback for asynchronous transfer requests.

**Param** dev

I2C device which is notifying of transfer completion or error
**Param result**
Result code of the transfer request. 0 is success, -errno for failure.

**Param data**
Transfer requester supplied data which is passed along to the callback.

typedef int (*i2c_target_write_requested_cb_t)(struct i2c_target_config *config)
Function called when a write to the device is initiated.

This function is invoked by the controller when the bus completes a start condition for a write operation to the address associated with a particular device.

A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Return**
0 if the write is accepted, or a negative error code.

typedef int (*i2c_target_write_received_cb_t)(struct i2c_target_config *config, uint8_t val)
Function called when a write to the device is continued.

This function is invoked by the controller when it completes reception of a byte of data in an ongoing write operation to the device.

A success return shall cause the controller to ACK the next byte received. An error return shall cause the controller to NACK the next byte received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
the byte received by the controller.

**Return**
0 if more data can be accepted, or a negative error code.

typedef int (*i2c_target_read_requested_cb_t)(struct i2c_target_config *config, uint8_t *val)
Function called when a read from the device is initiated.

This function is invoked by the controller when the bus completes a start condition for a read operation from the address associated with a particular device.

The value returned in *val will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
pointer to storage for the first byte of data to return for the read request.

**Return**
0 if more data can be requested, or a negative error code.

typedef int (*i2c_target_read_processed_cb_t)(struct i2c_target_config *config, uint8_t *val)
Function called when a read from the device is continued.
This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device.

The value returned in *val will be transmitted. A success return shall cause the controller to react to additional read operations. An error return shall cause the controller to ignore bus operations until a new start condition is received.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Param val**
pointer to storage for the next byte of data to return for the read request.

**Return**
0 if data has been provided, or a negative error code.

typedef int (*i2c_target_stop_cb_t)(struct i2c_target_config *config)

Function called when a stop condition is observed after a start condition addressed to a particular device.

This function is invoked by the controller when the bus is ready to provide additional data for a read operation from the address associated with the device device. After the function returns the controller shall enter a state where it is ready to react to new start conditions.

**Param config**
the configuration structure associated with the device to which the operation is addressed.

**Return**
Ignored.

**Functions**

static inline void i2c_xfer_stats(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs)

Updates the i2c stats for i2c transfers.

**Parameters**

- dev – I2C device to update stats for
- msgs – Array of struct i2c_msg
- num_msgs – Number of i2c_msgs

int i2c_configure(const struct device *dev, uint32_t dev_config)

Configure operation of a host controller.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- dev_config – Bit-packed 32-bit value to the device runtime configuration for the I2C controller.

**Return values**

- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
int i2c_get_config(const struct device *dev, uint32_t *dev_config)

Get configuration of a host controller.

This routine provides a way to get current configuration. It is allowed to call the function before i2c_configure, because some I2C ports can be configured during init process. However, if the I2C port is not configured, i2c_get_config returns an error.

i2c_get_config can return cached config or probe hardware, but it has to be up to date with current configuration.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `dev_config` – Pointer to return bit-packed 32-bit value of the I2C controller configuration.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.
- `-ERANGE` – Configured I2C frequency is invalid.
- `-ENOSYS` – If get config is not implemented

int i2c_transfer(const struct device *dev, struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr)

Perform data transfer to another I2C device in controller mode.

This routine provides a generic interface to perform data transfer to another I2C device synchronously. Use `i2c_read()`/`i2c_write()` for simple read or write.

The array of message `msgs` must not be NULL. The number of message `num_msgs` may be zero, in which case no transfer occurs.

**Note:** Not all scatter/gather transactions can be supported by all drivers. As an example, a gather write (multiple consecutive `i2c_msg` buffers all configured for `I2C_MSG_WRITE`) may be packed into a single transaction by some drivers, but others may emit each fragment as a distinct write transaction, which will not produce the same behavior. See the documentation of `struct i2c_msg` for limitations on support for multi-message bus transactions.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `msgs` – Array of messages to transfer.
- `num_msgs` – Number of messages to transfer.
- `addr` – Address of the I2C target device.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error.

static inline int i2c_transfer_dt(const struct i2c_dt_spec *spec, struct i2c_msg *msgs, uint8_t num_msgs)

Perform data transfer to another I2C device in controller mode.

This is equivalent to:
```c
i2c_transfer(spec->bus, msgs, num_msgs, spec->addr);
```

**Parameters**
- `spec` – I2C specification from devicetree.
- `msgs` – Array of messages to transfer.
- `num_msgs` – Number of messages to transfer.

**Returns**
a value from `i2c_transfer()`

```c
int i2c_recover_bus(const struct device *dev)
```

Recover the I2C bus.

Attempt to recover the I2C bus.

**Parameters**
- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.

**Return values**
- `0` – If successful
- `-EBUSY` – If bus is not clear after recovery attempt.
- `-EIO` – General input / output error.
- `-ENOSYS` – If bus recovery is not implemented

```c
static inline int i2c_target_register(const struct device *dev, struct i2c_target_config *cfg)
```

Registers the provided config as Target device of a controller.

Enable I2C target mode for the 'dev' I2C bus driver using the provided 'config' struct containing the functions and parameters to send bus events. The I2C target will be registered at the address provided as 'address' struct member. Addressing mode - 7 or 10 bit - depends on the 'flags' struct member. Any I2C bus events related to the target mode will be passed onto I2C target device driver via a set of callback functions provided in the ‘callbacks’ struct member.

Most of the existing hardware allows simultaneous support for controller and target mode. This is however not guaranteed.

**Parameters**
- `dev` – Pointer to the device structure for an I2C controller driver configured in target mode.
- `cfg` – Config struct with functions and parameters used by the I2C driver to send bus events

**Return values**
- `0` – Is successful
- `-EINVAL` – If parameters are invalid
- `-EIO` – General input / output error.
- `-ENOSYS` – If target mode is not implemented

```c
static inline int i2c_target_unregister(const struct device *dev, struct i2c_target_config *cfg)
```

Unregisters the provided config as Target device.

This routine disables I2C target mode for the 'dev' I2C bus driver using the provided 'config' struct containing the functions and parameters to send bus events.
Parameters

- `dev` – Pointer to the device structure for an I2C controller driver configured in target mode.
- `cfg` – Config struct with functions and parameters used by the I2C driver to send bus events

Return values

- `0` – Is successful
- `-EINVAL` – If parameters are invalid
- `-ENOSYS` – If target mode is not implemented

```
int i2c_target_driver_register(const struct device *dev)
```

Instructs the I2C Target device to register itself to the I2C Controller.

This routine instructs the I2C Target device to register itself to the I2C Controller via its parent controller's `i2c_target_register()` API.

Parameters

- `dev` – Pointer to the device structure for the I2C target device (not itself an I2C controller).

Return values

- `0` – Is successful
- `-EINVAL` – If parameters are invalid
- `-EIO` – General input / output error.

```
int i2c_target_driver_unregister(const struct device *dev)
```

Instructs the I2C Target device to unregister itself from the I2C Controller.

This routine instructs the I2C Target device to unregister itself from the I2C Controller via its parent controller's `i2c_target_register()` API.

Parameters

- `dev` – Pointer to the device structure for the I2C target device (not itself an I2C controller).

Return values

- `0` – Is successful
- `-EINVAL` – If parameters are invalid

```
static inline int i2c_write(const struct device *dev, const uint8_t *buf, uint32_t num_bytes, uint16_t addr)
```

Write a set amount of data to an I2C device.

This routine writes a set amount of data synchronously.

Parameters

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `buf` – Memory pool from which the data is transferred.
- `num_bytes` – Number of bytes to write.
- `addr` – Address to the target I2C device for writing.

Return values

- `0` – If successful.
-EIO – General input / output error.

```c
static inline int i2c_write_dt(const struct i2c_dt_spec *spec, const uint8_t *buf, uint32_t num_bytes)
{
    Write a set amount of data to an I2C device.

    This is equivalent to:

    i2c_write(spec->bus, buf, num_bytes, spec->addr);
}
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `buf` – Memory pool from which the data is transferred.
- `num_bytes` – Number of bytes to write.

**Returns**

A value from `i2c_write()`

```c
static inline int i2c_read(const struct device *dev, uint8_t *buf, uint32_t num_bytes, uint16_t addr)
{
    Read a set amount of data from an I2C device.

    This routine reads a set amount of data synchronously.

    **Parameters**

    - `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
    - `buf` – Memory pool that stores the retrieved data.
    - `num_bytes` – Number of bytes to read.
    - `addr` – Address of the I2C device being read.

    **Return values**

    - 0 – If successful.
    - -EIO – General input / output error.

    `i2c_read()`

    ```c
    static inline int i2c_read_dt(const struct i2c_dt_spec *spec, uint8_t *buf, uint32_t num_bytes)
    {
        Read a set amount of data from an I2C device.

        This is equivalent to:

        i2c_read(spec->bus, buf, num_bytes, spec->addr);
    }
    ```

    **Parameters**

    - `spec` – I2C specification from devicetree.
    - `buf` – Memory pool that stores the retrieved data.
    - `num_bytes` – Number of bytes to read.

    **Returns**

    A value from `i2c_read()`

    ```c
    static inline int i2c_write_read(const struct device *dev, uint16_t addr, const void *write_buf, size_t num_write, void *read_buf, size_t num_read)
    {
        Write then read data from an I2C device.
    }
    ```

7.3. Peripherals
This supports the common operation “this is what I want”, “now give it to me” transaction pair through a combined write-then-read bus transaction.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `addr` – Address of the I2C device
- `write_buf` – Pointer to the data to be written
- `num_write` – Number of bytes to write
- `read_buf` – Pointer to storage for read data
- `num_read` – Number of bytes to read

**Return values**

- 0 – if successful
- negative – on error.

```c
static inline int i2c_write_read_dt(const struct i2c_dt_spec *spec, const void *write_buf, size_t num_write, void *read_buf, size_t num_read)
```

Write then read data from an I2C device.

This is equivalent to:

```c
call i2c_write_read(spec->bus, spec->addr,
       write_buf, num_write,
       read_buf, num_read);
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `write_buf` – Pointer to the data to be written
- `num_write` – Number of bytes to write
- `read_buf` – Pointer to storage for read data
- `num_read` – Number of bytes to read

**Returns**

a value from `i2c_write_read()`

```c
static inline int i2c_burst_read(const struct device *dev, uint16_t dev_addr, uint8_t start_addr, uint8_t *buf, uint32_t num_bytes)
```

Read multiple bytes from an internal address of an I2C device.

This routine reads multiple bytes from an internal address of an I2C device synchronously. Instances of this may be replaced by `i2c_write_read()`.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `dev_addr` – Address of the I2C device for reading.
- `start_addr` – Internal address from which the data is being read.
- `buf` – Memory pool that stores the retrieved data.
- `num_bytes` – Number of bytes being read.
Return values

- 0 – If successful.
- -EIO – General input / output error.

static inline int i2c_burst_read_dt(const struct i2c_dt_spec *spec, uint8_t start_addr, uint8_t *buf, uint32_t num_bytes)

Read multiple bytes from an internal address of an I2C device.

This is equivalent to:

i2c_burst_read(spec->bus, spec->addr, start_addr, buf, num_bytes);

Parameters

- spec – I2C specification from devicetree.
- start_addr – Internal address from which the data is being read.
- buf – Memory pool that stores the retrieved data.
- num_bytes – Number of bytes to read.

Returns

a value from i2c_burst_read()

static inline int i2c_burst_write(const struct device *dev, uint16_t dev_addr, uint8_t start_addr, const uint8_t *buf, uint32_t num_bytes)

Write multiple bytes to an internal address of an I2C device.

This routine writes multiple bytes to an internal address of an I2C device synchronously.

Warning: The combined write synthesized by this API may not be supported on all I2C devices. Uses of this API may be made more portable by replacing them with calls to i2c_write() passing a buffer containing the combined address and data.

Parameters

- dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
- dev_addr – Address of the I2C device for writing.
- start_addr – Internal address to which the data is being written.
- buf – Memory pool from which the data is transferred.
- num_bytes – Number of bytes being written.

Return values

- 0 – If successful.
- -EIO – General input / output error.

static inline int i2c_burst_write_dt(const struct i2c_dt_spec *spec, uint8_t start_addr, const uint8_t *buf, uint32_t num_bytes)

Write multiple bytes to an internal address of an I2C device.

This is equivalent to:

i2c_burst_write(spec->bus, spec->addr, start_addr, buf, num_bytes);

Parameters
• `spec` – I2C specification from devicetree.
• `start_addr` – Internal address to which the data is being written.
• `buf` – Memory pool from which the data is transferred.
• `num_bytes` – Number of bytes being written.

**Returns**
A value from `i2c_burst_write()`

```c
static inline int i2c_reg_read_byte(const struct device *dev, uint16_t dev_addr, uint8_t reg_addr, uint8_t *value)
```

Read internal register of an I2C device.

This routine reads the value of an 8-bit internal register of an I2C device synchronously.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
- `dev_addr` – Address of the I2C device for reading.
- `reg_addr` – Address of the internal register being read.
- `value` – Memory pool that stores the retrieved register value.

**Return values**

- 0 – If successful.
- -EIO – General input / output error.

```c
static inline int i2c_reg_read_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t *value)
```

Read internal register of an I2C device.

This is equivalent to:

```c
i2c_reg_read_byte(spec->bus, spec->addr, reg_addr, value);
```

**Parameters**

- `spec` – I2C specification from devicetree.
- `reg_addr` – Address of the internal register being read.
- `value` – Memory pool that stores the retrieved register value.

**Returns**
A value from `i2c_reg_read_byte()`

```c
static inline int i2c_reg_write_byte(const struct device *dev, uint16_t dev_addr, uint8_t reg_addr, uint8_t value)
```

Write internal register of an I2C device.

This routine writes a value to an 8-bit internal register of an I2C device synchronously.

**Note:** This function internally combines the register and value into a single bus transaction.

**Parameters**

- `dev` – Pointer to the device structure for an I2C controller driver configured in controller mode.
• dev_addr – Address of the I2C device for writing.
• reg_addr – Address of the internal register being written.
• value – Value to be written to internal register.

Return values
• 0 – If successful.
• -EIO – General input / output error.

static inline int i2c_reg_write_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t value)

Write internal register of an I2C device.
This is equivalent to:

i2c_reg_write_byte(spec->bus, spec->addr, reg_addr, value);

Parameters
• spec – I2C specification from devicetree.
• reg_addr – Address of the internal register being written.
• value – Value to be written to internal register.

Returns
a value from i2c_reg_write_byte()

static inline int i2c_reg_update_byte(const struct device *dev, uint8_t dev_addr, uint8_t reg_addr, uint8_t mask, uint8_t value)

Update internal register of an I2C device.
This routine updates the value of a set of bits from an 8-bit internal register of an I2C device synchronously.

Note: If the calculated new register value matches the value that was read this function will not generate a write operation.

Parameters
• dev – Pointer to the device structure for an I2C controller driver configured in controller mode.
• dev_addr – Address of the I2C device for updating.
• reg_addr – Address of the internal register being updated.
• mask – Bitmask for updating internal register.
• value – Value for updating internal register.

Return values
• 0 – If successful.
• -EIO – General input / output error.

static inline int i2c_reg_update_byte_dt(const struct i2c_dt_spec *spec, uint8_t reg_addr, uint8_t mask, uint8_t value)

Update internal register of an I2C device.
This is equivalent to:
i2c_reg_update_byte(spec->bus, spec->addr, reg_addr, mask, value);

Parameters

- spec – I2C specification from devicetree.
- reg_addr – Address of the internal register being updated.
- mask – Bitmask for updating internal register.
- value – Value for updating internal register.

Returns

A value from i2c_reg_update_byte()

void i2c_dump_msgs(const char *name, const struct i2c_msg *msgs, uint8_t num_msgs, uint16_t addr)

Dump out an I2C message.

Dumps out a list of I2C messages. For any that are writes (W), the data is displayed in hex.

It looks something like this (with name “testing”):

D: I2C msg: testing, addr=56
D:   W len=01:
D: content:
D: 06 1
D: W len=0e:
D: content:
D: 00 01 02 03 04 05 06 07 ........
D: 08 09 0a 0b 0c 0d ........

Parameters

- name – Name of this dump, displayed at the top.
- msgs – Array of messages to dump.
- num_msgs – Number of messages to dump.
- addr – Address of the I2C target device.

struct i2c_dt_spec

#include <i2c.h> Complete I2C DT information.

Param bus

is the I2C bus

Param addr

is the target address

struct i2c_msg

#include <i2c.h> One I2C Message.

This defines one I2C message to transact on the I2C bus.

Note: Some of the configurations supported by this API may not be supported by specific SoC I2C hardware implementations, in particular features related to bus transactions intended to read or write data from different buffers within a single transaction. Invocations
of `i2c_transfer()` may not indicate an error when an unsupported configuration is encountered. In some cases drivers will generate separate transactions for each message fragment, with or without presence of `I2C_MSG_RESTART` in `flags`.

### Public Members

- `uint8_t *buf`
  Data buffer in bytes

- `uint32_t len`
  Length of buffer in bytes

- `uint8_t flags`
  Flags for this message

```c
#include <i2c.h>
```

Structure providing callbacks to be implemented for devices that supports the I2C target API.

This structure may be shared by multiple devices that implement the same API at different addresses on the bus.

```c
#include <i2c.h>
```

Structure describing a device that supports the I2C target API.

Instances of this are passed to the `i2c_target_register()` and `i2c_target_unregister()` functions to indicate addition and removal of a target device, respective.

Fields other than `node` must be initialized by the module that implements the device behavior prior to passing the object reference to `i2c_target_register()`.

### Public Members

- `sys_snnode_t node`
  Private, do not modify

- `uint8_t flags`
  Flags for the target device defined by `I2C_TARGET_FLAGS_*` constants

- `uint16_t address`
  Address for this target device

- `const struct i2c_target_callbacks *callbacks`
  Callback functions

```c
#include <i2c.h>
```

I2C specific device state which allows for `i2c` device class specific additions.
7.3.21 I3C

I3C (Improved Inter-Integrated Circuit) is a two-signal shared peripheral interface bus. Devices on the bus can operate in two roles: as a “controller” that initiates transactions and controls the clock, or as a “target” that responds to transaction commands.

Currently, the API is based on I3C Specification version 1.1.1.

- **I3C Controller API**
  - In-Band Interrupt (IBI)
  - Device Tree
  - Device Drivers for I3C Devices
  - I2C Devices under I3C Bus

- **Configuration Options**

- **API Reference**

**I3C Controller API**

Zephyr’s I3C controller API is used when an I3C controller controls the bus, in particularly the start and stop conditions and the clock. This is the most common mode, used to interact with I3C target devices such as sensors.

Due to the nature of the I3C, there are devices on the bus where they may not have addresses when powered on. Therefore, an additional dynamic address assignment needs to be carried out by the I3C controller. Because of this, the controller needs to maintain separate structures to keep track of device status. This can be done at build time, for example, by creating arrays of device descriptors for both I3C and I2C devices:

```c
static struct i3c_device_desc i3c_device_array[] = I3C DEVICE ARRAY DT INST(inst);
static struct i3c_i2c_device_desc i2c_device_array[] = I3C I2C DEVICE ARRAY DT INST(inst);
```

The macros `I3C DEVICE ARRAY DT INST` and `I3C I2C DEVICE ARRAY DT INST` are helper macros to aid in create arrays of device descriptors corresponding to the devicetree nodes under the I3C controller.

Here is a list of generic steps for initializing the I3C controller and the I3C bus inside the device driver initialization function:

1. Initialize the data structure of the I3C controller device driver instance. The usual device defining macros such as `DEVICE DT INST DEFINE` can be used, and the initialization function provided as a parameter to the macro.
   - The `i3c_addr_slots` and `i3c_dev_list` are structures to aid in address assignments and device list management. If this is being used, this struct needs to be initialized by calling `i3c_addr_slots_init()`. These two structures can also be used with various helper functions.
   - Initialize the device descriptors if needed by the controller driver.

2. Initialize the hardware, including but not limited to:
   - Setup pin mux and directions.
   - Setup the clock for the controller.
   - Power on the hardware.
   - Configure the hardware (e.g. SCL clock frequency).
3. Perform bus initialization. There is a generic helper function, `i3c_bus_init()`, which performs the following steps. This function can be used if the controller does not require any special handling during bus initialization.

1. Do `RSTDAA` to reset dynamic addresses of connected devices. If any connected devices have already been assigned an address, the bookkeeping data structures do not have records of these, for example, at power-on. So it is a good idea to reset and assign them new addresses.

2. Do `DISEC` to disable any events from devices.

3. Do `SETDASA` to use static addresses as dynamic address if so desired.
   - `SETDASA` may not be supported for all connected devices to assign static addresses as dynamic addresses.
   - BCR and DCR need to be obtained separately to populate the relevant fields in the I3C target device descriptor struct.

4. Do `ENTDAA` to start dynamic address assignment, if there are still devices without addresses.
   - If there is a device waiting for an address, it will send its Provisioned ID, BCR, and DCR back. Match the received Provisioned ID to the list of registered I3C devices.
     - If there is a match, assign an address (either from the stated static address if `SETDASA` has not been done, or use a free address).
     - Also, set the BCR and DCR fields in the device descriptor struct.
   - If there is no match, depending on policy, it can be assigned a free address, or the device driver can stop the assignment process and errors out.
   - Note that the I3C API requires device descriptor to function. A device without a device descriptor cannot be accessed through the API.
   - This step can be skipped if there is no connected devices requiring DAA.

5. These are optional but highly recommended:
   - Do `GETMRL` and `GETMWL` to get maximum read/write length.
   - Do `GETMXDS` to get maximum read/write speed and maximum read turnaround time.
   - The helper function, `i3c_bus_init()`, would retrieve basic device information such as BCR, DCR, MRL and MWL.

6. Do `ENEC` to re-enable events from devices.
   - The helper function, `i3c_bus_init()`, only re-enables hot-join events. IBI event should only be enabled when enabling IBI of a device.

**In-Band Interrupt (IBI)** If a target device can generate In-Band Interrupt (IBI), the controller needs to be made aware of it.

- `i3c_tbi_enable()` to enable IBI of a target device.
  - Some controller hardware have IBI slots which need to be programmed so that the controller can recognize incoming IBIs from a particular target device.
    - If the hardware has IBI slots, `i3c_tbi_enable()` needs to program those IBI slots.
    - Note that there are usually limited IBI slots on the controller so this operation may fail.
  - The implementation in driver should also send the `ENEC` command to enable interrupt of this target device.
- `i3c_tbi_disable()` to disable IBI of a target device.
  - If controller hardware makes use of IBI slots, this will remove description of the target device from the slots.
- The implementation in driver should also send the DISEC command to disable interrupt of this target device.

**Device Tree**  Here is an example for defining a I3C controller in device tree:

```plaintext
i3c0: i3c@10000 {
    compatible = "vendor,i3c";
    #address-cells = < 0x3 >;
    #size-cells = < 0x0 >;
    reg = < 0x10000 0x1000 >;
    interrupts = < 0x1F 0x0 >;
    pinctrl-0 = < &pinmux-i3c >;
    pinctrl-names = "default";
    i2c-scl-hz = < 400000 >;
    i3c-scl-hz = < 1200000 >;
    status = "okay";

    i3c-dev0: i3c-dev0@420000ABCD12345678 {
        compatible = "vendor,i3c-dev";
        reg = < 0x42 0xABCD 0x12345678 >;
        status = "okay";
    };

    i2c-dev0: i2c-dev0@380000000000000050 {
        compatible = "vendor-i2c-dev";
        reg = < 0x38 0x0 0x50 >;
        status = "okay";
    };
}
```

**I3C Devices** For I3C devices, the `reg` property has 3 elements:
- The first one is the static address of the device.
  - Can be zero if static address is not used. Address will be assigned during DAA (Dynamic Address Assignment).
  - If non-zero and property `assigned-address` is not set, this will be the address of the device after SETDASA (Set Dynamic Address from Static Address) is issued.
- Second element is the upper 16-bit of the Provisioned ID (PID) which contains the manufacturer ID left-shifted by 1. This is the bits 33-47 (zero-based) of the 48-bit Provisioned ID.
- Third element contains the lower 32-bit of the Provisioned ID which is a combination of the part ID (left-shifted by 16, bits 16-31 of the PID) and the instance ID (left-shifted by 12, bits 12-15 of the PID).

Note that the unit-address (the part after @) must match the `reg` property fully where each element is treated as 32-bit integer, combining to form a 96-bit integer. This is required for properly generating
device tree macros.

**I²C Devices**  For I²C devices where the device driver has support for working under I3C bus, the device node can be described as a child of the I3C controller. If the device driver is written to only work with I²C controllers, define the node under the I²C virtual controller as described below. Otherwise, the reg property, similar to I3C devices, has 3 elements:

- The first one is the static address of the device. This must be a valid address as I²C devices do not support dynamic address assignment.
- Second element is always zero.
- Third element is the LVR (Legacy Virtual Register):
  - bit[31:8] are unused.
  - bit[7:5] are the I²C device index:
    * Index 0
      - I3C device has a 50 ns spike filter where it is not affected by high frequency on SCL.
    * Index 1
      - I²C device does not have a 50 ns spike filter but can work with high frequency on SCL.
    * Index 2
      - I3C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.
  - bit[4] is the I²C mode indicator:
    * 0 is FM+ mode.
    * 1 is FM mode.

Similar to I3C devices, the unit-address must match the reg property fully where each element is treated as 32-bit integer, combining to form a 96-bit integer.

**Device Drivers for I3C Devices**  All of the transfer functions of I3C controller API require the use of device descriptors, *i3c_device_desc*. This struct contains runtime information about a I3C device, such as, its dynamic address, BCR, DCR, MRL and MWL. Therefore, the device driver of a I3C device should grab a pointer to this device descriptor from the controller using *i3c_device_find()*. This function takes an ID parameter of type *i3c_device_id* for matching. The returned pointer can then be used in subsequent API calls to the controller.

**I²C Devices under I3C Bus**  Since I3C is backward compatible with I²C, the I3C controller API can accommodate I2C API calls without modifications if the controller device driver implements the I2C API. This has the advantage of using existing I2C devices without any modifications to their device drivers. However, since the I3C controller API works on device descriptors, any calls to I2C API will need to look up the corresponding device descriptor from the I2C device address. This adds a bit of processing cost to any I2C API calls.

On the other hand, a device driver can be extended to utilize native I2C device support via the I3C controller API. During device initialization, *i3c_i2c_device_find()* needs to be called to retrieve the pointer to the device descriptor. This pointer can be used in subsequent API calls.

Note that, with either methods mentioned above, the devicetree node of the I2C device must be declared according to I3C standard:
The I²C virtual controller device driver provides a way to interface I²C devices on the I3C bus where the associated device drivers can be used as-is without modifications. This requires adding an intermediate node in the device tree:

```c
i3c0: i3c@10000 {
  <... I3C controller related properties ...>
  <... Nodes of I3C devices, if any ...>
      i2c-dev0: i2c-dev0@420000000000000050 {
        compatible = "vendor-i2c-dev";
        reg = < 0x42 0x0 0x50 >;
        status = "okay";
      }
};
```

### Configuration Options

Related configuration options:

- CONFIG_I3C
- CONFIG_I3C_USE_GROUP_ADDR
- CONFIG_I3C_USE_IBI
- CONFIG_I3C_IBI_MAX_PAYLOAD_SIZE
- CONFIG_I3C_CONTROLLER_INIT_PRIORITY

### API Reference

**group i3c_interface**

I3C Interface.

**Defines**

- I3C_BCR_MAX_DATA_SPEED_LIMIT
- I3C_BCR_IBI_REQUEST_CAPABLE
- I3C_BCR_IBI_PAYLOAD_HAS_DATA_BYTE
- I3C_BCR_OFFLINE_CAPABLE
- I3C_BCR_VIRTUAL_TARGET
- I3C_BCR_ADV_CAPABILITIES
- I3C_BCR_DEVICE_ROLE_I3C_TARGET
I3C_BCRDEVICE_ROLE_I3C_CONTROLLER_CAPABLE

I3C_BCRDEVICE_ROLE_SHIFT

I3C_BCRDEVICE_ROLE_MASK

I3C_BCRDEVICE_ROLE(bcr)

I3C_DCR_I2C_FM_PLUS_MODE

I3C_DCR_I2C_FM_MODE

I3C_DCR_I2C_MODE_SHIFT

I3C_DCR_I2C_MODE_MASK

I3C_DCR_I2C_MODE(dcr)

I3C_DCR_I2C_DEV_IDX_0

I3C_DCR_I2C_DEV_IDX_1

I3C_DCR_I2C_DEV_IDX_2

I3C_DCR_I2C_DEV_IDX_SHIFT

I3C_DCR_I2C_DEV_IDX_MASK

I3C_DCR_I2C_DEV_IDX(dcr)

I3C_MSG_WRITE
    Write message to I3C bus.

I3C_MSG_READ
    Read message from I2C bus.

I3C_MSG_STOP
    Send STOP after this message.

I3C_MSG_RESTART
    RESTART I3C transaction for this message.

Note: Not all I3C drivers have or require explicit support for this feature. Some drivers require this be present on a read message that follows a write, or vice-versa. Some drivers will merge adjacent fragments into a single transaction using this flag; some will not.

I3C_MSG_HDR
    Transfer use HDR mode
I3C_MSG_HDR_MODE0
    I3C HDR Mode 0

I3C_MSG_HDR_MODE1
    I3C HDR Mode 1

I3C_MSG_HDR_MODE2
    I3C HDR Mode 2

I3C_MSG_HDR_MODE3
    I3C HDR Mode 3

I3C_MSG_HDR_MODE4
    I3C HDR Mode 4

I3C_MSG_HDR_MODE5
    I3C HDR Mode 5

I3C_MSG_HDR_MODE6
    I3C HDR Mode 6

I3C_MSG_HDR_MODE7
    I3C HDR Mode 7

I3C_MSG_HDR_DDR
    I3C HDR-DDR (Double Data Rate)

I3C_MSG_HDR_TSP
    I3C HDR-TSP (Ternary Symbol Pure-bus)

I3C_MSG_HDR_TSL
    I3C HDR-TSL (Ternary Symbol Legacy-inclusive-bus)

I3C_MSG_HDR_BT
    I3C HDR-BT (Bulk Transport)

I3C_DEVICE_ID(pid)
    Structure initializer for i3c_device_id from PID.
    This helper macro expands to a static initializer for a struct i3c_device_id by populating the PID (Provisioned ID) field.

    **Parameters**
    - pid – Provisioned ID.

**Enums**

enum i3c_bus_mode
    I3C bus mode.
    **Values:**
enumerator I3C_BUS_MODE_PURE
    Only I3C devices are on the bus.

typedef enum {
    I3C_BUS_MODE_PURE,
    I3C_BUS_MODE_MIXED_FAST,
    I3C_BUS_MODE_MIXED_LIMITED,
    I3C_BUS_MODE_MIXED_SLOW,
    I3C_BUS_MODE_MAX = I3C_BUS_MODE_MIXED_SLOW,
    I3C_BUS_MODE_INVALID
} i3c_i2c_speed_type;

I2C bus speed under I3C bus.
Only FM and FM+ modes are supported for I2C devices under I3C bus.

Values:

typedef enum {
    I3C_I2C_SPEED_FM,
    I3C_I2C_SPEED_FMPLUS,
    I3C_I2C_SPEED_MAX = I3C_I2C_SPEED_FMPLUS,
    I3C_I2C_SPEED_INVALID
} i3c_data_rate;

I3C data rate.
I3C data transfer rate defined by the I3C specification.

Values:

enumerator I3C_DATA_RATE_HDR_TSP
    High Data Rate - Ternary Symbol for Pure Bus

denumerator I3C_DATA_RATE_HDR_BT
    High Data Rate - Bulk Transport

denumerator I3C_DATA_RATE_MAX = I3C_DATA_RATE_HDR_BT

denumerator I3C_DATA_RATE_INVALID

enum i3c_sdr_controller_error_codes
    I3C SDR Controller Error Codes.
    These are error codes defined by the I3C specification.
    I3C_ERROR_CE_UNKNOWN and I3C_ERROR_CE_NONE are not official error codes according to the specification. These are there simply to aid in error handling during interactions with the I3C drivers and subsystem.
    Values:

    enumerator I3C_ERROR_CE0
        Transaction after sending CCC

    enumerator I3C_ERROR_CE1
        Monitoring Error

    enumerator I3C_ERROR_CE2
        No response to broadcast address (0x7E)

    enumerator I3C_ERROR_CE3
        Failed Controller Handoff

    enumerator I3C_ERROR_CE_UNKNOWN
        Unknown error (not official error code)

    enumerator I3C_ERROR_CE_NONE
        No error (not official error code)

    enumerator I3C_ERROR_CE_MAX = I3C_ERROR_CE_UNKNOWN

    enumerator I3C_ERROR_CE_INVALID

enum i3c_sdr_target_error_codes
    I3C SDR Target Error Codes.
    These are error codes defined by the I3C specification.
    I3C_ERROR_TE_UNKNOWN and I3C_ERROR_TE_NONE are not official error codes according to the specification. These are there simply to aid in error handling during interactions with the I3C drivers and subsystem.
    Values:

    enumerator I3C_ERROR_TE0
    enumerator I3C_ERROR_TE1
    enumerator I3C_ERROR_TE2
    enumerator I3C_ERROR_TE3
    enumerator I3C_ERROR_TE_MAX = I3C_ERROR_TE_UNKNOWN

    enumerator I3C_ERROR_TE_INVALID
enumerator I3C_ERROR_TE0
Invalid Broadcast Address or Dynamic Address after DA assignment

denumerator I3C_ERROR_TE1
CCC Code

denumerator I3C_ERROR_TE2
Write Data

denumerator I3C_ERROR_TE3
Assigned Address during Dynamic Address Arbitration

denumerator I3C_ERROR_TE4
0x7E/R missing after RESTART during Dynamic Address Arbitration

denumerator I3C_ERROR_TE5
Transaction after detecting CCC

denumerator I3C_ERROR_TE6
Monitoring Error

denumerator I3C_ERROR_DBR
Dead Bus Recovery

denumerator I3C_ERROR_TE_UNKNOWN
Unknown error (not official error code)

denumerator I3C_ERROR_TE_NONE
No error (not official error code)

denumerator I3C_ERROR_TE_MAX = I3C_ERROR_TE_UNKNOWN

denumerator I3C_ERROR_TE_INVALID

enum i3c_config_type
Type of configuration being passed to configure function.
Values:

denumerator I3C_CONFIG_CONTROLLER

denumerator I3C_CONFIG_TARGET

denumerator I3C_CONFIG_CUSTOM

Functions
struct \texttt{i3c\_device\_desc} *\texttt{i3c\_dev\_list\_find}(\texttt{const struct i3c\_dev\_list} *\texttt{dev\_list}, \texttt{const struct i3c\_device\_id} *\texttt{id})

Find a I3C target device descriptor by ID.
This finds the I3C target device descriptor in the device list matching the provided ID struct (id).

**Parameters**

- \texttt{dev\_list} – Pointer to the device list struct.
- \texttt{id} – Pointer to I3C device ID struct.

**Returns**

Pointer the the I3C target device descriptor, or NULL if none is found.

struct \texttt{i3c\_device\_desc} *\texttt{i3c\_dev\_list\_i3c\_addr\_find}(\texttt{const struct i3c\_dev\_list} *\texttt{dev\_list}, \texttt{uint8\_t addr})

Find a I3C target device descriptor by dynamic address.
This finds the I3C target device descriptor in the device list matching the dynamic address (addr)

**Parameters**

- \texttt{dev\_list} – Pointer to the device list struct.
- \texttt{addr} – Dynamic address to be matched.

**Returns**

Pointer the the I3C target device descriptor, or NULL if none is found.

struct \texttt{i3c\_i2c\_device\_desc} *\texttt{i3c\_dev\_list\_i2c\_addr\_find}(\texttt{const struct i3c\_dev\_list} *\texttt{dev\_list}, \texttt{uint16\_t addr})

Find a I2C target device descriptor by address.
This finds the I2C target device descriptor in the device list matching the address (addr)

**Parameters**

- \texttt{dev\_list} – Pointer to the device list struct.
- \texttt{addr} – Address to be matched.

**Returns**

Pointer the the I2C target device descriptor, or NULL if none is found.

\texttt{int i3c\_dev\_list\_daa\_addr\_helper(\texttt{struct i3c\_addr\_slots} *\texttt{addr\_slots}, \texttt{const struct i3c\_dev\_list} *\texttt{dev\_list}, \texttt{uint64\_t pid}, \texttt{bool must\_match}, \texttt{bool assigned\_okay}, \texttt{struct i3c\_device\_desc} **\texttt{target}, \texttt{uint8\_t *addr})}

Helper function to find a usable address during ENTDAA.

This is a helper function to find a usable address during Dynamic Address Assignment. Given the PID (pid), it will search through the device list for the matching device descriptor. If the device descriptor indicates that there is a preferred address (i.e. assigned-address in device tree),

If \texttt{must\_match} is true, the PID (pid) must match one of the device in the device list.

**See also:**

\texttt{i3c\_device\_desc::init\_dynamic\_addr}, this preferred address will be returned if this address is still available. If it is not available, another free address will be returned.

If \texttt{must\_match} is false, this will return an arbitrary address. This is useful when not all devices are described in device tree. Or else, the DAA process cannot proceed since there is no address to be assigned.
If assigned_okay is true, it will return the same address already assigned to the device. If assigned_okay is false, the device cannot have an address assigned already (that
See also:
i3c_device_desc::dynamic_addr). If no address has been assigned, it behaves as if assigned_okay is false. This is useful for assigning the same address to the same device (for example, hot-join after device coming back from suspend).

See also:
i3c_device_desc::dynamic_addr is not zero). This is mainly used during the initial DAA.

Parameters
• addr_slots – [in] Pointer to address slots struct.
• dev_list – [in] Pointer to the device list struct.
• pid – [in] Provisioned ID of device to be assigned address.
• must_match – [in] True if PID must match devices in the device list. False otherwise.
• assigned_okay – [in] True if it is okay to return the address already assigned to the target matching the PID (pid).
• target – [out] Store the pointer of the device descriptor if it matches the incoming PID (pid).
• addr – [out] Address to be assigned to target device.

Return values
• 0 – if successful.
• -ENODEV – if no device matches the PID (pid) in the device list and must_match is true.
• -EINVAL – if the device matching PID (pid) already has an address assigned or invalid function arguments.

static inline int i3c_configure(const struct device *dev, enum i3c_config_type type, void *config)
Configure the I3C hardware.

Parameters
• dev – Pointer to controller device driver instance.
• type – Type of configuration parameters being passed in config.
• config – Pointer to the configuration parameters.

Return values
• 0 – If successful.
• -EINVAL – If invalid configure parameters.
• -EIO – General Input/Output errors.
• -ENOSYS – If not implemented.

static inline int i3c_config_get(const struct device *dev, enum i3c_config_type type, void *config)
Get configuration of the I3C hardware.

This provides a way to get the current configuration of the I3C hardware.

This can return cached config or probed hardware parameters, but it has to be up to date with current configuration.
Note that if \texttt{type} is \texttt{I3C\_CONFIG\_CUSTOM}, \texttt{config} must contain the ID of the parameter to be retrieved.

**Parameters**

- \texttt{dev} – \texttt{[in]} Pointer to controller device driver instance.
- \texttt{type} – \texttt{[in]} Type of configuration parameters being passed in \texttt{config}.
- \texttt{config} – \texttt{[inout]} Pointer to the configuration parameters.

**Return values**

- \texttt{0} – If successful.
- \texttt{-EIO} – General Input/Output errors.
- \texttt{-ENOSYS} – If not implemented.

```c
static inline int i3c_recover_bus(const struct device *dev)
```

Attempt bus recovery on the I3C bus.

This routine asks the controller to attempt bus recovery.

**Return values**

- \texttt{0} – If successful.
- \texttt{-EBUSY} – If bus recovery fails.
- \texttt{-EIO} – General input / output error.
- \texttt{-ENOSYS} – Bus recovery is not supported by the controller driver.

```c
static inline int i3c_do_daa(const struct device *dev)
```

Perform Dynamic Address Assignment on the I3C bus.

This routine asks the controller to perform dynamic address assignment where the controller belongs. Only the active controller of the bus should do this.

**Note:** For controller driver implementation, the controller should perform SETDASA to allow static addresses to be the dynamic addresses before actually doing ENTDAA.

**Parameters**

- \texttt{dev} – Pointer to the device structure for the controller driver instance.

**Return values**

- \texttt{0} – If successful.
- \texttt{-EBUSY} – Bus is busy.
- \texttt{-EIO} – General input / output error.
- \texttt{-ENODEV} – If a provisioned ID does not match to any target devices in the registered device list.
- \texttt{-ENOSPC} – No more free addresses can be assigned to target.
- \texttt{-ENOSYS} – Dynamic address assignment is not supported by the controller driver.

```c
int i3c_do_ccc(const struct device *dev, struct i3c_ccc_payload *payload)
```

Send CCC to the bus.

**Parameters**
• **dev** – Pointer to the device structure for the controller driver instance.
• **payload** – Pointer to the structure describing the CCC payload.

**Return values**

• **0** – If successful.
• **-EBUSY** – Bus is busy.
• **-EIO** – General Input / output error.
• **-EINVAL** – Invalid valid set in the payload structure.
• **-ENOSYS** – Not implemented.

```c
int i3c_transfer(struct i3c_device_desc *target, struct i3c_msg *msgs, uint8_t num_msgs)
```

Perform data transfer from the controller to an I3C target device.

This routine provides a generic interface to perform data transfer to a target device synchronously. Use `i3c_read()`/`i3c_write()` for simple read or write.

The array of message `msgs` must not be NULL. The number of message `num_msgs` may be zero, in which case no transfer occurs.

**Note**: Not all scatter/gather transactions can be supported by all drivers. As an example, a gather write (multiple consecutive `i3c_msg` buffers all configured for `I3C_MSG_WRITE`) may be packed into a single transaction by some drivers, but others may emit each fragment as a distinct write transaction, which will not produce the same behavior. See the documentation of `struct i3c_msg` for limitations on support for multi-message bus transactions.

**Parameters**

• `target` – I3C target device descriptor.
• `msgs` – Array of messages to transfer.
• `num_msgs` – Number of messages to transfer.

**Return values**

• **0** – If successful.
• **-EBUSY** – Bus is busy.
• **-EIO** – General input / output error.

```c
static inline struct i3c_device_desc *i3c_device_find(const struct device *dev, const struct i3c_device_id *id)
```

Find a registered I3C target device.

Controller only API.

This returns the I3C device descriptor of the I3C device matching the incoming `id`.

**Parameters**

• `dev` – Pointer to controller device driver instance.
• `id` – Pointer to I3C device ID.

**Returns**

Pointer to I3C device descriptor, or NULL if no I3C device found matching incoming `id`. 

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7.3. Peripherals 2229
static inline int i3c_ibi_raise(const struct device *dev, struct i3c_ibi *request)
    Raise an In-Band Interrupt (IBI).

    This raises an In-Band Interrupt (IBI) to the active controller.

    **Parameters**
    - dev – Pointer to controller device driver instance.
    - request – Pointer to the IBI request struct.

    **Return values**
    - 0 – if operation is successful.
    - -EIO – General input / output error.

static inline int i3c_ibi_enable(struct i3c_device_desc *target)
    Enable IBI of a target device.

    This enables IBI of a target device where the IBI has already been request.

    **Parameters**
    - target – I3C target device descriptor.

    **Return values**
    - 0 – If successful.
    - -EIO – General Input / output error.
    - -ENOMEM – If there is no more empty entries in the controller's IBI table (if the
      controller uses such table).

static inline int i3c_ibi_disable(struct i3c_device_desc *target)
    Disable IBI of a target device.

    This enables IBI of a target device where the IBI has already been request.

    **Parameters**
    - target – I3C target device descriptor.

    **Return values**
    - 0 – If successful.
    - -EIO – General Input / output error.
    - -ENODEV – If IBI is not previously enabled for target.

static inline int i3c_ibi_has_payload(struct i3c_device_desc *target)
    Check if target's IBI has payload.

    This reads the BCR from the device descriptor struct to determine whether IBI from device
    has payload.

    Note that BCR must have been obtained from device and

    **See also:**
    
    i3c_device_desc::bcr must be set.

    **Returns**
    - True if IBI has payload, false otherwise.
static inline int i3c_device_is_ibi_capable(struct i3c_device_desc *target)

Check if device is IBI capable.

This reads the BCR from the device descriptor struct to determine whether device is capable
of IBI.

Note that BCR must have been obtained from device and

See also:
i3c_device_desc::bcr must be set.

Returns
True if IBI has payload, false otherwise.

static inline int i3c_write(struct i3c_device_desc *target, const uint8_t *buf, uint32_t num_bytes)

Write a set amount of data to an I3C target device.

This routine writes a set amount of data synchronously.

Parameters
- target – I3C target device descriptor.
- buf – Memory pool from which the data is transferred.
- num_bytes – Number of bytes to write.

Return values
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.

static inline int i3c_read(struct i3c_device_desc *target, uint8_t *buf, uint32_t num_bytes)

Read a set amount of data from an I3C target device.

This routine reads a set amount of data synchronously.

Parameters
- target – I3C target device descriptor.
- buf – Memory pool that stores the retrieved data.
- num_bytes – Number of bytes to read.

Return values
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.

static inline int i3c_write_read(struct i3c_device_desc *target, const void *write_buf, size_t num_write, void *read_buf, size_t num_read)

Write then read data from an I3C target device.

This supports the common operation “this is what I want”, “now give
it to me” transaction pair through a combined write-then-read bus transaction.

Parameters
- target – I3C target device descriptor.
- write_buf – Pointer to the data to be written
• num_write – Number of bytes to write
• read_buf – Pointer to storage for read data
• num_read – Number of bytes to read

Return values
• 0 – if successful
• -EBUSY – Bus is busy.
• -EIO – General input / output error.

static inline int i3c_burst_read(struct i3c_device_desc *target, uint8_t start_addr, uint8_t *buf, uint32_t num_bytes)

Read multiple bytes from an internal address of an I3C target device.

This routine reads multiple bytes from an internal address of an I3C target device synchronously.

Instances of this may be replaced by i3c_write_read().

Parameters
• target – I3C target device descriptor,
• start_addr – Internal address from which the data is being read.
• buf – Memory pool that stores the retrieved data.
• num_bytes – Number of bytes being read.

Return values
• 0 – If successful.
• -EBUSY – Bus is busy.
• -EIO – General input / output error.

static inline int i3c_burst_write(struct i3c_device_desc *target, uint8_t start_addr, const uint8_t *buf, uint32_t num_bytes)

Write multiple bytes to an internal address of an I3C target device.

This routine writes multiple bytes to an internal address of an I3C target device synchronously.

Warning: The combined write synthesized by this API may not be supported on all I3C devices. Uses of this API may be made more portable by replacing them with calls to i3c_write() passing a buffer containing the combined address and data.

Parameters
• target – I3C target device descriptor.
• start_addr – Internal address to which the data is being written.
• buf – Memory pool from which the data is transferred.
• num_bytes – Number of bytes being written.

Return values
• 0 – If successful.
• -EBUSY – Bus is busy.
• -EIO – General input / output error.
static inline int i3c_reg_read_byte(struct i3c_device_desc *target, uint8_t reg_addr, uint8_t *value)

Read internal register of an I3C target device.

This routine reads the value of an 8-bit internal register of an I3C target device synchronously.

Parameters
- target – I3C target device descriptor.
- reg_addr – Address of the internal register being read.
- value – Memory pool that stores the retrieved register value.

Return values
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.

static inline int i3c_reg_write_byte(struct i3c_device_desc *target, uint8_t reg_addr, uint8_t value)

Write internal register of an I3C target device.

This routine writes a value to an 8-bit internal register of an I3C target device synchronously.

Note: This function internally combines the register and value into a single bus transaction.

Parameters
- target – I3C target device descriptor.
- reg_addr – Address of the internal register being written.
- value – Value to be written to internal register.

Return values
- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.

static inline int i3c_reg_update_byte(struct i3c_device_desc *target, uint8_t reg_addr, uint8_t mask, uint8_t value)

Update internal register of an I3C target device.

This routine updates the value of a set of bits from an 8-bit internal register of an I3C target device synchronously.

Note: If the calculated new register value matches the value that was read this function will not generate a write operation.

Parameters
- target – I3C target device descriptor.
- reg_addr – Address of the internal register being updated.
- mask – Bitmask for updating internal register.
- value – Value for updating internal register.
Return values

- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.

```c
void i3c_dump_msgs(const char *name, const struct i3c_msg *msgs, uint8_t num_msgs, struct i3c_device_desc *target)
```

Dump out an I3C message.

Dumps out a list of I3C messages. For any that are writes (W), the data is displayed in hex.

It looks something like this (with name “testing”):

```
D: I3C msg: testing, addr=56
D:     W len=01:
D:     contents: 06 |.
D:     W len=0e:
D:     contents: 00 01 02 03 04 05 06 07 |........
D: 08 09 0a 0b 0c 0d |.......   
```

**Parameters**

- name – Name of this dump, displayed at the top.
- msgs – Array of messages to dump.
- num_msgs – Number of messages to dump.
- target – I3C target device descriptor.

```c
int i3c_bus_init(const struct device *dev, const struct i3c_dev_list *i3c_dev_list)
```

Generic helper function to perform bus initialization.

**Parameters**

- dev – Pointer to controller device driver instance.
- i3c_dev_list – Pointer to I3C device list.

**Return values**

- 0 – If successful.
- -EBUSY – Bus is busy.
- -EIO – General input / output error.
- -ENODEV – If a provisioned ID does not match to any target devices in the registered device list.
- -ENOSPC – No more free addresses can be assigned to target.
- -ENOSYS – Dynamic address assignment is not supported by the controller driver.

```c
int i3c_device_basic_info_get(struct i3c_device_desc *target)
```

Get basic information from device and update device descriptor.

This retrieves some basic information:

- Bus Characteristics Register (GETBCR)
• Device Characteristics Register (GETDCR)
• Max Read Length (GETMRL)
• Max Write Length (GETMWL) from the device and update the corresponding fields of the device descriptor.

This only updates the field(s) in device descriptor only if CCC operations succeed.

**Parameters**

- target – [inout] I3C target device descriptor.

**Return values**

- 0 – if successful.
- -EIO – General Input/Output error.

```
struct i3c_msg
```

```
#include <i3c.h>
```

One I3C Message.

This defines one I3C message to transact on the I3C bus.

**Note:** Some of the configurations supported by this API may not be supported by specific SoC I3C hardware implementations, in particular features related to bus transactions intended to read or write data from different buffers within a single transaction. Invocations of `i3c_transfer()` may not indicate an error when an unsupported configuration is encountered. In some cases drivers will generate separate transactions for each message fragment, with or without presence of `I3C_MSG_RESTART` in flags.

---

**Public Members**

```
uint8_t *buf
```

Data buffer in bytes

```
uint32_t len
```

Length of buffer in bytes

```
uint8_t flags
```

Flags for this message

```
uint8_t hdr_mode
```

HDR mode (I3C_MSG_HDR_MODE*) for transfer if any I3C_MSG_HDR_* is set in flags.

Use SDR mode if none is set.

```
struct i3c_config_controller
```

```
#include <i3c.h>
```

Configuration parameters for I3C hardware to act as controller.

**Public Members**

```
bool is_primary
```

True if the controller is to be the primary controller of the bus. False to be the secondary controller.

---

7.3. Peripherals
uint32_t i3c
   SCL frequency (in Hz) for I3C transfers.

uint32_t i2c
   SCL frequency (in Hz) for I2C transfers.

uint8_t supported_hdr
   Bit mask of supported HDR modes (0 - 7).
   This can be used to enable or disable HDR mode supported by the hardware at runtime.

struct i3c_config_custom
   #include <i3c.h> Custom I3C configuration parameters.
   This can be used to configure the I3C hardware on parameters not covered by
   See also:
   i3c_config_controller or
   See also:
   i3c_config_target. Mostly used to configure vendor specific parameters of the I3C hardware.

Public Members

uint32_t id
   ID of the configuration parameter.

uintptr_t val
   Value of configuration parameter.

void *ptr
   Pointer to configuration parameter.
   Mainly used to pointer to a struct that the device driver understands.

struct i3c_device_id
   #include <i3c.h> Structure used for matching I3C devices.

Public Members

const uint64_t pid
   Device Provisioned ID

struct i3c_device_desc
   #include <i3c.h> Structure describing a I3C target device.
   Instances of this are passed to the I3C controller device APIs, for example:
   • i3c_device_register() to tell the controller of a target device.
   • i3c_transfers() to initiate data transfers between controller and target device.
Fields `bus`, `pid` and `static_addr` must be initialized by the module that implements the target device behavior prior to passing the object reference to I3C controller device APIs. `static_addr` can be zero if target device does not have static address.

Field `node` should not be initialized or modified manually.

Public Members

```c
sys_snode_t node
    Private, do not modify

const struct device *const bus
    I3C bus to which this target device is attached

const struct device *const dev
    Device driver instance of the I3C device

const uint64_t pid
    Device Provisioned ID

const uint8_t static_addr
    Static address for this target device.
    0 if static address is not being used, and only dynamic address is used. This means that the target device must go through ENTDAA (Dynamic Address Assignment) to get a dynamic address before it can communicate with the controller. This means SETAASA and SETDASA CCC cannot be used to set dynamic address on the target device (as both are to tell target device to use static address as dynamic address).

const uint8_t init_dynamic_addr
    Initial dynamic address.
    This is specified in the device tree property “assigned-address” to indicate the desired dynamic address during address assignment (SETDASA and ENTDAA).
    0 if there is no preference.

uint8_t dynamic_addr
    Dynamic Address for this target device used for communication.
    This is to be set by the controller driver in one of the following situations:
    • During Dynamic Address Assignment (during ENTDAA)
    • Reset Dynamic Address Assignment (RSTDAA)
    • Set All Addresses to Static Addresses (SETAASA)
    • Set New Dynamic Address (SETNEWDA)
    • Set Dynamic Address from Static Address (SETDASA)
    0 if address has not been assigned.

uint8_t group_addr
    Group address for this target device. Set during:
    • Reset Group Address(es) (RSTGRPA)
    • Set Group Address (SETGRPA)
    0 if group address has not been assigned.
```
uint8_t bcr

Bus Characteristic Register (BCR)
- BCR[7:6]: Device Role
  - 0: I3C Target
  - 1: I3C Controller capable
  - 2: Reserved
  - 3: Reserved
- BCR[5]: Advanced Capabilities
  - 0: Does not support optional advanced capabilities.
  - 1: Supports optional advanced capabilities which can be viewed via GETCAPS CCC.
- BCR[4]: Virtual Target Support
  - 0: Is not a virtual target.
  - 1: Is a virtual target.
- BCR[3]: Offline Capable
  - 0: Will always response to I3C commands.
  - 1: Will not always response to I3C commands.
- BCR[2]: IBI Payload
  - 0: No data bytes following the accepted IBI.
  - 1: One data byte (MDB, Mandatory Data Byte) follows the accepted IBI. Additional data bytes may also follows.
- BCR[1]: IBI Request Capable
  - 0: Not capable
  - 1: Capable
- BCR[0]: Max Data Speed Limitation
  - 0: No Limitation
  - 1: Limitation obtained via GETMXDS CCC.

uint8_t dcr

Device Characteristic Register (DCR)
Describes the type of device. Refer to official documentation on what this number means.

uint8_t maxrd

Maximum Read Speed

uint8_t maxwr

Maximum Write Speed

uint32_t max_read_turnaround

Maximum Read turnaround time in microseconds.

uint16_t mrl

Maximum Read Length

uint16_t mwl

Maximum Write Length

uint8_t max_ibi

Maximum IBI Payload Size. Valid only if BCR[2] is 1.

void *controller_priv

Private data by the controller to aid in transactions. Do not modify.
i3c_target_ibi_cb_t ibi_cb
In-Band Interrupt (IBI) callback.

struct i3c_i2c_device_desc
#include <i3c.h> Structure describing a I2C device on I3C bus.
Instances of this are passed to the I3C controller device APIs, for example: ()
i3c_i2c_device_register() to tell the controller of an I2C device. () i3c_i2c_transfers() to initiate data transfers between controller and I2C device.
Fields other than node must be initialized by the module that implements the device behavior prior to passing the object reference to I3C controller device APIs.

Public Members

sys_snode_t node
   Private, do not modify

const struct device *bus
   I3C bus to which this I2C device is attached

const uint16_t addr
   Static address for this I2C device.

const uint8_t lvr
   Legacy Virtual Register (LVR)
   - IVR[7:5]: I2C device index:
     - 0: I2C device has a 50 ns spike filter where it is not affected by high frequency on SCL.
     - 1: I2C device does not have a 50 ns spike filter but can work with high frequency on SCL.
     - 2: I2C device does not have a 50 ns spike filter and cannot work with high frequency on SCL.
   - IVR[4]: I2C mode indicator:
     - 0: FM+ mode
     - 1: FM mode
   - IVR[3:0]: Reserved.

void *controller_priv
   Private data by the controller to aid in transactions. Do not modify.

struct i3c_dev_list
#include <i3c.h> Structure for describing attached devices for a controller.
This contains arrays of attached I3C and I2C devices.
This is a helper struct that can be used by controller device driver to aid in device management.

Public Members

struct i3c_device_desc *const i3c
   Pointer to array of attached I3C devices.
struct i3c_i2c_device_desc *const i2c
  Pointer to array of attached I2C devices.

const uint8_t num_i3c
  Number of I3C devices in array.

const uint8_t num_i2c
  Number of I2C devices in array.

group i3c_ccc
  I3C Common Command Codes.

Defines

I3C_CCC_BROADCAST_MAX_ID
  Maximum CCC ID for broadcast

I3C_CCC_ENEC(broadcast)
  Enable Events Command
  Parameters
    • broadcast – True if broadcast, false if direct.

I3C_CCC_DISEC(broadcast)
  Disable Events Command
  Parameters
    • broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS(as, broadcast)
  Enter Activity State
  Parameters
    • as – Desired activity state
    • broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS0(broadcast)
  Enter Activity State 0
  Parameters
    • broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS1(broadcast)
  Enter Activity State 1
  Parameters
    • broadcast – True if broadcast, false if direct.

I3C_CCC_ENTAS2(broadcast)
  Enter Activity State 2
  Parameters
    • broadcast – True if broadcast, false if direct.
I3C_CCC_ENTAS3(broadcast)
Enter Activity State 3

**Parameters**

- `broadcast` – True if broadcast, false if direct.

I3C_CCC_RSTDAA
Reset Dynamic Address Assignment (Broadcast)

I3C_CCC_ENTDAA
Enter Dynamic Address Assignment (Broadcast)

I3C_CCC_DEFTGTS
Define List of Targets (Broadcast)

I3C_CCC_SETMVL(broadcast)
Set Max Write Length (Broadcast or Direct)

**Parameters**

- `broadcast` – True if broadcast, false if direct.

I3C_CCC_SETMRL(broadcast)
Set Max Read Length (Broadcast or Direct)

**Parameters**

- `broadcast` – True if broadcast, false if direct.

I3C_CCC_ENTTM
Enter Test Mode (Broadcast)

I3C_CCC_SETBUSCON
Set Bus Context (Broadcast)

I3C_CCC_ENDXFER(broadcast)
Data Transfer Ending Procedure Control

**Parameters**

- `broadcast` – True if broadcast, false if direct.

I3C_CCC_ENTHDR(x)
Enter HDR Mode (HDR-DDR) (Broadcast)

I3C_CCC_ENTHDR0
Enter HDR Mode 0 (HDR-DDR) (Broadcast)

I3C_CCC_ENTHDR1
Enter HDR Mode 1 (HDR-TSP) (Broadcast)

I3C_CCC_ENTHDR2
Enter HDR Mode 2 (HDR-TSL) (Broadcast)

I3C_CCC_ENTHDR3
Enter HDR Mode 3 (HDR-BT) (Broadcast)
I3C_CCC_ENTHDR4
Enter HDR Mode 4 (Broadcast)

I3C_CCC_ENTHDR5
Enter HDR Mode 5 (Broadcast)

I3C_CCC_ENTHDR6
Enter HDR Mode 6 (Broadcast)

I3C_CCC_ENTHDR7
Enter HDR Mode 7 (Broadcast)

I3C_CCC_SETXTIME(broadcast)
Exchange Timing Information (Broadcast or Direct)

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_SETAASA
Set All Addresses to Static Addresses (Broadcast)

I3C_CCC_RSTACT(broadcast)
Target Reset Action

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_DEFGGRA
Define List of Group Address (Broadcast)

I3C_CCC_RSTGPA(broadcast)
Reset Group Address

Parameters
• broadcast – True if broadcast, false if direct.

I3C_CCC_MLANE(broadcast)
Multi-Lane Data Transfer Control (Broadcast)

I3C_CCC_VENDOR(broadcast, id)
Vendor/Standard Extension

Parameters
• broadcast – True if broadcast, false if direct.
• id – Extension ID.

I3C_CCC_SETDASA
Set Dynamic Address from Static Address (Direct)

I3C_CCC_SETNEWDA
Set New Dynamic Address (Direct)

I3C_CCC_GETMWL
Get Max Write Length (Direct)
I3C_CCC_GETMRL
   Get Max Read Length (Direct)

I3C_CCC_GETPID
   Get Provisioned ID (Direct)

I3C_CCC_GETBCR
   Get Bus Characteristics Register (Direct)

I3C_CCC_GETDCR
   Get Device Characteristics Register (Direct)

I3C_CCC_GETSTATUS
   Get Device Status (Direct)

I3C_CCC_GETACCCR
   Get Accept Controller Role (Direct)

I3C_CCC_SETBRGTGT
   Set Bridge Targets (Direct)

I3C_CCC_GETMXDS
   Get Max Data Speed (Direct)

I3C_CCC_GETCAPS
   Get Optional Feature Capabilities (Direct)

I3C_CCC_SETROUTE
   Set Route (Direct)

I3C_CCC_D2DXFER
   Device to Device(s) Tunneling Control (Direct)

I3C_CCC_GETXTIME
   Get Exchange Timing Information (Direct)

I3C_CCC_SETGRPA
   Set Group Address (Direct)

I3C_CCC_ENEC_EVT_ENINTR

I3C_CCC_ENEC_EVT_ENCR

I3C_CCC_ENEC_EVT_ENHJ

I3C_CCC_ENEC_EVT_ALL

I3C_CCC_DISSEC_EVT_DISINTR
I3C_CCC_DISEC_EVT_DISCR
I3C_CCC_DISEC_EVT_DISHJ
I3C_CCC_DISEC_EVT_ALL
I3C_CCC_EVT_INTR
I3C_CCC_EVT_CR
I3C_CCC_EVT_HJ
I3C_CCC_EVT_ALL
I3C_CCC_GETSTATUS_PROTOCOL_ERR
I3C_CCC_GETSTATUS_ACTIVITY_MODE_SHIFT
I3C_CCC_GETSTATUS_ACTIVITY_MODE_MASK
I3C_CCC_GETSTATUS_ACTIVITY_MODE(status)
I3C_CCC_GETSTATUS_NUM_INT_SHIFT
I3C_CCC_GETSTATUS_NUM_INT_MASK
I3C_CCC_GETSTATUS_NUM_INT(status)
I3C_CCC_GETSTATUS_PRECR_DEEP_SLEEP_DETECTED
I3C_CCC_GETSTATUS_PRECR_HANDOFF_DELAY_NACK
I3C_CCC_GETMXDS_MAX_SDR_FSCL_MAX
I3C_CCC_GETMXDS_MAX_SDR_FSCL_8MHZ
I3C_CCC_GETMXDS_MAX_SDR_FSCL_6MHZ
I3C_CCC_GETMXDS_MAX_SDR_FSCL_4MHZ
I3C_CCC_GETMXDS_MAX_SDR_FSCL_2MHZ
I3C_CCC_GETMXDS_TSCO_8NS
I3C_CCC_GETMXDS_TSCO_9NS
I3C_CCC_GETMXDS_TSCO_10NS
I3C_CCC_GETMXDS_TSCO_11NS
I3C_CCC_GETMXDS_TSCO_12NS
I3C_CCC_GETMXDS_TSCO_GT_12NS
I3C_CCC_GETMXDS_MAXWR_DEFINING_BYTE_SUPPORT
I3C_CCC_GETMXDS_MAXWR_MAX_SDR_FSCL_SHIFT
I3C_CCC_GETMXDS_MAXWR_MAX_SDR_FSCL_MASK
I3C_CCC_GETMXDS_MAXWR_MAX_SDR_FSCL(maxwr)
I3C_CCC_GETMXDS_MAXRD_W2R_PERMITS_STOP_BETWEEN
I3C_CCC_GETMXDS_MAXRD_TSCO_SHIFT
I3C_CCC_GETMXDS_MAXRD_TSCO_MASK
I3C_CCC_GETMXDS_MAXRD_TSCO(maxrd)
I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL_SHIFT
I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL_MASK
I3C_CCC_GETMXDS_MAXRD_MAX_SDR_FSCL(maxrd)
I3C_CCC_GETMXDS_CRDHLY1_SET_BUS_ACT_STATE
I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE_SHIFT
I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE_MASK
I3C_CCC_GETMXDS_CRDHLY1_CTRL_HANDOFF_ACT_STATE(crhdly1)
I3C_CCC_GETCAPS1_HDR_DDR
I3C_CCC_GETCAPS1_HDR_BT
I3C_CCC_GETCAPS1_HDR_MODE(x)
I3C_CCC_GETCAPS1_HDR_MODE0
I3C_CCC_GETCAPS1_HDR_MODE1

7.3. Peripherals
I3C_CCC_GETCAPS1_HDR_MODE2
I3C_CCC_GETCAPS1_HDR_MODE3
I3C_CCC_GETCAPS1_HDR_MODE4
I3C_CCC_GETCAPS1_HDR_MODE5
I3C_CCC_GETCAPS1_HDR_MODE6
I3C_CCC_GETCAPS1_HDR_MODE7
I3C_CCC_GETCAPS2_HRDHDR_WRITE_ABORT
I3C_CCC_GETCAPS2_HRDHDR_ABORT_CRC
I3C_CCC_GETCAPS2_GRPADDR_CAP SHIFT
I3C_CCC_GETCAPS2_GRPADDR_CAP_MASK
I3C_CCC_GETCAPS2_GRPADDR_CAP(getcaps2)
I3C_CCC_GETCAPS2_SPEC_VER SHIFT
I3C_CCC_GETCAPS2_SPEC_VER_MASK
I3C_CCC_GETCAPS2_SPEC_VER(getcaps2)
I3C_CCC_GETCAPS3_MLAME_SUPPORT
I3C_CCC_GETCAPS3_D2DXFER_SUPPORT
I3C_CCC_GETCAPS3_D3DXFER_IBI_CAPABLE
I3C_CCC_GETCAPS3_GETCAPS_DEFINING_BYTE_SUPPORT
I3C_CCC_GETCAPS3_GETSTATUS_DEFINING_BYTE_SUPPORT
I3C_CCC_GETCAPS3_HDRBT_CRC32_SUPPORT
I3C_CCC_GETCAPS3_IBI_MDR_PENDING_READ_NOTIFICATION

**Enums**
enum i3c_ccc_getstatus_fmt

Indicate which format of GETSTATUS to use.

Values:

enumerator GETSTATUS_FORMAT_1
enumerator GETSTATUS_FORMAT_2

enum i3c_ccc_getstatus_defbyte

Values:

enumerator GETSTATUS_FORMAT_2_TGTSTAT = 0x00U
enumerator GETSTATUS_FORMAT_2_PRECR = 0x91U
enumerator GETSTATUS_FORMAT_2_INVALID = 0x100U

enum i3c_ccc_rstact_defining_byte

Values:

enumerator I3C_CCC_RSTACT_NO_RESET = 0x00U
enumerator I3C_CCC_RSTACT_PERIPHERAL_ONLY = 0x01U
enumerator I3C_CCC_RSTACT_RESET_WHOLE_TARGET = 0x02U
enumerator I3C_CCC_RSTACT_DEBUG_NETWORK_ADAPTER = 0x03U
enumerator I3C_CCC_RSTACT_VIRTUAL_TARGET_DETECT = 0x04U

Functions

static inline bool i3c_ccc_is_payload_broadcast(const struct i3c_ccc_payload *payload)
Test if I3C CCC payload is for broadcast.
This tests if the CCC payload is for broadcast.

Parameters

• payload – [in] Pointer to the CCC payload.

Return values

• true – if payload target is broadcast
• false – if payload target is direct

int i3c_ccc_do_getbcr(struct i3c_device_desc *target, struct i3c_ccc_getbcr *bcr)
Get BCR from a target.

Helper function to get BCR (Bus Characteristic Register) from target device.

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See also:

`i3c_do_ccc`

Parameters

- bcr – [out] Pointer to the BCR payload structure.

Returns

```
int i3c_ccc_do_getdcr(struct i3c_device_desc *target, struct i3c_ccc_getdcr *dcr)
```

Get DCR from a target.

Helper function to get DCR (Device Characteristic Register) from target device.

See also:

`i3c_do_ccc`

Parameters

- dcr – [out] Pointer to the DCR payload structure.

Returns

```
int i3c_ccc_do_getpid(struct i3c_device_desc *target, struct i3c_ccc_getpid *pid)
```

Get PID from a target.

Helper function to get PID (Provisioned ID) from target device.

See also:

`i3c_do_ccc`

Parameters


Returns

```
int i3c_ccc_do_rstact_all(const struct device *controller, enum i3c_ccc_rstact_defining_byte action)
```

Broadcast RSTACT to reset I3C Peripheral.

Helper function to broadcast Target Reset Action (RSTACT) to all connected targets to Reset the I3C Peripheral Only (0x01).

See also:

`i3c_do_ccc`

Parameters

- controller – [in] Pointer to the controller device driver instance.

Returns
int i3c_ccc_do_rstdaa_all(const struct device *controller)
Broadcast RSTDAA to reset dynamic addresses for all targets.
Helper function to reset dynamic addresses of all connected targets.

See also:
i3c_do_ccc

Parameters
• controller – [in] Pointer to the controller device driver instance.

Returns

int i3c_ccc_do_setdasa(const struct i3c_device_desc *target)
Set Dynamic Address from Static Address for a target.
Helper function to do SETDASA (Set Dynamic Address from Static Address) for a particular target.
Note this does not update target with the new dynamic address.

See also:
i3c_do_ccc

Parameters
• target – [in] Pointer to the target device descriptor where the device is configured with a static address.

Returns

int i3c_ccc_do_events_all_set(const struct device *controller, bool enable, struct i3c_ccc_events *events)
Broadcast ENEC/DISEC to enable/disable target events.
Helper function to broadcast Target Events Command to enable or disable target events (ENEC/DISEC).

See also:
i3c_do_ccc

Parameters
• controller – [in] Pointer to the controller device driver instance.
• enable – [in] ENEC if true, DISEC if false.
• events – [in] Pointer to the event struct.

Returns

int i3c_ccc_do_events_set(struct i3c_device_desc *target, bool enable, struct i3c_ccc_events *events)
Direct CCC ENEC/DISEC to enable/disable target events.
Helper function to send Target Events Command to enable or disable target events (ENEC/DISEC) on a single target.
See also:

*i3c_do_ccc*

**Parameters**

- target – **[in]** Pointer to the target device descriptor.
- enable – **[in]** ENEC if true, DISEC if false.
- events – **[in]** Pointer to the event struct.

**Returns**

int i3c_ccc_do_setmwl_all(const struct *controller, const struct *mwl)

Broadcast SETMWL to Set Maximum Write Length.
Helper function to do SETMWL (Set Maximum Write Length) to all connected targets.

See also:

*i3c_do_ccc*

**Parameters**

- controller – **[in]** Pointer to the controller device driver instance.
- mwl – **[in]** Pointer to SETMWL payload.

**Returns**

int i3c_ccc_do_setmwl(const struct *target, const struct *mwl)

Single target SETMWL to Set Maximum Write Length.
Helper function to do SETMWL (Set Maximum Write Length) to one target.

See also:

*i3c_do_ccc*

**Parameters**

- target – **[in]** Pointer to the target device descriptor.
- mwl – **[in]** Pointer to SETMWL payload.

**Returns**

int i3c_ccc_do_getmwl(const struct *target, struct *mwl)

Single target GETMWL to Get Maximum Write Length.
Helper function to do GETMWL (Get Maximum Write Length) of one target.

See also:

*i3c_do_ccc*

**Parameters**

- target – **[in]** Pointer to the target device descriptor.
- mwl – **[out]** Pointer to GETMWL payload.
Returns

int i3c_ccc_do_setmrl_all(const struct device *controller, const struct i3c_ccc_mrl *mrl, bool has_ibi_size)

Broadcast SETMRL to Set Maximum Read Length.
Helper function to do SETMRL (Set Maximum Read Length) to all connected targets.

See also:

i3c_do_ccc

Parameters

• controller – [in] Pointer to the controller device driver instance.
• mrl – [in] Pointer to SETMRL payload.
• has_ibi_size – [in] True if also sending the optional IBI payload size. False if not sending.

Returns

int i3c_ccc_do_setmrl(const struct i3c_device_desc *target, const struct i3c_ccc_mrl *mrl)

Single target SETMRL to Set Maximum Read Length.
Helper function to do SETMRL (Set Maximum Read Length) to one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:

i3c_do_ccc

Parameters

• target – [in] Pointer to the target device descriptor.
• mrl – [in] Pointer to SETMRL payload.

Returns

int i3c_ccc_do_getmrl(const struct i3c_device_desc *target, struct i3c_ccc_mrl *mrl)

Single target GETMRL to Get Maximum Read Length.
Helper function to do GETMRL (Get Maximum Read Length) of one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:

i3c_do_ccc

Parameters

• target – [in] Pointer to the target device descriptor.
• mrl – [out] Pointer to GETMRL payload.

Returns
int i3c_ccc_do_getstatus(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status, enum i3c_ccc_getstatus_fmt fmt, enum i3c_ccc_getstatus_defbyte defbyte)

Single target GETSTATUS to Get Target Status.
Helper function to do GETSTATUS (Get Target Status) of one target.
Note this uses the BCR of the target to determine whether to send the optional IBI payload size.

See also:
i3c_do_ccc

Parameters
- status – [out] Pointer to GETSTATUS payload.

Returns

static inline int i3c_ccc_do_getstatus_fmt1(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status)

Single target GETSTATUS to Get Target Status (Format 1).
Helper function to do GETSTATUS (Get Target Status, format 1) of one target.

See also:
i3c_do_ccc

Parameters
- status – [out] Pointer to GETSTATUS payload.

Returns

static inline int i3c_ccc_do_getstatus_fmt2(const struct i3c_device_desc *target, union i3c_ccc_getstatus *status, enum i3c_ccc_getstatus_defbyte defbyte)

Single target GETSTATUS to Get Target Status (Format 2).
Helper function to do GETSTATUS (Get Target Status, format 2) of one target.

See also:
i3c_do_ccc

Parameters
- status – [out] Pointer to GETSTATUS payload.

Returns
struct i3c_ccc_target_payload

#include <ccc.h> Payload structure for Direct CCC to one target.

Public Members

uint8_t addr
  Target address

uint8_t rnw
  0 for Write, 1 for Read

uint8_t *data
  • For Write CCC, pointer to the byte array of data to be sent, which may contain the
    Sub-Command Byte and additional data.
  • For Read CCC, pointer to the byte buffer for data to be read into.

size_t data_len
  Length in bytes for data.

struct i3c_ccc_payload

#include <ccc.h> Payload structure for one CCC transaction.

Public Members

uint8_t id
  The CCC ID (I3C_CCC_*).

uint8_t *data
  Pointer to byte array of data for this CCC.
  This is the bytes following the CCC command in CCC frame. Set to NULL if no associated
data.

size_t data_len
  Length in bytes for optional data array.

struct i3c_ccc_target_payload *payloads
  Array of struct i3c_ccc_target_payload.
  Each element describes the target and associated payloads for this CCC.
  Use with Direct CCC.

size_t num_targets
  Number of targets

struct i3c_ccc_events

#include <ccc.h> Payload for ENEC/DISEC CCC (Target Events Command).
Public Members

uint8_t events

Event byte:
- Bit[0]: ENINT/DISINT:
  - Target Interrupt Requests
- Bit[1]: ENCR/DISCR:
  - Controller Role Requests
- Bit[3]: ENHJ/DISHJ:
  - Hot-Join Event

struct i3c_ccc_mwl
#include <ccc.h>
Payload for SETMWL/GETMWL CCC (Set/Get Maximum Write Length).

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

Public Members

uint16_t len
Maximum Write Length

struct i3c_ccc_mrl
#include <ccc.h>
Payload for SETMRL/GETMRL CCC (Set/Get Maximum Read Length).

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

Public Members

uint16_t len
Maximum Read Length

uint8_t ibi_len
Optional IBI Payload Size

struct i3c_ccc_deftgts_active_controller
#include <ccc.h>
The active controller part of payload for DEFTGTS CCC.
This is used by DEFTGTS (Define List of Targets) CCC to describe the active controller on the I3C bus.
uint8_t addr
   Dynamic Address of Active Controller

uint8_t dcr
   Device Characteristic Register of Active Controller

uint8_t bcr
   Bus Characteristic Register of Active Controller

uint8_t static_addr
   Static Address of Active Controller

struct i3c_ccc_deftgts_target
#include <ccc.h> The target device part of payload for DEFTGTS CCC.
This is used by DEFTGTS (Define List of Targets) CCC to describe the existing target devices
on the I3C bus.

Public Members

uint8_t addr
   Dynamic Address of a target device, or a group address

uint8_t dcr
   Device Characteristic Register of a I3C target device or a group.

uint8_t lvr
   Legacy Virtual Register for legacy I2C device.

uint8_t bcr
   Bus Characteristic Register of a target device or a group

uint8_t static_addr
   Static Address of a target device or a group

struct i3c_ccc_deftgts
#include <ccc.h> Payload for DEFTGTS CCC (Define List of Targets).

Note:  i3c_ccc_deftgts_target is an array of targets, where the number of elements is
dependent on the number of I3C targets on the bus. Please have enough space for both read
and write of this CCC.

Public Members

struct i3c_ccc_deftgts_active_controller active_controller
   Data describing the active controller
struct i3c_ccc_deftgts_target targets[]
  Data describing the target(s) on the bus

struct i3c_ccc_address
#include <ccc.h> Payload for a single device address.
This is used for:
  • SETDASA (Set Dynamic Address from Static Address)
  • SETNEWDA (Set New Dynamic Address)
  • SETGRPA (Set Group Address)
  • GETACCCCR (Get Accept Controller Role)
Note that the target address is encoded within struct i3c_ccc_target_payload instead of being encoded in this payload.

Public Members

uint8_t addr
  • For SETDASA, Static Address to be assigned as Dynamic Address.
  • For SETNEWDA, new Dynamic Address to be assigned.
  • For SETGRPA, new Group Address to be set.
  • For GETACCCCR, the correct address of Secondary Controller.

Note: For SETDATA, SETNEWDA and SETGRAP, the address is left-shift by 1, and bit[0] is always 0.

Note: Fpr SET GETACCCCR, the address is left-shift by 1, and bit[0] is the calculated odd parity bit.

struct i3c_ccc_getpid
#include <ccc.h> Payload for GETPID CCC (Get Provisioned ID).

Public Members

uint8_t pid[6]
  48-bit Provisioned ID.

Note: Data is big-endian where first byte is MSB.

struct i3c_ccc_getbcr
#include <ccc.h> Payload for GETBCR CCC (Get Bus Characteristics Register).

Public Members
### uint8_t bcr

Bus Characteristics Register

### struct i3c_ccc_getdcr

```c
#include <ccc.h>
```

Payload for GETDCR CCC (Get Device Characteristics Register).

#### Public Members

- **uint8_t dcr**
  - Device Characteristics Register

### union i3c_ccc_getstatus

```c
#include <ccc.h>
```

Payload for GETSTATUS CCC (Get Device Status).

#### Public Members

- **uint16_t status**
  - Device Status
    - Bit[15:8]: Reserved.
    - Bit[7:6]: Activity Mode.
    - Bit[5]: Protocol Error.
    - Bit[4]: Reserved.
    - Bit[3:0]: Number of Pending Interrupts.

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

### struct i3c_ccc_getstatus.[anonymous] fmt1

- **uint16_t tgtstat**
  - Defining Byte 0x00: TGTSTAT

See also:
- i3c_ccc_getstatus::fmt1::status

- **uint16_t precr**
  - Defining Byte 0x91: PRECR
    - Bit[15:8]: Vendor Reserved
    - Bit[7:2]: Reserved
    - Bit[1]: Handoff Delay NACK
    - Bit[0]: Deep Sleep Detected

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.
uint16_t raw_u16

union i3c_ccc_getstatus.[anonymous] fmt2

struct i3c_ccc_setbrgtgt_tgt
#include <ccc.h> One Bridged Target for SETBRGTGT payload.

Public Members

uint8_t addr
Dynamic address of the bridged target.

Note: The address is left-shift by 1, and bit[0] is always 0.

uint16_t id
16-bit ID for the bridged target.

Note: For drivers and help functions, the raw data coming back from target device is in big endian. This needs to be translated back to CPU endianness before passing back to function caller.

struct i3c_ccc_setbrgtgt
#include <ccc.h> Payload for SETBRGTGT CCC (Set Bridge Targets).
Note that the bridge target address is encoded within struct i3c_ccc_target_payload instead of being encoded in this payload.

Public Members

uint8_t count
Number of bridged targets

struct i3c_ccc_setbrgtgt_tgt targets[]
Array of bridged targets

union i3c_ccc_getmxds
#include <ccc.h> Payload for GETMXDS CCC (Get Max Data Speed).

Note: This is only for GETMXDS Format 1 and Format 2.

Public Members

uint8_t maxwr
maxWr


```c
uint8_t maxrd
maxRd

struct i3c_ccc_getmxds.[anonymous] fmt1

uint8_t maxrdturn[3]
   Maximum Read Turnaround Time in microsecond.
   This is in little-endian where first byte is LSB.

struct i3c_ccc_getmxds.[anonymous] fmt2

uint8_t wrrdturn
   Defining Byte 0x00: WRRDTURN

See also:
i3c_ccc_getmxds::fmt2

uint8_t crhdly1
   Defining Byte 0x91: CRHDLY
       • Bit[2]: Set Bus Activity State
       • Bit[1:0]: Controller Handoff Activity State

struct i3c_ccc_getmxds.[anonymous] fmt3

struct i3c_ccc_getcaps
   #include <ccc.h> Payload for GETCAPS CCC (Get Optional Feature Capabilities).

Note: Only support GETCAPS Format 1.

Public Members

uint8_t getcaps[4]

group i3c_addresses
   I3C Address-related Helper Code.

Defines

I3C_BROADCAST_ADDR

I3C_MAX_ADDR
```

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 Enums

enum i3c_addr_slot_status

   Values:

   enumerator I3C_ADDR_SLOT_STATUS_FREE = 0U

   enumerator I3C_ADDR_SLOT_STATUS_RSVD

   enumerator I3C_ADDR SLOT_STATUS_I3C_DEV

   enumerator I3C_ADDR SLOT_STATUS_I2C_DEV

   enumerator I3C_ADDR_SLOT_STATUS_MASK = 0x03U

 Functions

int i3c_addr_slots_init(struct i3c_addr_slots *slots, const struct i3c_dev_list *dev_list)

Initialize the I3C address slots struct.

This clears out the assigned address bits, and set the reserved address bits according to the I3C specification.

Parameters

• slots – Pointer to address slots struct.

• dev_list – Pointer to device list struct.

Return values

• 0 – if successful.

• -EINVAL – if duplicate addresses.

void i3c_addr_slots_set(struct i3c_addr_slots *slots, uint8_t dev_addr, enum i3c_addr_slot_status status)

Set the address status of a device.

Parameters

• slots – Pointer to the address slots structure.

• dev_addr – Device address.

• status – New status for the address dev_addr.

enum i3c_addr_slot_status i3c_addr_slots_status(struct i3c_addr_slots *slots, uint8_t dev_addr)

Get the address status of a device.

Parameters

• slots – Pointer to the address slots structure.

• dev_addr – Device address.

Returns

Address status for the address dev_addr.
bool i3c_addr_slots_is_free(struct i3c_addr_slots *slots, uint8_t dev_addr)
Check if the address is free.

Parameters
• slots – Pointer to the address slots structure.
• dev_addr – Device address.

Return values
• true – if address is free.
• false – if address is not free.

uint8_t i3c_addr_slots_next_free_find(struct i3c_addr_slots *slots)
Find the next free address.
This can be used to find the next free address that can be assigned to a new device.

Parameters
• slots – Pointer to the address slots structure.

Returns
The next free address, or 0 if none found.

static inline void i3c_addr_slots_mark_free(struct i3c_addr_slots *addr_slots, uint8_t addr)
Mark the address as free (not used) in device list.

Parameters
• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_rsvd(struct i3c_addr_slots *addr_slots, uint8_t addr)
Mark the address as reserved in device list.

Parameters
• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_i3c(struct i3c_addr_slots *addr_slots, uint8_t addr)
Mark the address as I3C device in device list.

Parameters
• addr_slots – Pointer to the address slots struct.
• addr – Device address.

static inline void i3c_addr_slots_mark_i2c(struct i3c_addr_slots *addr_slots, uint8_t addr)
Mark the address as I2C device in device list.

Parameters
• addr_slots – Pointer to the address slots struct.
• addr – Device address.

#include <addresses.h>
Structure to keep track of addresses on I3C bus.
7.3.22 IPM

Overview

API Reference

group ipm_interface
   IPM Interface.

Typedefs

typedef void (*ipm_callback_t)(const struct device *ipmdev, void *user_data, uint32_t id, volatile void *data)
   Callback API for incoming IPM messages.
   These callbacks execute in interrupt context. Therefore, use only interrupt-safe APIs. Registration of callbacks is done via ipm_register_callback

   Param ipmdev
      Driver instance

   Param user_data
      Pointer to some private data provided at registration time.

   Param id
      Message type identifier.

   Param data
      Message data pointer. The correct amount of data to read out must be inferred using the message id/upper level protocol.

typedef int (*ipm_send_t)(const struct device *ipmdev, int wait, uint32_t id, const void *data, int size)
   Callback API to send IPM messages.
   See ipm_send() for argument definitions.

typedef int (*ipm_max_data_size_get_t)(const struct device *ipmdev)
   Callback API to get maximum data size.
   See ipm_max_data_size_get() for argument definitions.

typedef uint32_t (*ipm_max_id_val_get_t)(const struct device *ipmdev)
   Callback API to get the ID's maximum value.
   See ipm_max_id_val_get() for argument definitions.

typedef void (*ipm_register_callback_t)(const struct device *port, ipm_callback_t cb, void *user_data)
   Callback API upon registration.
   See ipm_register_callback() for argument definitions.

typedef int (*ipm_set_enabled_t)(const struct device *ipmdev, int enable)
   Callback API upon enablement of interrupts.
   See ipm_set_enabled() for argument definitions.
typedef void (*ipm_complete_t)(const struct device *ipmdev)
Callback API upon command completion.
See ipm_complete() for argument definitions.

Functions

int ipm_send(const struct device *ipmdev, int wait, uint32_t id, const void *data, int size)
Try to send a message over the IPM device.

A message is considered consumed once the remote interrupt handler finishes. If there is
defferred processing on the remote side, or if outgoing messages must be queued and wait on
an event/semaphore, a high-level driver can implement that.

There are constraints on how much data can be sent or the maximum value of id. Use the
ipm_max_data_size_get and ipm_max_id_val_get routines to determine them.

The size parameter is used only on the sending side to determine the amount of data to put
in the message registers. It is not passed along to the receiving side. The upper-level protocol
dictates the amount of data read back.

Parameters

• ipmdev – Driver instance
• wait – If nonzero, busy-wait for remote to consume the message. The message
  is considered consumed once the remote interrupt handler finishes. If there is
  deferred processing on the remote side, or you would like to queue outgoing
  messages and wait on an event/semaphore, you can implement that in a high-
  level driver
• id – Message identifier. Values are constrained by ipm_max_data_size_get since
  many boards only allow for a subset of bits in a 32-bit register to store the ID.
• data – Pointer to the data sent in the message.
• size – Size of the data.

Return values

• -EBUSY – If the remote hasn’t yet read the last data sent.
• -EMSGSIZE – If the supplied data size is unsupported by the driver.
• -EINVAL – If there was a bad parameter, such as: too-large id value. or the
  device isn’t an outbound IPM channel.
• 0 – On success.

static inline void ipm_register_callback(const struct device *ipmdev, ipm_callback_t cb, void *
user_data)
Register a callback function for incoming messages.

Parameters

• ipmdev – Driver instance pointer.
• cb – Callback function to execute on incoming message interrupts.
• user_data – Application-specific data pointer which will be passed to the call-
  back function when executed.

int ipm_max_data_size_get(const struct device *ipmdev)
Return the maximum number of bytes possible in an outbound message.

IPM implementations vary on the amount of data that can be sent in a single message since
the data payload is typically stored in registers.
Parameters

- ipmdev – Driver instance pointer.

Returns

Maximum possible size of a message in bytes.

```c
uint32_t ipm_max_id_val_get(const struct device *ipmdev)
```

Return the maximum id value possible in an outbound message.

Many IPM implementations store the message's ID in a register with some bits reserved for other uses.

Parameters

- ipmdev – Driver instance pointer.

Returns

Maximum possible value of a message ID.

```c
int ipm_set_enabled(const struct device *ipmdev, int enable)
```

Enable interrupts and callbacks for inbound channels.

Parameters

- ipmdev – Driver instance pointer.
- enable – Set to 0 to disable and to nonzero to enable.

Return values

- 0 – On success.
- -EINVAL – If it isn't an inbound channel.

```c
void ipm_complete(const struct device *ipmdev)
```

Signal asynchronous command completion.

Some IPM backends have an ability to deliver a command asynchronously. The callback will be invoked in interrupt context, but the message (including the provided data pointer) will stay “active” and unacknowledged until later code (presumably in thread mode) calls `ipm_complete()`.

This function is, obviously, a noop on drivers without async support.

Parameters

- ipmdev – Driver instance pointer.

```c
#include <ipm.h>
```

### 7.3.23 KSCAN

**Overview**

The kscan driver (keyboard scan matrix) is used for detecting a key press in a connected matrix keyboard or any device with buttons such as joysticks. Typically, matrix keyboards are implemented using a two-dimensional configuration in order to sense several keys. This allows interfacing to many keys through fewer physical pins. Keyboard matrix drivers read the rows while applying power through the columns one at a time with the purpose of detecting key events. There is no correlation between the physical and electrical layout of keys. For example, the physical layout may be one array of 16 or fewer keys, which may be electrically connected to a 4 x 4 array. In addition, key values are defined by a keymap provided by the keyboard manufacturer.
**Configuration Options**

Related configuration options:

- CONFIG_KSCAN

**API Reference**

**group** kscan_interface

KSCAN APIs.

**Typedefs**

typedef void (*kscan_callback_t)(const struct device *dev, uint32_t row, uint32_t column, bool pressed)

Keyboard scan callback called when user press/release a key on a matrix keyboard.

**Param dev**
Pointer to the device structure for the driver instance.

**Param row**
Describes row change.

**Param column**
Describes column change.

**Param pressed**
Describes the kind of key event.

**Functions**

int kscan_config(const struct device *dev, kscan_callback_t callback)

Configure a Keyboard scan instance.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- callback – called when keyboard devices reply to to a keyboard event such as key pressed/released.

**Return values**

- 0 – If successful.
- Negative – errno code if failure.

int kscan_enable_callback(const struct device *dev)

Enables callback.

**Parameters**

- dev – Pointer to the device structure for the driver instance.

**Return values**

- 0 – If successful.
- Negative – errno code if failure.
int kscan_disable_callback(const struct device *dev)

Disables callback.

**Parameters**

- *dev* – Pointer to the device structure for the driver instance.

**Return values**

- 0 – If successful.
- Negative – errno code if failure.

---

### 7.3.24 LED

**Overview**

The LED API provides access to Light Emitting Diodes, both in individual and strip form.

**Configuration Options**

Related configuration options:

- `CONFIG_LED`
- `CONFIG_LED_STRIP`

**API Reference**

#### LED

**group led_interface**

LED Interface.

**Typedefs**

typedef int (*led_api_blink)(const struct device *dev, uint32_t led, uint32_t delay_on, uint32_t delay_off)

Callback API for blinking an LED.

**See also:**

`led_blink()` for argument descriptions.

typedef int (*led_api_get_info)(const struct device *dev, uint32_t led, const struct led_info **info)

Optional API callback to get LED information.

**See also:**

`led_get_info()` for argument descriptions.
typedef int (*led_api_set_brightness)(const struct device *dev, uint32_t led, uint8_t value)
   Callback API for setting brightness of an LED.

   See also:
   led_set_brightness() for argument descriptions.

typedef int (*led_api_set_color)(const struct device *dev, uint32_t led, uint8_t num_colors,
   const uint8_t *color)
   Optional API callback to set the colors of a LED.

   See also:
   led_set_color() for argument descriptions.

typedef int (*led_api_on)(const struct device *dev, uint32_t led)
   Callback API for turning on an LED.

   See also:
   led_on() for argument descriptions.

typedef int (*led_api_off)(const struct device *dev, uint32_t led)
   Callback API for turning off an LED.

   See also:
   led_off() for argument descriptions.

typedef int (*led_api_write_channels)(const struct device *dev, uint32_t start_channel,
   uint32_t num_channels, const uint8_t *buf)
   Callback API for writing a strip of LED channels.

   See also:
   led_api_write_channels() for arguments descriptions.

Functions

int led_blink(const struct device *dev, uint32_t led, uint32_t delay_on, uint32_t delay_off)
   Blink an LED.

   This optional routine starts blinking a LED forever with the given time period.

   Parameters
   • dev – LED device
   • led – LED number
   • delay_on – Time period (in milliseconds) an LED should be ON
   • delay_off – Time period (in milliseconds) an LED should be OFF
Returns
0 on success, negative on error

int led_get_info(const struct device *dev, uint32_t led, const struct led_info **info)
Get LED information.
This optional routine provides information about a LED.

Parameters
• dev – LED device
• led – LED number
• info – Pointer to a pointer filled with LED information

Returns
0 on success, negative on error

int led_set_brightness(const struct device *dev, uint32_t led, uint8_t value)
Set LED brightness.
This optional routine sets the brightness of a LED to the given value. Calling this function after led_blink() won't affect blinking.
LEDs which can only be turned on or off may provide this function. These should simply turn the LED on if value is nonzero, and off if value is zero.

Parameters
• dev – LED device
• led – LED number
• value – Brightness value to set in percent

Returns
0 on success, negative on error

int led_write_channels(const struct device *dev, uint32_t start_channel, uint32_t num_channels, const uint8_t *buf)
Write/update a strip of LED channels.
This optional routine writes a strip of LED channels to the given array of levels. Therefore it can be used to configure several LEDs at the same time.
Calling this function after led_blink() won't affect blinking.

Parameters
• dev – LED device
• start_channel – Absolute number (i.e. not relative to a LED) of the first channel to update.
• num_channels – The number of channels to write/update.
• buf – array of values to configure the channels with. num_channels entries must be provided.

Returns
0 on success, negative on error

int led_set_channel(const struct device *dev, uint32_t channel, uint8_t value)
Set a single LED channel.
This optional routine sets a single LED channel to the given value.
Calling this function after led_blink() won't affect blinking.

Parameters
• **dev** – LED device
• **channel** – Absolute channel number (i.e. not relative to a LED)
• **value** – Value to configure the channel with

**Returns**
0 on success, negative on error

```
int led_set_color(const struct device *dev, uint32_t led, uint8_t num_colors, const uint8_t *color)
```

Set LED color.
This routine configures all the color channels of a LED with the given color array.
Calling this function after `led_blink()` won’t affect blinking.

**Parameters**
• **dev** – LED device
• **led** – LED number
• **num_colors** – Number of colors in the array.
• **color** – Array of colors. It must be ordered following the color mapping of the LED controller. See the the color_mapping member in struct `led_info`.

**Returns**
0 on success, negative on error

```
int led_on(const struct device *dev, uint32_t led)
```

Turn on an LED.
This routine turns on an LED

**Parameters**
• **dev** – LED device
• **led** – LED number

**Returns**
0 on success, negative on error

```
int led_off(const struct device *dev, uint32_t led)
```

Turn off an LED.
This routine turns off an LED

**Parameters**
• **dev** – LED device
• **led** – LED number

**Returns**
0 on success, negative on error

```
struct led_info
#include <led.h> LED information structure.
```

This structure gathers useful information about LED controller.

**Param label**
LED label.

**Param num_colors**
Number of colors per LED.
Param index
Index of the LED on the controller.

Param color_mapping
Mapping of the LED colors.

struct led_driver_api
#include <led.h> LED driver API.

LED Strip

group led_strip_interface
LED Strip Interface.

Typedefs

typedef int (*led_api_update_rgb)(const struct device *dev, struct led_rgb *pixels, size_t num_pixels)
Callback API for updating an RGB LED strip.

See also:
led_strip_update_rgb() for argument descriptions.

typedef int (*led_api_update_channels)(const struct device *dev, uint8_t *channels, size_t num_channels)
Callback API for updating channels without an RGB interpretation.

See also:
led_strip_update_channels() for argument descriptions.

Functions

static inline int led_strip_update_rgb(const struct device *dev, struct led_rgb *pixels, size_t num_pixels)
Update an LED strip made of RGB pixels.
Important: This routine may overwrite pixels.
This routine immediately updates the strip display according to the given pixels array.

Warning: May overwrite pixels

Parameters
• dev – LED strip device
• pixels – Array of pixel data
• num_pixels – Length of pixels array

Returns
0 on success, negative on error
static inline int led_strip_update_channels(const struct device *dev, uint8_t *channels, size_t num_channels)

Update an LED strip on a per-channel basis.

Important: This routine may overwrite channels.

This routine immediately updates the strip display according to the given channels array. Each channel byte corresponds to an individually addressable color channel or LED. Channels are updated linearly in strip order.

**Warning:** May overwrite channels

**Parameters**

- **dev** – LED strip device
- **channels** – Array of per-channel data
- **num_channels** – Length of channels array

**Returns**

0 on success, negative on error

```c
struct led_rgb
#include <led_strip.h> Color value for a single RGB LED.

Individual strip drivers may ignore lower-order bits if their resolution in any channel is less than a full byte.

**Public Members**

```c
uint8_t r
Red channel

uint8_t g
Green channel

uint8_t b
Blue channel
```

```c
struct led_strip_driver_api
#include <led_strip.h> LED strip driver API.

This is the mandatory API any LED strip driver needs to expose.
```

### 7.3.25 MBOX

#### Overview

An MBOX device is a peripheral capable of passing signals (and data depending on the peripheral) between CPUs and clusters in the system. Each MBOX instance is providing one or more channels, each one targeting one other CPU cluster (multiple channels can target the same cluster).
An MBOX device is a peripheral capable of passing signals (and data depending on the peripheral) between CPUs and clusters in the system. Each MBOX instance is providing one or more channels, each one targeting one other CPU cluster (multiple channels can target the same cluster).

For example in the plot the device ‘dev A’ is using the TX channel 9 to signal (or send data to) the CPU #2 and it’s expecting data or signals on the RX channel 8. Thus it can send the message through the channel 9, and it can register a callback on the channel 8 of the MBOX device.

This API supports two modes: signalling mode and data transfer mode.

In signalling mode:
- `mbox_mtu_get()` must return 0
- `mbox_send()` must have (msg == NULL)
- the callback must be called with (data == NULL)

In data transfer mode:
- `mbox_mtu_get()` must return a (value != 0)
- `mbox_send()` must have (msg != NULL)
- the callback must be called with (data != NULL)
- The msg content must be the same between sender and receiver

**Defines**

MBOX_DT_CHANNEL_GET(node_id, name)

Structure initializer for `mbox_channel` from devicetree.

This helper macro expands to a static initializer for a `mbox_channel` by reading the relevant device controller and channel number from the devicetree.

Example devicetree fragment:
mbox1: mbox-controller@... { ... };

n: node {
    mboxes = <&mbox1 8>,
    <&mbox1 9>;
    mbox-names = "tx", "rx";
};

Example usage:

const struct mbox_channel channel = MBOX_DT_CHANNEL_GET(DT_NODELABEL(n), tx);

Parameters

- node_id – Devicetree node identifier for the MBOX device
- name – lowercase-and-underscores name of the mboxes element

Typedefs

typedef void (*mbox_callback_t)(const struct device *dev, uint32_t channel, void *user_data, struct mbox_msg *data)

Callback API for incoming MBOX messages.
These callbacks execute in interrupt context. Therefore, use only interrupt-safe APIs. Registration of callbacks is done via mbox_register_callback()

The data parameter must be NULL in signalling mode.

Param dev
    Driver instance

Param channel
    Channel ID

Param user_data
    Pointer to some private data provided at registration time

Param data
    Message struct

typedef int (*mbox_send_t)(const struct device *dev, uint32_t channel, const struct mbox_msg *msg)

Callback API to send MBOX messages.
See mbox_send() for function description

Param dev
    Driver instance

Param channel
    Channel ID

Param msg
    Message struct

Return
    See return values for mbox_send()
typedef int (*mbox_mtu_get_t)(const struct device *dev)
Callback API to get maximum data size.
See mbox_mtu_get() for argument definitions.

typedef int (*mbox_register_callback_t)(const struct device *dev, uint32_t channel, mbox_callback_t cb, void *user_data)
Callback API upon registration.
See mbox_register_callback() for function description

  Param dev            Driver instance
  Param channel       Channel ID
  Param cb            Callback function to execute on incoming message interrupts.
  Param user_data     Application-specific data pointer which will be passed to the callback function when executed.

  Return See return values for mbox_register_callback()

typedef int (*mbox_set_enabled_t)(const struct device *dev, uint32_t channel, bool enable)
Callback API upon enablement of interrupts.
See mbox_set_enabled() for function description

  Param dev            Driver instance
  Param channel       Channel ID
  Param enable        Set to 0 to disable and to nonzero to enable.

  Return See return values for mbox_set_enabled()

typedef uint32_t (*mbox_max_channels_get_t)(const struct device *dev)
Callback API to get maximum number of channels.
See mbox_max_channels_get() for argument definitions.

Functions

static inline void mbox_init_channel(struct mbox_channel *channel, const struct device *dev, uint32_t ch_id)
Initialize a channel struct.
Initialize an mbox_channel passed by the user with a provided MBOX device and channel ID.
This function is needed when the information about the device and the channel ID is not in
the DT. In the DT case MBOX_DT_CHANNEL_GET() must be used instead.

  Parameters
  • channel – Pointer to the channel struct
Try to send a message over the MBOX device.

Send a message over an `mbox_channel`. The `msg` parameter must be NULL when the driver is used for signalling.

If the `msg` parameter is not NULL, this data is expected to be delivered on the receiving side using the data parameter of the receiving callback.

### Parameters

- `channel` – Channel instance pointer.
- `msg` – Pointer to the message struct

### Return values

- `-EBUSY` – If the remote hasn’t yet read the last data sent.
- `-EMSGSIZE` – If the supplied data size is unsupported by the driver.
- `-EINVAL` – If there was a bad parameter, such as: too-large channel descriptor or the device isn’t an outbound MBOX channel.
- `0` – On success, negative value on error.

---

Register a callback function on a channel for incoming messages.

This function doesn’t assume anything concerning the status of the interrupts. Use `mbox_set_enabled()` to enable or to disable the interrupts if needed.

### Parameters

- `channel` – Channel instance pointer.
- `cb` – Callback function to execute on incoming message interrupts.
- `user_data` – Application-specific data pointer which will be passed to the callback function when executed.

### Return values

- `0` – On success, negative value on error.

---

Return the maximum number of bytes possible in an outbound message.

Returns the actual number of bytes that it is possible to send through an outgoing channel.

This number can be 0 when the driver only supports signalling or when on the receiving side the content and size of the message must be retrieved in an indirect way (i.e. probing some other peripheral, reading memory regions, etc...).

If this function returns 0, the `msg` parameter in `mbox_send()` is expected to be NULL.

### Parameters

- `dev` – Driver instance pointer.

### Returns

Maximum possible size of a message in bytes, 0 for signalling, negative value on error.
int mbox_set_enabled(const struct mbox_channel *channel, bool enable)
Enable (disable) interrupts and callbacks for inbound channels.
Enable interrupt for the channel when the parameter 'enable' is set to true. Disable it otherwise.
Immediately after calling this function with 'enable' set to true, the channel is considered enabled and ready to receive signal and messages (even already pending), so the user must take care of installing a proper callback (if needed) using mbox_register_callback() on the channel before enabling it. For this reason it is recommended that all the channels are disabled at probe time.
Enabling a channel for which there is no installed callback is considered undefined behavior (in general the driver must take care of gracefully handling spurious interrupts with no installed callback).

Parameters
• channel – Channel instance pointer.
• enable – Set to 0 to disable and to nonzero to enable.

Return values
• 0 – On success.
• -EINVAL – If it isn’t an inbound channel.

uint32_t mbox_max_channels_get(const struct device *dev)
Return the maximum number of channels.

Parameters
• dev – Driver instance pointer.

Returns
Maximum possible number of supported channels on success, negative value on error.

struct mbox_msg

#include <mbox.h> Message struct (to hold data and its size).

Public Members

const void *data
Pointer to the data sent in the message.

size_t size
Size of the data.

struct mbox_channel

#include <mbox.h> Provides a type to hold an MBOX channel.
Struct type to hold an MBOX device pointer and the channel ID.

Public Members
const struct device *dev
   MBOX device pointer.

uint32_t id
   Channel ID.

#include <mbox.h>

7.3.26 Pinmux

Overview

API Reference

group pinmux_interface
   Pinmux Interface.

Defines

PINMUX_FUNC_A
PINMUX_FUNC_B
PINMUX_FUNC_C
PINMUX_FUNC_D
PINMUX_FUNC_E
PINMUX_FUNC_F
PINMUX_FUNC_G
PINMUX_FUNC_H
PINMUX_FUNC_I
PINMUX_FUNC_J
PINMUX_FUNC_K
PINMUX_FUNC_L
PINMUX_FUNC_M
typedef int (*pmux_set)(const struct device *dev, uint32_t pin, uint32_t func)
        Callback API upon setting a PIN's function See pinmux_pin_set() for argument description.

typedef int (*pmux_get)(const struct device *dev, uint32_t pin, uint32_t *func)
        Callback API upon getting a PIN's function See pinmux_pin_get() for argument description.

typedef int (*pmux_pullup)(const struct device *dev, uint32_t pin, uint8_t func)
        Callback API upon setting a PIN's pullup See pinmux_pin_pullup() for argument description.

typedef int (*pmux_input)(const struct device *dev, uint32_t pin, uint8_t func)
        Callback API upon setting a PIN's input function See pinmux_input() for argument description.

Functions

static inline int pinmux_pin_set(const struct device *dev, uint32_t pin, uint32_t func)
static inline int pinmux_pin_get(const struct device *dev, uint32_t pin, uint32_t *func)
static inline int pinmux_pin_pullup(const struct device *dev, uint32_t pin, uint8_t func)
static inline int pinmux_pin_input_enable(const struct device *dev, uint32_t pin, uint8_t func)

#include <pinmux.h>
group pwm_interface

   PWM Interface.

   **PWM capture configuration flags**

   PWM_CAPTURE_TYPE_PERIOD
       PWM pin capture captures period.

   PWM_CAPTURE_TYPE_PULSE
       PWM pin capture captures pulse width.

   PWM_CAPTURE_TYPE_BOTH
       PWM pin capture captures both period and pulse width.

   PWM_CAPTURE_MODE_SINGLE
       PWM pin capture captures a single period/pulse width.

   PWM_CAPTURE_MODE_CONTINUOUS
       PWM pin capture captures period/pulse width continuously.

   **PWM period set helpers**

   The period cell in the PWM specifier needs to be provided in nanoseconds. However, in some applications it is more convenient to use another scale.

   PWM_NSEC(x)
       Specify PWM period in nanoseconds

   PWM_USEC(x)
       Specify PWM period in microseconds

   PWM_MSEC(x)
       Specify PWM period in milliseconds

   PWM_SEC(x)
       Specify PWM period in seconds

   PWM_HZ(x)
       Specify PWM frequency in hertz

   PWM_KHZ(x)
       Specify PWM frequency in kilohertz

   **PWM polarity flags**

   The PWM_POLARITY_* flags are used with *pwm_set_cycles(), pwm_set() or pwm_configure_capture()* to specify the polarity of a PWM channel.

   The flags are on the lower 8 bits of the pwm_flags_t
PWM_POLARITY_NORMAL
PWM pin normal polarity (active-high pulse).

PWM_POLARITY_INVERTED
PWM pin inverted polarity (active-low pulse).

Defines

PWM_DT_SPEC_GET_BY_NAME(node_id, name)
Static initializer for a struct pwm_dt_spec.
This returns a static initializer for a struct pwm_dt_spec given a devicetree node identifier and an index.

Example devicetree fragment:

```c
n: node {
    pwms = &pwm1 1 1000 PWM_POLARITY_NORMAL,
           &pwm2 3 2000 PWM_POLARITY_INVERTED;
    pwm-names = "alpha", "beta";
}
```

Example usage:

```c
const struct pwm_dt_spec spec =
    PWM_DT_SPEC_GET_BY_NAME(DT_NODELABEL(n), alpha);
```

// Initializes 'spec' to:
// { 
//    .dev = DEVICE_DT_GET(DT_NODELABEL(pwm1)),
//    .channel = 1,
//    .period = 1000,
//    .flags = PWM_POLARITY_NORMAL,
// }

The device (dev) must still be checked for readiness, e.g. using device_is_ready(). It is an error to use this macro unless the node exists, has the 'pwms' property, and that 'pwms' property specifies a PWM controller, a channel, a period in nanoseconds and optionally flags.

See also:

PWM_DT_SPEC_INST_GET_BY_NAME

Parameters

- node_id – Devicetree node identifier.
- name – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property.

Returns

Static initializer for a struct pwm_dt_spec for the property.
PWM_DT_SPEC_INST_GET_BY_NAME(inst, name)

Static initializer for a struct pwm_dt_spec from a DT_DRV_COMPAT instance.

See also:
PWM_DT_SPEC_GET_BY_NAME

Parameters

• inst – DT_DRV_COMPAT instance number
• name – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property.

Returns
Static initializer for a struct pwm_dt_spec for the property.

PWM_DT_SPEC_GET_BY_NAME_OR(node_id, name, default_value)

Like PWM_DT_SPEC_GET_BY_NAME(), with a fallback to a default value.

If the devicetree node identifier ‘node_id’ refers to a node with a property ‘pwms’, this expands to PWM_DT_SPEC_GET_BY_NAME(node_id, name). The default_value parameter is not expanded in this case. Otherwise, this expands to default_value.

See also:
PWM_DT_SPEC_INST_GET_BY_NAME_OR

Parameters

• node_id – Devicetree node identifier.
• name – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property, or default_value if the node or property do not exist.

PWM_DT_SPEC_INST_GET_BY_NAME_OR(inst, name, default_value)

Like PWM_DT_SPEC_INST_GET_BY_NAME_OR, with a fallback to a default value.

See also:
PWM_DT_SPEC_GET_BY_NAME_OR

Parameters

• inst – DT_DRV_COMPAT instance number
• name – Lowercase-and-underscores name of a pwms element as defined by the node’s pwm-names property.
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property, or default_value if the node or property do not exist.
PWM_DT_SPEC_GET_BY_IDX(node_id, idx)

Static initializer for a struct pwm_dt_spec.

This returns a static initializer for a struct pwm_dt_spec given a devicetree node identifier and an index.

Example devicetree fragment:

```c
n: node {
    pwms = <&pwm1 1 1000 PWM_POLARITY_NORMAL>,
          <&pwm2 3 2000 PWM_POLARITY_INVERTED>;
};
```

Example usage:

```c
const struct pwm_dt_spec spec =
    PWM_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n), 1);

// Initializes 'spec' to:
// {
//   .dev = DEVICE_DT_GET(DT_NODELABEL(pwm2)),
//   .channel = 3,
//   .period = 2000,
//   .flags = PWM_POLARITY_INVERTED,
// }
```

The device (dev) must still be checked for readiness, e.g. using device_is_ready(). It is an error to use this macro unless the node exists, has the ‘pwms’ property, and that ‘pwms’ property specifies a PWM controller, a channel, a period in nanoseconds and optionally flags.

See also:

PWM_DT_SPEC_INST_GET_BY_IDX

Parameters

- node_id – Devicetree node identifier.
- idx – Logical index into ‘pwms’ property.

Returns

Static initializer for a struct pwm_dt_spec for the property.

PWM_DT_SPEC_INST_GET_BY_IDX(inst, idx)

Static initializer for a struct pwm_dt_spec from a DT_DRV_COMPAT instance.

See also:

PWM_DT_SPEC_GET_BY_IDX

Parameters

- inst – DT_DRV_COMPAT instance number
- idx – Logical index into ‘pwms’ property.

Returns

Static initializer for a struct pwm_dt_spec for the property.
PWM_DT_SPEC_GET_BY_IDX_OR(node_id, idx, default_value)
Like PWM_DT_SPEC_GET_BYIDX(), with a fallback to a default value.
If the devicetree node identifier ‘node_id’ refers to a node with a property ‘pwms’, this expands to PWM_DT_SPEC_GET_BYIDX(node_id, idx). The default_value parameter is not expanded in this case. Otherwise, this expands to default_value.

See also:
PWM_DT_SPEC_INST_GET_BY_IDX_OR

Parameters
• node_id – Devicetree node identifier.
• idx – Logical index into ‘pwms’ property.
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property, or default_value if the node or property do not exist.

PWM_DT_SPEC_INST_GET_BY_IDX_OR(inst, idx, default_value)
Like PWM_DT_SPEC_INST_GET_BYIDX(), with a fallback to a default value.

See also:
PWM_DT_SPEC_GET_BY_IDX_OR

Parameters
• inst – DT_DRV_COMPAT instance number
• idx – Logical index into ‘pwms’ property.
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property, or default_value if the node or property do not exist.

PWM_DT_SPEC_GET(node_id)
Equivalent to PWM_DT_SPEC_GET_BYIDX(node_id, 0).

See also:
PWM_DT_SPEC_GET_BYIDX

See also:
PWM_DT_SPEC_INST_GET

Parameters
• node_id – Devicetree node identifier.

Returns
Static initializer for a struct pwm_dt_spec for the property.
PWM_DT_SPEC_INST_GET(inst)
    Equivalent to PWM_DT_SPEC_INST_GET_BY_IDX(inst, 0).

See also:
PWM_DT_SPEC_INST_GET_BY_IDX

See also:
PWM_DT_SPEC_GET

Parameters
• inst – DT_DRV_COMPAT instance number

Returns
Static initializer for a struct pwm_dt_spec for the property.

PWM_DT_SPEC_GET_OR(node_id, default_value)
    Equivalent to PWM_DT_SPEC_GET_BY_IDX_OR(node_id, 0, default_value).

See also:
PWM_DT_SPEC_GET_BY_IDX_OR

See also:
PWM_DT_SPEC_INST_GET_OR

Parameters
• node_id – Devicetree node identifier.
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property.

PWM_DT_SPEC_INST_GET_OR(inst, default_value)
    Equivalent to PWM_DT_SPEC_INST_GET_BY_IDX_OR(inst, 0, default_value).

See also:
PWM_DT_SPEC_INST_GET_BY_IDX_OR

See also:
PWM_DT_SPEC_GET_OR

Parameters
• inst – DT_DRV_COMPAT instance number
• default_value – Fallback value to expand to.

Returns
Static initializer for a struct pwm_dt_spec for the property.
Typedefs

typedef uint16_t pwm_flags_t

  Provides a type to hold PWM configuration flags.
  The lower 8 bits are used for standard flags. The upper 8 bits are reserved for SoC specific flags.

See also: PWM_CAPTURE_FLAGS.

typedef void (*pwm_capture_callback_handler_t)(const struct device *dev, uint32_t channel,
uint32_t period_cycles, uint32_t pulse_cycles, int status, void *user_data)

  PWM capture callback handler function signature.

  Note: The callback handler will be called in interrupt context.

  Note: CONFIG_PWM_CAPTURE must be selected to enable PWM capture support.

  Param dev
      [in] PWM device instance.

  Param channel
      PWM channel.

  Param period_cycles
      Captured PWM period width (in clock cycles). HW specific.

  Param pulse_cycles
      Captured PWM pulse width (in clock cycles). HW specific.

  Param status
      Status for the PWM capture (0 if no error, negative errno otherwise. See pwm_capture_cycles() return value descriptions for details).

  Param user_data
      User data passed to pwm_configure_capture()

Functions

int pwm_set_cycles(const struct device *dev, uint32_t channel, uint32_t period, uint32_t pulse,
                   pwm_flags_t flags)

  Set the period and pulse width for a single PWM output.
  The PWM period and pulse width will synchronously be set to the new values without glitches
  in the PWM signal, but the call will not block for the change to take effect.

  Passing 0 as pulse will cause the pin to be driven to a constant inactive level. Passing a
  non-zero pulse equal to period will cause the pin to be driven to a constant active level.
Note: Not all PWM controllers support synchronous, glitch-free updates of the PWM period and pulse width. Depending on the hardware, changing the PWM period and/or pulse width may cause a glitch in the generated PWM signal.

Note: Some multi-channel PWM controllers share the PWM period across all channels. Depending on the hardware, changing the PWM period for one channel may affect the PWM period for the other channels of the same PWM controller.

Parameters

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **period** – Period (in clock cycles) set to the PWM. HW specific.
- **pulse** – Pulse width (in clock cycles) set to the PWM. HW specific.
- **flags** – Flags for pin configuration.

Return values

- **0** – If successful.
- **-EINVAL** – If pulse > period.
- **-errno** – Negative errno code on failure.

```c
int pwm_get_cycles_per_sec(const struct device *dev, uint32_t channel, uint64_t *cycles)
```

Get the clock rate (cycles per second) for a single PWM output.

Parameters

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **cycles** – [out] Pointer to the memory to store clock rate (cycles per sec). HW specific.

Return values

- **0** – If successful.
- **-errno** – Negative errno code on failure.

```c
static inline int pwm_set(const struct device *dev, uint32_t channel, uint32_t period, uint32_t pulse, pwm_flags_t flags)
```

Set the period and pulse width in nanoseconds for a single PWM output.

Note: Utility macros such as `PWM_MSEC()` can be used to convert from other scales or units to nanoseconds, the units used by this function.
Return values

• 0 – If successful.
• -ENOTSUP – If requested period or pulse cycles are not supported.
• -errno – Other negative errno code on failure.

static inline int pwm_set_dt(const struct pwm_dt_spec *spec, uint32_t period, uint32_t pulse)

Set the period and pulse width in nanoseconds from a struct pwm_dt_spec (with custom period).

This is equivalent to:

```c
pwm_set(spec->dev, spec->channel, period, pulse, spec->flags)
```

The period specified in spec is ignored. This API call can be used when the period specified in Devicetree needs to be changed at runtime.

See also:

pwm_set_pulse_dt()

Parameters

• spec – [in] PWM specification from devicetree.
• period – Period (in nanoseconds) set to the PWM.
• pulse – Pulse width (in nanoseconds) set to the PWM.

Returns

A value from pwm_set().

static inline int pwm_set_pulse_dt(const struct pwm_dt_spec *spec, uint32_t pulse)

Set the period and pulse width in nanoseconds from a struct pwm_dt_spec.

This is equivalent to:

```c
pwm_set(spec->dev, spec->channel, spec->period, pulse, spec->flags)
```

See also:

pwm_set_pulse_dt()

Parameters

• spec – [in] PWM specification from devicetree.
• pulse – Pulse width (in nanoseconds) set to the PWM.

Returns

A value from pwm_set().

static inline int pwm_cycles_to_usec(const struct device *dev, uint32_t channel, uint32_t cycles, uint64_t *usec)

Convert from PWM cycles to microseconds.

Parameters

• dev – [in] PWM device instance.
• channel – PWM channel.
• cycles – Cycles to be converted.
• **usec** – [out] Pointer to the memory to store calculated usec.

**Return values**
- 0 – If successful.
- -ERANGE – If result is too large.
- -errno – Other negative errno code on failure.

static inline int pwm_cycles_to_nsec(const struct device *dev, uint32_t channel, uint32_t cycles, uint64_t *nsec)

Convert from PWM cycles to nanoseconds.

**Parameters**
- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **cycles** – Cycles to be converted.
- **nsec** – [out] Pointer to the memory to store the calculated nsec.

**Return values**
- 0 – If successful.
- -ERANGE – If result is too large.
- -errno – Other negative errno code on failure.

static inline int pwm_configure_capture(const struct device *dev, uint32_t channel, pwm_flags_t flags, pwm_capture_callback_handler_t cb, void *user_data)

Configure PWM period/pulse width capture for a single PWM input.

After configuring PWM capture using this function, the capture can be enabled/disabled using `pwm_enable_capture()` and `pwm_disable_capture()`.

**Note:** This API function cannot be invoked from user space due to the use of a function callback. In user space, one of the simpler API functions (`pwm_capture_cycles()`, `pwm_capture_usec()`, or `pwm_capture_nsec()`) can be used instead.

**Note:** CONFIG_PWM_CAPTURE must be selected for this function to be available.

**Parameters**
- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **flags** – PWM capture flags
- **cb** – [in] Application callback handler function to be called upon capture
- **user_data** – [in] User data to pass to the application callback handler function

**Return values**
- EINVAL – if invalid function parameters were given
- ENSYS – if PWM capture is not supported or the given flags are not supported
- EIO – if IO error occurred while configuring
- EBUSY – if PWM capture is already in progress
int pwm_enable_capture(const struct device *dev, uint32_t channel)
Enable PWM period/pulse width capture for a single PWM input.

The PWM pin must be configured using pwm_configure_capture() prior to calling this function.

**Note:** CONFIG_PWM_CAPTURE must be selected for this function to be available.

**Parameters**
- channel – PWM channel.

**Return values**
- 0 – If successful.
- -EINVAL – if invalid function parameters were given
- -ENOSYS – if PWM capture is not supported
- -EIO – if IO error occurred while enabling PWM capture
- -EBUSY – if PWM capture is already in progress

int pwm_disable_capture(const struct device *dev, uint32_t channel)
Disable PWM period/pulse width capture for a single PWM input.

**Note:** CONFIG_PWM_CAPTURE must be selected for this function to be available.

**Parameters**
- channel – PWM channel.

**Return values**
- 0 – If successful.
- -EINVAL – if invalid function parameters were given
- -ENOSYS – if PWM capture is not supported
- -EIO – if IO error occurred while disabling PWM capture

int pwm_capture_cycles(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint32_t *period, uint32_t *pulse, k_timeout_t timeout)
Capture a single PWM period/pulse width in clock cycles for a single PWM input.

This API function wraps calls to pwm_configure_capture(), pwm_enable_capture(), and pwm_disable_capture() and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

**Note:** CONFIG_PWM_CAPTURE must be selected for this function to be available.

**Parameters**
- channel – PWM channel.
- flags – PWM capture flags.
• **period** – [out] Pointer to the memory to store the captured PWM period width (in clock cycles). HW specific.

• **pulse** – [out] Pointer to the memory to store the captured PWM pulse width (in clock cycles). HW specific.

• **timeout** – Waiting period for the capture to complete.

**Return values**

- 0 – If successful.
- -EBUSY – PWM capture already in progress.
- -EAGAIN – Waiting period timed out.
- -EIO – IO error while capturing.
- -ERANGE – If result is too large.

```c
static inline int pwm_capture_usec(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint64_t *period, uint64_t *pulse, k_timeout_t timeout)
```

Capture a single PWM period/pulse width in microseconds for a single PWM input.

This API function wraps calls to `pwm_capture_cycles()` and `pwm_cycles_to_usec()` and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.

---

**Note:** `CONFIG_PWM_CAPTURE` must be selected for this function to be available.

**Parameters**

- **dev** – [in] PWM device instance.
- **channel** – PWM channel.
- **flags** – PWM capture flags.
- **period** – [out] Pointer to the memory to store the captured PWM period width (in usec).
- **pulse** – [out] Pointer to the memory to store the captured PWM pulse width (in usec).
- **timeout** – Waiting period for the capture to complete.

**Return values**

- 0 – If successful.
- -EBUSY – PWM capture already in progress.
- -EAGAIN – Waiting period timed out.
- -EIO – IO error while capturing.
- -ERANGE – If result is too large.
- -errno – Other negative errno code on failure.

```c
static inline int pwm_capture_nsec(const struct device *dev, uint32_t channel, pwm_flags_t flags, uint64_t *period, uint64_t *pulse, k_timeout_t timeout)
```

Capture a single PWM period/pulse width in nanoseconds for a single PWM input.

This API function wraps calls to `pwm_capture_cycles()` and `pwm_cycles_to_nsec()` and passes the capture result to the caller. The function is blocking until either the PWM capture is completed or a timeout occurs.
Note: CONFIG_PWM_CAPTURE must be selected for this function to be available.

Parameters

- `channel` – PWM channel.
- `flags` – PWM capture flags.
- `period` – [out] Pointer to the memory to store the captured PWM period width (in nsec).
- `pulse` – [out] Pointer to the memory to store the captured PWM pulse width (in nsec).
- `timeout` – Waiting period for the capture to complete.

Return values

- 0 – If successful.
- -EBUSY – PWM capture already in progress.
- -EAGAIN – Waiting period timed out.
- -EIO – IO error while capturing.
- -ERANGE – If result is too large.
- -errno – Other negative errno code on failure.

```
struct pwm_dt_spec

#include <pwm.h> Container for PWM information specified in devicetree.

This type contains a pointer to a PWM device, channel number (controlled by the PWM device), the PWM signal period in nanoseconds and the flags applicable to the channel. Note that not all PWM drivers support flags. In such case, flags will be set to 0.

See also:

PWM_DT_SPEC_GET_BY_NAME

See also:

PWM_DT_SPEC_GET_BY_NAME_OR

See also:

PWM_DT_SPEC_GET_BY_IDX

See also:

PWM_DT_SPEC_GET_BY_IDX_OR

See also:

PWM_DT_SPEC_GET

See also:

PWM_DT_SPEC_GET_OR

```
Public Members

const struct device *dev
    PWM device instance.

uint32_t channel
    Channel number.

uint32_t period
    Period in nanoseconds.

pwm_flags_t flags
    Flags.

7.3.28  PS/2

Overview

The PS/2 connector first hit the market in 1987 on IBM's desktop PC line of the same name before becoming an industry-wide standard for mouse and keyboard connections. Starting around 2007, USB superseded PS/2 and is the modern peripheral device connection standard. For legacy support on boards with a PS/2 connector, Zephyr provides these PS/2 driver APIs.

Configuration Options

Related configuration options:

- CONFIG_PS2

API Reference

group ps2_interface
    PS/2 Driver APIs.

Typedefs

typedef void (*ps2_callback_t)(const struct device *dev, uint8_t data)
    PS/2 callback called when user types or click a mouse.

    Param dev
        Pointer to the device structure for the driver instance.

    Param data
        Data byte passed pack to the user.

Functions
int ps2_config(const struct device *dev, ps2_callback_t callback_isr)
Configure a ps2 instance.

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback_isr – called when PS/2 devices reply to a configuration command or when a mouse/keyboard send data to the client application.

Return values

- 0 – If successful.
- Negative – errno code if failure.

int ps2_write(const struct device *dev, uint8_t value)
Write to PS/2 device.

Parameters

- dev – Pointer to the device structure for the driver instance.
- value – Data for the PS2 device.

Return values

- 0 – If successful.
- Negative – errno code if failure.

int ps2_read(const struct device *dev, uint8_t *value)
Read slave-to-host values from PS/2 device.

Parameters

- dev – Pointer to the device structure for the driver instance.
- value – Pointer used for reading the PS/2 device.

Return values

- 0 – If successful.
- Negative – errno code if failure.

int ps2_enable_callback(const struct device *dev)
Enables callback.

Parameters

- dev – Pointer to the device structure for the driver instance.

Return values

- 0 – If successful.
- Negative – errno code if failure.

int ps2_disable_callback(const struct device *dev)
Disables callback.

Parameters

- dev – Pointer to the device structure for the driver instance.

Return values

- 0 – If successful.
- Negative – errno code if failure.
7.3.29 PECI

Overview

The Platform Environment Control Interface, abbreviated as PECI, is a thermal management standard introduced in 2006 with the Intel Core 2 Duo Microprocessors. The PECI interface allows external devices to read processor temperature, perform processor manageability functions, and manage processor interface tuning and diagnostics. The PECI bus driver APIs enable the interaction between Embedded Microcontrollers and CPUs.

Configuration Options

Related configuration options:

- CONFIG_PECI

API Reference

```
group peci_interface
  
  PECI Interface 3.0.

  Defines

  PECI_CC_RSP_SUCCESS
    PECI read/write supported responses

  PECI_CC_RSP_TIMEOUT

  PECI_CC_OUT_OF_RESOURCES_TIMEOUT

  PECI_CC_RESOURCES_LOWPWR_TIMEOUT

  PECI_CC_ILLEGAL_REQUEST

  PECI_PING_WR_LEN
    Ping command format.

  PECI_PING_RD_LEN

  PECI_PING_LEN

  PECI_GET_DIB_WR_LEN
    GetDIB command format.

  PECI_GET_DIB_RD_LEN

  PECI_GET_DIB_CMD_LEN
```
PECI_GET_DIB_DEVINFO

PECI_GET_DIB_RENVNUM

PECI_GET_DIB_DOMAIN_BIT_MASK

PECI_GET_DIB_MAJOR_REV_MASK

PECI_GET_DIB_MINOR_REV_MASK

PECI_GET_TEMP_WR_LEN
    GetTemp command format.

PECI_GET_TEMP_RD_LEN

PECI_GET_TEMP_CMD_LEN

PECI_GET_TEMP_LSB

PECI_GET_TEMP_MSB

PECI_GET_TEMP_ERR_MSB

PECI_GET_TEMP_ERR_LSB_GENERAL

PECI_GET_TEMP_ERR_LSB_RES

PECI_GET_TEMP_ERR_LSB_TEMP_LO

PECI_GET_TEMP_ERR_LSB_TEMP_HI

PECI_RD_PKG_WR_LEN
    RdPkgConfig command format.

PECI_RD_PKG_LEN_BYTE

PECI_RD_PKG_LEN_WORD

PECI_RD_PKG_LEN_DWORD

PECI_RD_PKG_CMD_LEN

PECI_WR_PKG_RD_LEN
    WrPkgConfig command format

PECI_WR_PKG_LEN_BYTE
PECI_WR_PKG_LEN_WORD

PECI_WR_PKG_LEN_DWORD

PECI_WR_PKG_CMD_LEN

PECI_RD_IAMSR_WR_LEN
RdIAMSR command format

PECI_RD_IAMSR_LEN_BYTE

PECI_RD_IAMSR_LEN_WORD

PECI_RD_IAMSR_LEN_DWORD

PECI_RD_IAMSR_LEN_QWORD

PECI_RD_IAMSR_CMD_LEN

PECI_WR_IAMSR_RD_LEN
WrIAMSR command format

PECI_WR_IAMSR_LEN_BYTE

PECI_WR_IAMSR_LEN_WORD

PECI_WR_IAMSR_LEN_DWORD

PECI_WR_IAMSR_LEN_QWORD

PECI_WR_IAMSR_CMD_LEN

PECI_RD_PCICFG_WR_LEN
RdPCIConfig command format

PECI_RD_PCICFG_LEN_BYTE

PECI_RD_PCICFG_LEN_WORD

PECI_RD_PCICFG_LEN_DWORD

PECI_RD_PCICFG_CMD_LEN

PECI_WR_PCICFG_RD_LEN
WrPCIConfig command format
PECI_WR_PCICFG_LEN_BYTE

PECI_WR_PCICFG_LEN_WORD

PECI_WR_PCICFG_LEN_DWORD

PECI_WR_PCICFG_CMD_LEN

PECI_RD_PCICFGL_WR_LEN

RdPCIConfigLocal command format

PECI_RD_PCICFGL_RD_LEN_BYTE

PECI_RD_PCICFGL_RD_LEN_WORD

PECI_RD_PCICFGL_RD_LEN_DWORD

PECI_RD_PCICFGL_CMD_LEN

PECI_WR_PCICFGL_RD_LEN

WrPCIConfigLocal command format

PECI_WR_PCICFGL_WR_LEN_BYTE

PECI_WR_PCICFGL_WR_LEN_WORD

PECI_WR_PCICFGL_WR_LEN_DWORD

PECI_WR_PCICFGL_CMD_LEN

**Enums**

enum peci_error_code

PECI error codes.

*Values:*

enumerator PECI_GENERAL_SENSOR_ERROR = 0x8000

enumerator PECI_UNDERFLOW_SENSOR_ERROR = 0x8002

enumerator PECI_OVERFLOW_SENSOR_ERROR = 0x8003

enum peci_command_code

PECI commands.

*Values:*

7.3. Peripherals
enumerator PECI_CMD_PING = 0x00
enumerator PECI_CMD_GET_TEMP0 = 0x01
enumerator PECI_CMD_GET_TEMP1 = 0x02
enumerator PECI_CMD_RD_PCI_CFG0 = 0x61
enumerator PECI_CMD_RD_PCI_CFG1 = 0x62
enumerator PECI_CMD_WR_PCI_CFG0 = 0x65
enumerator PECI_CMD_WR_PCI_CFG1 = 0x66
enumerator PECI_CMD_RD_PKG_CFG0 = 0xA1
enumerator PECI_CMD_RD_PKG_CFG1 = 0xA2
enumerator PECI_CMD_WR_PKG_CFG0 = 0xA5
enumerator PECI_CMD_WR_PKG_CFG1 = 0xA6
enumerator PECI_CMD_RD_IAMSR0 = 0xB1
enumerator PECI_CMD_RD_IAMSR1 = 0xB2
enumerator PECI_CMD_WR_IAMSR0 = 0xB5
enumerator PECI_CMD_WR_IAMSR1 = 0xB6
enumerator PECI_CMD_RD_PCI_CFG_LOCAL0 = 0xE1
enumerator PECI_CMD_RD_PCI_CFG_LOCAL1 = 0xE2
enumerator PECI_CMD_WR_PCI_CFG_LOCAL0 = 0xE5
enumerator PECI_CMD_WR_PCI_CFG_LOCAL1 = 0xE6
enumerator PECI_CMD_GET_DIB = 0xF7

Functions

int peci_config(const struct device *dev, uint32_t bitrate)
  Configures the PECI interface.

Parameters
• `dev` – Pointer to the device structure for the driver instance.
• `bitrate` – the selected expressed in Kbps, command or when an event needs to be sent to the client application.

**Return values**
• 0 – If successful.
• Negative – errno code if failure.

```c
int peci_enable(const struct device *dev)
```
Enable PECI interface.

**Parameters**
• `dev` – Pointer to the device structure for the driver instance.

**Return values**
• 0 – If successful.
• Negative – errno code if failure.

```c
int peci_disable(const struct device *dev)
```
Disable PECI interface.

**Parameters**
• `dev` – Pointer to the device structure for the driver instance.

**Return values**
• 0 – If successful.
• Negative – errno code if failure.

```c
int peci_transfer(const struct device *dev, struct peci_msg *msg)
```
Performs a PECI transaction.

**Parameters**
• `dev` – Pointer to the device structure for the driver instance.
• `msg` – Structure representing a PECI transaction.

**Return values**
• 0 – If successful.
• Negative – errno code if failure.

```c
struct peci_buf
```
PECI buffer structure.

Note: Frame check sequence byte is added into rx buffer, need to allocate an additional byte for this in rx buffer.

**Param buf**
is a valid pointer on a data buffer, or NULL otherwise.

**Param len**
is the length of the data buffer expected to received without considering the frame check sequence byte.

```c
struct peci_msg
```
PECI transaction packet format.
Public Members

uint8_t addr
    Client address

enum peci_command_code cmd_code
    Command code

struct peci_buf tx_buffer
    Pointer to buffer of write data

struct peci_buf rx_buffer
    Pointer to buffer of read data

uint8_t flags
    PECI msg flags

7.3.30 Regulators

This subsystem provides control of voltage and current regulators. A common example is a GPIO that controls a transistor that supplies current to a device that is not always needed.

Conceptually regulators have two modes: off and on. A transition between modes may involve a time delay, so operations on regulators are inherently asynchronous. To maximize flexibility the On-Off Manager infrastructure is used in the generic API for the regulator subsystem. Nodes with a devicetree compatible of regulator-fixed are the most common flexible regulators.

In some cases the transitions are close enough to instantaneous that the asynchronous driver implementation is not needed, and the resource cost in RAM is not justified. Such a regulator still uses the asynchronous API, but may be implemented internally in a way that ensures the result of the operation is presented before the transition completes. Zephyr recognizes devicetree nodes with a compatible of regulator-fixed-sync as devices with synchronous transitions.

The vin-supply devicetree property is used to identify the regulator(s) that a devicetree node directly depends on. Within the driver for the node the regulator API is used to issue requests for power when the device is to be active, and release the power request when the device shuts down.

The simplest case where a regulator is needed is one where there is only one client. For those situations the cost of using even the optimized synchronous regulator device infrastructure is not justified, and the supply-gpios devicetree property should be used. There is no device interface to these regulators as they are entirely controlled within the driver for the corresponding node, e.g. a sensor.

API Reference

group regulator_interface
    Regulator Interface.

Functions
static inline int regulator_enable(const struct device *dev, struct onoff_client *cli)

Enable a regulator.

Reference-counted request that a regulator be turned on. This is an asynchronous operation; if successfully initiated the result will be communicated through the cli parameter.

A regulator is considered “on” when it has reached a stable/usable state.

**Function properties (list may not be complete)**

*isr-ok pre-kernel-ok*

**Parameters**

- `dev` – Regulator device instance
- `cli` – On-off client instance. This is used to notify the caller when the attempt to turn on the regulator has completed (can be `NULL`).

**Return values**

- `0` – If enable request has been successfully initiated.
- `-errno` – Negative errno in case of failure (can be from `onoff_request()` or individual regulator drivers).

static inline int regulator_disable(const struct device *dev)

Disable a regulator.

Release a regulator after a previous `regulator_enable()` completed successfully.

If the release removes the last dependency on the regulator it will begin a transition to its “off” state. There is currently no mechanism to notify when the regulator has completely turned off.

This must be invoked at most once for each successful `regulator_enable()`.

**Function properties (list may not be complete)**

*isr-ok*

**Parameters**

- `dev` – Regulator device instance.

**Return values**

- `0` – If enable request has been successfully initiated.
- `-errno` – Negative errno in case of failure (can be from `onoff_release()` or individual regulator drivers).

static inline int regulator_count_voltages(const struct device *dev)

Obtain the number of supported voltage levels.

Selectors are numbered starting at zero, and typically correspond to bitfields in hardware registers.

**Parameters**

- `dev` – Regulator device instance.

**Return values**

- `selectors` – Number of selectors, if successful.
- `-ENOSYS` – If function is not implemented.
- **errno** – In case of any other error.

```c
static inline int regulator_count_modes(const struct device *dev)
```

Obtain the number of supported modes.

**See also:**

`regulator_set_mode()`

**Parameters**

- `dev` – Regulator device instance.

**Returns**

Number of supported modes.

```c
static inline int32_t regulator_list_voltages(const struct device *dev, unsigned int selector)
```

Obtain supported voltages.

**Parameters**

- `dev` – Regulator device instance.
- `selector` – Voltage selector.

**Return values**

0 – If selector code can’t be used.

**Returns**

voltage Voltage level in microvolts.

```c
static inline int regulator_is_supported_voltage(const struct device *dev, int32_t min_uv, int32_t max_uv)
```

Check if a voltage range is supported.

**Parameters**

- `dev` – Regulator device instance.
- `min_uv` – Minimum voltage in microvolts.
- `max_uv` – Maximum voltage in microvolts.

**Return values**

- 0 – If successful.
- `-ENOSYS` – If function is not implemented.
- `errno` – In case of any other error.

```c
static inline int regulator_set_voltage(const struct device *dev, int32_t min_uv, int32_t max_uv)
```

Set output voltage.

**Note:** The output voltage will be configured to the closest supported output voltage. `regulator_get_voltage()` can be used to obtain the actual configured voltage.

**Parameters**

- `dev` – Regulator device instance.
- `min_uv` – Minimum acceptable voltage in microvolts.
- `max_uv` – Maximum acceptable voltage in microvolts.
Return values

- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

static inline int32_t regulator_get_voltage(const struct device *dev)
Obtain output voltage.

Parameters
- dev – Regulator device instance.

Returns
Voltage level in microvolts.

static inline int regulator_set_current_limit(const struct device *dev, int32_t min_ua, int32_t max_ua)
Set output current limit.

Parameters
- dev – Regulator device instance.
- min_ua – Minimum acceptable current limit in microamps.
- max_ua – Maximum acceptable current limit in microamps.

Return values
- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

static inline int32_t regulator_get_current_limit(const struct device *dev)
Get output current limit.

Parameters
- dev – Regulator device instance.

Return values
- current – Current limit in microamperes
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

static inline int regulator_set_mode(const struct device *dev, uint32_t mode)
Set mode.

Regulators can support multiple modes in order to permit different voltage configuration or better power savings. This API will apply a mode for the regulator.

Parameters
- dev – Regulator device instance.
- mode – Mode to select for this regulator. Only modes present in the regulator-allowed-modes devicetree property are permitted.

Return values
- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.
static inline int regulator_set_mode_voltage(const struct device *dev, uint32_t mode, int32_t min_uv, int32_t max_uv)

Set target voltage for a regulator mode.

**Note:** Mode does not need to be the active mode. The regulator can be switched to that mode with `regulator_set_mode()`.

**Parameters**
- `dev` – Regulator device instance.
- `mode` – Regulator mode.
- `min_uv` – Minimum acceptable voltage in microvolts.
- `max_uv` – Maximum acceptable voltage in microvolts.

**Return values**
- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

static inline int32_t regulator_get_mode_voltage(const struct device *dev, uint32_t mode)

Get target voltage for a regulator mode.

This API can be used to read voltages from a regulator mode other than the default. The given mode does not need to be active.

**Parameters**
- `dev` – Regulator device instance.
- `mode` – Regulator mode.

**Returns**
Voltage level in microvolts.

static inline int regulator_mode_disable(const struct device *dev, uint32_t mode)

Disable regulator for a given mode.

**Parameters**
- `dev` – Regulator device instance.
- `mode` – Regulator mode.

**Return values**
- 0 – If successful.
- -ENOSYS – If function is not implemented.
- -errno – In case of any other error.

static inline int regulator_mode_enable(const struct device *dev, uint32_t mode)

Enable regulator for a given mode.

**Parameters**
- `dev` – Regulator device instance.
- `mode` – Regulator mode.

**Return values**
- 0 – If successful.
- ENOSYS – If function is not implemented.
- errno – In case of any other error.

### 7.3.31 Reset Controller

#### Overview

Reset controllers are units that control the reset signals to multiple peripherals. The reset controller API allows peripheral drivers to request control over their reset input signals, including the ability to assert, deassert and toggle those signals. Also, the reset status of the reset input signal can be checked.

Mainly, the line_assert and line_deassert API functions are optional because in most cases we want to toggle the reset signals.

#### Configuration Options

Related configuration options:
- CONFIG_RESET

#### API Reference

**group** reset_controller_interface

Reset Controller Interface.

**Defines**

RESET_DT_SPEC_GET_BY_IDX(node_id, idx)

Static initializer for a reset_dt_spec.

This returns a static initializer for a reset_dt_spec structure given a devicetree node identifier, a property specifying a Reset Controller and an index.

Example devicetree fragment:

```plaintext
n: node {
    resets = <&reset 10>;
}
```

Example usage:

```plaintext
const struct reset_dt_spec spec = RESET_DT_SPEC_GET_BY_IDX(DT_NODELABEL(n), 0);
// Initializes 'spec' to:
// {
//   .dev = DEVICE_DT_GET(DT_NODELABEL(reset)),
//   .id = 10
// }
```

The 'reset' field must still be checked for readiness, e.g. using device_is_ready(). It is an error to use this macro unless the node exists, has the given property, and that property specifies a reset controller reset line id as shown above.

**Parameters**

- node_id – devicetree node identifier
• idx – logical index into “resets”

**Returns**
static initializer for a struct `reset_dt_spec` for the property

`RESET_DT_SPEC_GET(node_id)`
Equivalent to `RESET_DT_SPEC_GET_BY_IDX(node_id, 0)`.

**See also:**
`RESET_DT_SPEC_GET_BY_IDX()`

**Parameters**
• `node_id` – devicetree node identifier

**Returns**
static initializer for a struct `reset_dt_spec` for the property

`RESET_DT_SPEC_INST_GET_BY_IDX(inst, idx)`
Static initializer for a `reset_dt_spec` from a DT_DRV_COMPAT instance's Reset Controller property at an index.

**See also:**
`RESET_DT_SPEC_GET_BY_IDX()`

**Parameters**
• `inst` – DT_DRV_COMPAT instance number
  • `idx` – logical index into “resets”

**Returns**
static initializer for a struct `reset_dt_spec` for the property

`RESET_DT_SPEC_INST_GET(inst)`
Equivalent to `RESET_DT_SPEC_INST_GET_BY_IDX(inst, 0)`.

**See also:**
`RESET_DT_SPEC_INST_GET_BY_IDX()`

**Parameters**
• `inst` – DT_DRV_COMPAT instance number

**Functions**

```c
int reset_status(const struct device *dev, uint32_t id, uint8_t *status)
```
Get the reset status.

This function returns the reset status of the device.

**Parameters**
• `dev` – Reset controller device.
• id – Reset line.
• status – Where to write the reset status.

**Return values**
• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

```c
static inline int reset_status_dt(const struct reset_dt_spec *spec, uint8_t *status)
```

Get the reset status from a `reset_dt_spec`.

This is equivalent to:

```c
reset_status(spec->dev, spec->id, status);
```

**Parameters**
• spec – Reset controller specification from devicetree
• status – Where to write the reset status.

**Returns**
• a value from `reset_status()`

```c
int reset_line_assert(const struct device *dev, uint32_t id)
```

Put the device in reset state.

This function sets/clears the reset bits of the device, depending on the logic level (active-high/active-low).

**Parameters**
• dev – Reset controller device.
• id – Reset line.

**Return values**
• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

```c
static inline int reset_line_assert_dt(const struct reset_dt_spec *spec)
```

Assert the reset state from a `reset_dt_spec`.

This is equivalent to:

```c
reset_line_assert(spec->dev, spec->id);
```

**Parameters**
• spec – Reset controller specification from devicetree

**Returns**
• a value from `reset_line_assert()`

```c
int reset_line_deassert(const struct device *dev, uint32_t id)
```

Take out the device from reset state.

This function sets/clears the reset bits of the device, depending on the logic level (active-low/active-high).

**Parameters**
• dev – Reset controller device.
• id – Reset line.

**Return values**

• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

```c
static inline int reset_line_deassert_dt(const struct reset_dt_spec *spec)
```
Deassert the reset state from a `reset_dt_spec`.
This is equivalent to:

```c
reset_line_deassert(spec->dev, spec->id)
```

**Parameters**

• spec – Reset controller specification from devicetree

**Returns**

a value from `reset_line_deassert()`

```c
int reset_line_toggle(const struct device *dev, uint32_t id)
```
Reset the device.
This function performs reset for a device (assert + deassert).

**Parameters**

• dev – Reset controller device.
• id – Reset line.

**Return values**

• 0 – On success.
• -ENOSYS – If the functionality is not implemented by the driver.
• -errno – Other negative errno in case of failure.

```c
static inline int reset_line_toggle_dt(const struct reset_dt_spec *spec)
```
Reset the device from a `reset_dt_spec`.
This is equivalent to:

```c
reset_line_toggle(spec->dev, spec->id)
```

**Parameters**

• spec – Reset controller specification from devicetree

**Returns**

a value from `reset_line_toggle()`

```c
struct reset_dt_spec
#include <reset.h> Reset controller device configuration.
```

**Public Members**

```c
const struct device *dev
Reset controller device.
```
uint32_t id
Reset line.

7.3.32 RTC

Overview

This is a placeholder for API specific to real-time clocks. Currently all RTC peripherals are implemented
through Counter with device-specific API for counters with real-time support.

API Reference

group rtc_interface

RTC DS3231 Driver-Specific API.

Typedefs

typedef void (*maxim_ds3231_alarm_callback_handler_t)(const struct device *dev, uint8_t id,
uint32_t syncclock, void *user_data)
Signature for DS3231 alarm callbacks.
The alarm callback is invoked from the system work queue thread. At the point the callback is
invoked the corresponding alarm flags will have been cleared from the device status register.
The callback is permitted to invoke operations on the device.

Param dev
the device from which the callback originated

Param id
the alarm id

Param syncclock
the value from maxim_ds3231_read_syncclock() at the time the alarm interrupt
was processed.

Param user_data
the corresponding parameter from maxim_ds3231_alarm::user_data.

typedef void (*maxim_ds3231_notify_callback)(const struct device *dev, struct sys_notify
*notify, int res)
Signature used to notify a user of the DS3231 that an asynchronous operation has completed.
Functions compatible with this type are subject to all the constraints of
sys_notify_generic_callback.

Param dev
the DS3231 device pointer

Param notify
the notification structure provided in the call

Param res
the result of the operation.
Functions

```c
static inline uint32_t maxim_ds3231_read_syncclock(const struct device *dev)
    Read the local synchronization clock.
    Synchronization aligns the DS3231 real-time clock with a stable monotonic local clock which
    should have a frequency between 1 kHz and 1 MHz and be itself synchronized with the primary
    system time clock. The accuracy of the alignment and the maximum time between
    synchronization updates is affected by the resolution of this clock.
    On some systems the hardware clock from k_cycles_get_32() is suitable, but on others
    that clock advances too quickly. The frequency of the target-specific clock is provided by
    maxim_ds3231_syncclock_frequency().
    At this time the value is captured from k_uptime_get_32(); future kernel extensions may
    make a higher-resolution clock available.
```

**Note:** This function is *isr-ok*.

### Parameters
- `dev` – the DS3231 device pointer

### Returns
- the current value of the synchronization clock.

```c
static inline uint32_t maxim_ds3231_syncclock_frequency(const struct device *dev)
    Get the frequency of the synchronization clock.
    Provides the frequency of the clock used in maxim_ds3231_read_syncclock().
```

### Parameters
- `dev` – the DS3231 device pointer

### Returns
- the frequency of the selected synchronization clock.

```c
int maxim_ds3231_ctrl_update(const struct device *dev, uint8_t set_bits, uint8_t clear_bits)
    Set and clear specific bits in the control register.
```

**Note:** This function assumes the device register cache is valid. It will not read the register
value, and it will write to the device only if the value changes as a result of applying the set
and clear changes.

**Note:** Unlike maxim_ds3231_stat_update() the return value from this function indicates the
register value after changes were made. That return value is cached for use in subsequent
operations.

**Note:** This function is *supervisor*.

### Returns
- the non-negative updated value of the register, or a negative error code from an
  I2C transaction.
int maxim_ds3231_stat_update(const struct device *dev, uint8_t set_bits, uint8_t clear_bits)

Read the ctrl_stat register then set and clear bits in it.

The content of the ctrl_stat register will be read, then the set and clear bits applied and the result written back to the device (regardless of whether there appears to be a change in value). OSF, A1F, and A2F will be written with 1s if the corresponding bits do not appear in either set_bits or clear_bits. This ensures that if any flag becomes set between the read and the write that indicator will not be cleared.

**Note:** Unlike `maxim_ds3231_ctrl_update()` the return value from this function indicates the register value before any changes were made.

**Note:** This function is `supervisor`.

**Parameters**
- `dev` – the DS3231 device pointer
- `set_bits` – bits to be set when writing back. Setting bits other than MAXIM_DS3231_REG_STAT_EN32kHz will have no effect.
- `clear_bits` – bits to be cleared when writing back. Include the bits for the status flags you want to clear.

**Returns**
the non-negative register value as originally read (disregarding the effect of clears and sets), or a negative error code from an I2C transaction.

int maxim_ds3231_get_alarm(const struct device *dev, uint8_t id, struct maxim_ds3231_alarm *cfg)

Read a DS3231 alarm configuration.

The alarm configuration data is read from the device and reconstructed into the output parameter.

**Note:** This function is `supervisor`.

**Parameters**
- `dev` – the DS3231 device pointer.
- `id` – the alarm index, which must be 0 (for the 1 s resolution alarm) or 1 (for the 1 min resolution alarm).
- `cfg` – a pointer to a structure into which the configured alarm data will be stored.

**Returns**
a non-negative value indicating successful conversion, or a negative error code from an I2C transaction or invalid parameter.

int maxim_ds3231_set_alarm(const struct device *dev, uint8_t id, const struct maxim_ds3231_alarm *cfg)

Configure a DS3231 alarm.

The alarm configuration is validated and stored into the device.

To cancel an alarm use `counter_cancel_channel_alarm()`.
Note: This function is *supervisor*.

**Parameters**

- `dev` – the DS3231 device pointer.
- `id` – 0 Analog to counter index. ALARM1 is 0 and has 1 s resolution, ALARM2 is 1 and has 1 minute resolution.
- `cfg` – a pointer to the desired alarm configuration. Both alarms are configured if only one is to change the application must supply the existing configuration for the other.

**Returns**

a non-negative value on success, or a negative error code from an I2C transaction or an invalid parameter.

```c
int maxim_ds3231_synchronize(const struct device *dev, struct sys_notify *notify)
```

Synchronize the RTC against the local clock.

The RTC advances one tick per second with no access to sub-second precision. Synchronizing clocks at sub-second resolution requires enabling a 1pps signal then capturing the system clocks in a GPIO callback. This function provides that operation.

Synchronization is performed in asynchronously, and may take as long as 1 s to complete; notification of completion is provided through the `notify` parameter.

Applications should use `maxim_ds3231_get_syncpoint()` to retrieve the synchronization data collected by this operation.

Note: This function is *supervisor*.

**Parameters**

- `dev` – the DS3231 device pointer.
- `notify` – pointer to the object used to specify asynchronous function behavior and store completion information.

**Return values**

- `non-negative` – on success
- `-EBUSY` – if a synchronization or set is currently in progress
- `-EINVAL` – if `notify` is not provided
- `-ENOTSUP` – if the required interrupt is not configured

```c
int maxim_ds3231_req_syncpoint(const struct device *dev, struct k_poll_signal *signal)
```

Request to update the synchronization point.

This is a variant of `maxim_ds3231_synchronize()` for use from user threads.

**Parameters**

- `dev` – the DS3231 device pointer.
- `signal` – pointer to a valid and ready-to-be-signalled `k poll_signal`. May be NULL to request a synchronization point be collected without notifying when it has been updated.

**Return values**
• non-negative – on success
• -EBUSY – if a synchronization or set is currently in progress
• -ENOTSUP – if the required interrupt is not configured

```c
int maxim_ds3231_get_syncpoint(const struct device *dev, struct maxim_ds3231_syncpoint *syncpoint)
```

Retrieve the most recent synchronization point.

This function returns the synchronization data last captured using `maxim_ds3231_synchronize()`.

**Parameters**

- `dev` – the DS3231 device pointer.
- `syncpoint` – where to store the synchronization data.

**Return values**

- non-negative – on success
- -ENOENT – if no syncpoint has been captured

```c
int maxim_ds3231_set(const struct device *dev, const struct maxim_ds3231_syncpoint *syncpoint, struct sys_notify *notify)
```

Set the RTC to a time consistent with the provided synchronization.

The RTC advances one tick per second with no access to sub-second precision, and setting the clock resets the internal countdown chain. This function implements the magic necessary to set the clock while retaining as much sub-second accuracy as possible. It requires a synchronization point that pairs sub-second resolution civil time with a local synchronization clock captured at the same instant. The set operation may take as long as 1 second to complete; notification of completion is provided through the `notify` parameter.

**Note:** This function is *supervisor*.

**Parameters**

- `dev` – the DS3231 device pointer.
- `syncpoint` – the structure providing the synchronization point.
- `notify` – pointer to the object used to specify asynchronous function behavior and store completion information.

**Return values**

- non-negative – on success
- EINVAL – if syncpoint or notify are null
- ENOTSUP – if the required interrupt signal is not configured
- EBUSY – if a synchronization or set is currently in progress

```c
int maxim_ds3231_check_alarms(const struct device *dev)
```

Check for and clear flags indicating that an alarm has fired.

Returns a mask indicating alarms that are marked as having fired, and clears from stat the flags that it found set. Alarms that have been configured with a callback are not represented in the return value.

This API may be used when a persistent alarm has been programmed.

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Note: This function is supervisor.

Parameters
• dev – the DS3231 device pointer.

Returns
a non-negative value that may have MAXIM_DS3231_ALARM1 and/or MAXIM_DS3231_ALARM2 set, or a negative error code.

struct maxim_ds3231_alarm
#include <maxim_ds3231.h> Information defining the alarm configuration.
DS3231 alarms can be set to fire at specific times or at the rollover of minute, hour, day, or day of week.
When an alarm is configured with a handler an interrupt will be generated and the handler called from the system work queue.
When an alarm is configured without a handler, or a persisted alarm is present, alarms can be read using maxim_ds3231_check_alarms() .

Public Members
time_t time
Time specification for an RTC alarm.
Though specified as a UNIX time, the alarm parameters are determined by converting to civil time and interpreting the component hours, minutes, seconds, day-of-week, and day-of-month fields, mediated by the corresponding flags.
The year and month are ignored, but be aware that gmtime() determines day-of-week based on calendar date. Decoded alarm times will fall within 1978-01 since 1978-01-01 (first of month) was a Sunday (first of week).

maxim_ds3231_alarm_callback_handler_t handler
Handler to be invoked when alarms are signalled.
If this is null the alarm will not be triggered by the INTn/SQW GPIO. This is a “persisted” alarm from its role in using the DS3231 to trigger a wake from deep sleep. The application should use maxim_ds3231_check_alarms() to determine whether such an alarm has been triggered.
If this is not null the driver will monitor the ISW GPIO for alarm signals and will invoke the handler with a parameter carrying the value returned by maxim_ds3231_check_alarms(). The corresponding status flags will be cleared in the device before the handler is invoked.
The handler will be invoked from the system work queue.

void *user_data
User-provided pointer passed to alarm callback.

uint8_t flags
Flags controlling configuration of the alarm alarm.
See MAXIM_DS3231_ALARM_FLAGS_IGNSE and related constants.
Note that as described the alarm mask fields require that if a unit is not ignored, higher-precision units must also not be ignored. For example, if match on hours is enabled, match on minutes and seconds must also be enabled. Failure to comply with this requirement will cause `maxim_ds3231_set_alarm()` to return an error, leaving the alarm configuration unchanged.

```c
struct maxim_ds3231_syncpoint
#include <maxim_ds3231.h>  // Register the RTC clock against system clocks.

This captures the same instant in both the RTC time scale and a stable system clock scale, allowing conversion between those scales.

Public Members

struct timespec rtc
   // Time from the DS3231.
   // This maybe in UTC, TAI, or local offset depending on how the RTC is maintained.

    uint32_t sync_clock
   // Value of a local clock at the same instant as rtc.
   // This is captured from a stable monotonic system clock running at between 1 kHz and 1 MHz, allowing for microsecond to millisecond accuracy in synchronization.

7.3.33 SDHC

The SDHC api offers a generic interface for interacting with an SD host controller device. It is used by the SD subsystem, and is not intended to be directly used by the application.

Basic Operation

SD Host Controller An SD host controller is a device capable of sending SD commands to an attached SD card. These commands can be sent using the native SD protocol, or over SPI. the SDHC api is designed to provide a generic way to send commands to and interact with attached SD devices.

Requests The core of the SDHC api is the `sdhc_request()` api. Requests contain a `sdhc_command` command structure, and an optional `sdhc_data` data structure. The caller may check the return code, or the response field of the SD command structure to determine if the SDHC request succeeded. The data structure allows the caller to specify a number of blocks to transfer, and a buffer location to read or write them from. Whether the provided buffer is used for sending or reading data depends on the command opcode provided.

Host Controller I/O The `sdhc_set_i0()` api allows the user to change I/O settings of the SD host controller, such as clock frequency, I/O voltage, and card power. Not all controllers will support applying all I/O settings. For example, SPI mode controllers typically cannot toggle power to the SD card.

Related configuration options:

- `CONFIG_SDHC`
API Reference

&enspace;group sdhc_interface
&enspace;&enspace;SDHC interface.

SD command timeouts

SDHC_TIMEOUT_FOREVER

Defines

SDHC_NATIVE_RESPONSE_MASK

SD_HC_SPI_RESPONSE_TYPE_MASK

 Enums

enum sdhc_bus_mode
&enspace;SD bus mode.
Most controllers will use push/pull, including spi, but SDHC controllers that implement SD host specification can support open drain mode
Values:

enumerator SDHC_BUSMODE_OPENDRAIN = 1

enumerator SDHC_BUSMODE_PUSHPULL = 2

enum sdhc_power
&enspace;SD host controller power.
Many host controllers can control power to attached SD cards. This enum allows applications to request the host controller power off the SD card.
Values:

enumerator SDHC_POWER_OFF = 1

enumerator SDHC_POWER_ON = 2

enum sdhc_bus_width
&enspace;SD host controller bus width.
Only relevant in SD mode, SPI does not support bus width. UHS cards will use 4 bit data bus, all cards start in 1 bit mode
Values:

enumerator SDHC_BUS_WIDTH1BIT = 1U
enumerator SD_HC_BUS_WIDTH4BIT = 4U
enumerator SD_HC_BUS_WIDTH8BIT = 8U

enum sdhc_timing_mode
SD host controller timing mode.
Used by SD host controller to determine the timing of the cards attached to the bus. Cards
start with legacy timing, but UHS-II cards can go up to SDR104.
Values:
enumerator SD_HC_TIMING_LEGACY = 1U
  Legacy 3.3V Mode
enumerator SD_HC_TIMING_HS = 2U
  Legacy High speed mode (3.3V)
enumerator SD_HC_TIMING_SDR12 = 3U
  Identification mode & SDR12
enumerator SD_HC_TIMING_SDR25 = 4U
  High speed mode & SDR25
enumerator SD_HC_TIMING_SDR50 = 5U
  SDR49 mode
enumerator SD_HC_TIMING_SDR104 = 6U
  SDR104 mode
enumerator SD_HC_TIMING_DDR50 = 7U
  DDR50 mode
enumerator SD_HC_TIMING_DDR52 = 8U
  DDR52 mode
enumerator SD_HC_TIMING_HS200 = 9U
  HS200 mode
enumerator SD_HC_TIMING_HS400 = 10U
  HS400 mode

enum sd_voltage
SD voltage.
UHS cards can run with 1.8V signalling for improved power consumption. Legacy cards may
support 3.0V signalling, and all cards start at 3.3V. Only relevant for SD controllers, not SPI
ones.
Values:
enumerator SD_VOL_3_3_V = 1U
  card operation voltage around 3.3v

enumerator SD_VOL_3_0_V = 2U
  card operation voltage around 3.0v

enumerator SD_VOL_1_8_V = 3U
  card operation voltage around 1.8v

enumerator SD_VOL_1_2_V = 4U
  card operation voltage around 1.2v

Functions

int sdhc_hw_reset(const struct device *dev)
  reset SDHC controller state
  Used when the SDHC has encountered an error. Resetting the SDHC controller should clear
  all errors on the SDHC, but does not necessarily reset I/O settings to boot (this can be done
  with sdhc_set_io)

Parameters
  • dev – SD host controller device

Return values
  • 0 – reset succeeded
  • -ETIMEDOUT – controller reset timed out
  • -EIO – reset failed

int sdhc_request(const struct device *dev, struct sdhc_command *cmd, struct sdhc_data *data)
  Send command to SDHC.
  Sends a command to the SD host controller, which will send this command to attached SD
  cards.

Parameters
  • dev – SDHC device
  • cmd – SDHC command
  • data – SDHC data. Leave NULL to send SD command without data.

Return values
  • 0 – command was sent successfully
  • -ETIMEDOUT – command timed out while sending
  • -ENOTSUP – host controller does not support command
  • -EIO – I/O error

int sdhc_set_io(const struct device *dev, struct sdhc_io *io)
  set I/O properties of SDHC
  I/O properties should be reconfigured when the card has been sent a command to change its
  own SD settings. This function can also be used to toggle power to the SD card.

Parameters
• `dev` – SDHC device
• `io` – I/O properties

**Returns**

0 I/O was configured correctly

**Returns**

- ENOTSUP controller does not support these I/O settings
- EIO controller could not configure I/O settings

```c
int sdhc_card_present(const struct device *dev)
```

check for SDHC card presence

Checks if card is present on the SD bus. Note that if a controller requires cards be powered up to detect presence, it should do so in this function.

**Parameters**

• `dev` – SDHC device

**Return values**

• 1 – card is present
• 0 – card is not present
• -EIO – I/O error

```c
int sdhc_execute_tuning(const struct device *dev)
```

run SDHC tuning

SD cards require signal tuning for UHS modes SDR104 and SDR50. This function allows an application to request the SD host controller to tune the card.

**Parameters**

• `dev` – SDHC device

**Return values**

• 0 – tuning succeeded, card is ready for commands
• -ETIMEDOUT – tuning failed after timeout
• -ENOTSUP – controller does not support tuning
• -EIO – I/O error while tuning

```c
int sdhc_card_busy(const struct device *dev)
```

check if SD card is busy

This check should generally be implemented as checking the line level of the DAT[0:3] lines of the SD bus. No SD commands need to be sent, the controller simply needs to report the status of the SD bus.

**Parameters**

• `dev` – SDHC device

**Return values**

• 0 – card is not busy
• 1 – card is busy
• -EIO – I/O error
int sdhc_get_host_props(const struct device *dev, struct sdhc_host_props *props)

Get SD host controller properties.

Gets host properties from the host controller. Host controller should initialize all values in the
sdhc_host_props structure provided.

Parameters

• dev – SDHC device
• props – property structure to be filled by sdhc driver

Return values

• 0 – function succeeded.
• -ENOTSUP – host controller does not support this call

struct sdhc_command

#include <sdhc.h> SD host controller command structure.

This command structure is used to send command requests to an SD host controller, which
will be sent to SD devices.

Public Members

uint32_t opcode

SD Host specification CMD index

uint32_t arg

SD host specification argument

uint32_t response[4]

SD card response field

uint32_t response_type

Expected SD response type

unsigned int retries

Max number of retries

int timeout_ms

Command timeout in milliseconds

struct sdhc_data

#include <sdhc.h> SD host controller data structure.

This command structure is used to send data transfer requests to an SD host controller, which
will be sent to SD devices.

Public Members

unsigned int block_addr

Block to start read from
unsigned int block_size
   Block size

unsigned int blocks
   Number of blocks

unsigned int bytes_xfered
   populated with number of bytes sent by SDHC

void *data
   Data to transfer or receive

int timeout_ms
   data timeout in milliseconds

struct sdhc_host_caps
   #include <sdhc.h>  SD host controller capabilities.
   SD host controller capability flags. These flags should be set by the SDHC driver, using the
   sdhc_get_host_props api.

struct sdhc_io
   #include <sdhc.h>  SD host controller I/O control structure.
   Controls I/O settings for the SDHC. Note that only a subset of these settings apply to host
   controllers in SPI mode. Populate this struct, then call sdhc_set_io to apply I/O settings

Public Members

enum sdhc_clock_speed clock
   Clock rate

enum sdhc_bus_mode bus_mode
   command output mode

enum sdhc_power power_mode
   SD power supply mode

enum sdhc_bus_width bus_width
   SD bus width

enum sdhc_timing_mode timing
   SD bus timing

enum sd_driver_type driver_type
   SD driver type

enum sd_voltage signal_voltage
   IO signalling voltage (usually 1.8 or 3.3V)
struct sdhc_host_props
#include <sdhc.h> SD host controller properties.
Populated by the host controller using sdhc_get_host_props api.

Public Members

unsigned int f_max
Max bus frequency

unsigned int f_min
Min bus frequency

unsigned int power_delay
Delay to allow SD to power up or down (in ms)

struct sdhc_host_caps host_caps
Host capability bitfield

uint32_t max_current_330
Max current (in mA) at 3.3V

uint32_t max_current_300
Max current (in mA) at 3.0V

uint32_t max_current_180
Max current (in mA) at 1.8V

bool is_spi
Is the host using SPI mode

struct sdhc_driver_api
#include <sdhc.h>

7.3.34 Sensors

The sensor subsystem exposes an API to uniformly access sensor devices. Common operations are: reading data and executing code when specific conditions are met.

Basic Operation

Channels Fundamentally, a channel is a quantity that a sensor device can measure.

Sensors can have multiple channels, either to represent different axes of the same physical property (e.g. acceleration); or because they can measure different properties altogether (ambient temperature, pressure and humidity). Complex sensors cover both cases, so a single device can expose three acceleration channels and a temperature one.

It is imperative that all sensors that support a given channel express results in the same unit of measurement. Consult the API Reference for all supported channels, along with their description and units of measurement:
Values  Sensor devices return results as `sensor_value`. This representation avoids use of floating point values as they may not be supported on certain setups.

Fetching Values  Getting a reading from a sensor requires two operations. First, an application instructs the driver to fetch a sample of all its channels. Then, individual channels may be read. In the case of channels with multiple axes, they can be read in a single operation by supplying the corresponding `_XYZ` channel type and a buffer of 3 `sensor_value` objects. This approach ensures consistency of channels between reads and efficiency of communication by issuing a single transaction on the underlying bus.

Below is an example illustrating the usage of the BME280 sensor, which measures ambient temperature and atmospheric pressure. Note that `sensor_sample_fetch()` is only called once, as it reads and compensates data for both channels.

```c
/*
 * Get a device structure from a devicetree node with compatible
 * "bosch,bme280". (If there are multiple, just pick one.) */
static const struct device *get_bme280_device(void)
{
    const struct device *const dev = DEVICE_DT_GET_ANY(bosch_bme280);

    if (dev == NULL) {
        /* No such node, or the node does not have status "okay". */
        printk("Error: no device found.
");
        return NULL;
    }

    if (!device_is_ready(dev)) {
        printk("Error: Device \"%s\" is not ready; "
            "check the driver initialization logs for errors.\n",
            dev->name);
        return NULL;
    }

    printk("Found device \"%s\", getting sensor data\n", dev->name);
    return dev;
}

void main(void)
{
    const struct device *dev = get_bme280_device();

    if (dev == NULL) {
        return;
    }

    while (1) {
        struct sensor_value temp, press, humidity;

        sensor_sample_fetch(dev);
        sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
        sensor_channel_get(dev, SENSOR_CHAN_PRESS, &press);
        sensor_channel_get(dev, SENSOR_CHAN_HUMIDITY, &humidity);

        printk("temp: %d.%06d; press: %d.%06d; humidity: %d.%06d\n",
            temp.val1, temp.val2, press.val1, press.val2,
            humidity.val1, humidity.val2,
            (continues on next page)
```
humidity.val1, humidity.val2);

        k_sleep(K_MSEC(1000));
    }
}

Configuration and Attributes

Setting the communication bus and address is considered the most basic configuration for sensor devices. This setting is done at compile time, via the configuration menu. If the sensor supports interrupts, the interrupt lines and triggering parameters described below are also configured at compile time.

Alongside these communication parameters, sensor chips typically expose multiple parameters that control the accuracy and frequency of measurement. In compliance with Zephyr’s design goals, most of these values are statically configured at compile time.

However, certain parameters could require runtime configuration, for example, threshold values for interrupts. These values are configured via attributes. The example in the following section showcases a sensor with an interrupt line that is triggered when the temperature crosses a threshold. The threshold is configured at runtime using an attribute.

Triggers

Triggers in Zephyr refer to the interrupt lines of the sensor chips. Many sensor chips support one or more triggers. Some examples of triggers include: new data is ready for reading, a channel value has crossed a threshold, or the device has sensed motion.

To configure a trigger, an application needs to supply a sensor_trigger and a handler function. The structure contains the trigger type and the channel on which the trigger must be configured.

Because most sensors are connected via SPI or I2C buses, it is not possible to communicate with them from the interrupt execution context. The execution of the trigger handler is deferred to a thread, so that data fetching operations are possible. A driver can spawn its own thread to fetch data, thus ensuring minimum latency. Alternatively, multiple sensor drivers can share a system-wide thread. The shared thread approach increases the latency of handling interrupts but uses less memory. You can configure which approach to follow for each driver. Most drivers can entirely disable triggers resulting in a smaller footprint.

The following example contains a trigger fired whenever temperature crosses the 26 degree Celsius threshold. It also samples the temperature every second. A real application would ideally disable periodic sampling in the interest of saving power. Since the application has direct access to the kernel config symbols, no trigger is registered when triggering was disabled by the driver’s configuration.
now /= MSEC_PER_SEC;
s = now % 60U;
now /= 60U;
min = now % 60U;
now /= 60U;
h = now;

snprintf(buf, sizeof(buf), "%u:%02u:%02u.%03u",
h, min, s, ms);
return buf;
}

#endif CONFIG_MCP9808_TRIGGER

static struct sensor_trigger trig;

static int set_window(const struct device *dev,
    const struct sensor_value *temp)
{
    const int temp_ucel = temp->val1 * UCEL_PER_CEL + temp->val2;
    const int low_ucel = temp_ucel - TEMP_WINDOW_HALF_UCEL;
    const int high_ucel = temp_ucel + TEMP_WINDOW_HALF_UCEL;

    struct sensor_value val = {
        .val1 = low_ucel / UCEL_PER_CEL,
        .val2 = low_ucel % UCEL_PER_CEL,
    };
    int rc = sensor_attr_set(dev, SENSOR_CHAN_AMBIENT_TEMP,
        SENSOR_ATTR_LOWER_THRESH, &val);
    if (rc == 0) {
        val.val1 = high_ucel / UCEL_PER_CEL,
        val.val2 = high_ucel % UCEL_PER_CEL,
        rc = sensor_attr_set(dev, SENSOR_CHAN_AMBIENT_TEMP,
            SENSOR_ATTR_UPPER_THRESH, &val);
    }

    if (rc == 0) {
        printf("Alert on temp outside [%d, %d] milli-Celsius\n",
            low_ucel / UCEL_PER_MCEL,
            high_ucel / UCEL_PER_MCEL);
    }

    return rc;
}

static inline int set_window_ucel(const struct device *dev,
    int temp_ucel)
{
    struct sensor_value val = {
        .val1 = temp_ucel / UCEL_PER_CEL,
        .val2 = temp_ucel % UCEL_PER_CEL,
    };

    return set_window(dev, &val);
}


```c
static void trigger_handler(const struct device *dev,
    const struct sensor_trigger *trig)
{
    struct sensor_value temp;
    static size_t cnt;
    int rc;

    ++cnt;
    rc = sensor_sample_fetch(dev);
    if (rc != 0) {
        printf("sensor_sample_fetch error: %d\n", rc);
        return;
    }

    rc = sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
    if (rc != 0) {
        printf("sensor_channel_get error: %d\n", rc);
        return;
    }

    printf("trigger fired %u, temp %g deg C\n", cnt,
        sensor_value_to_double(&temp));
    set_window(dev, &temp);
}
#endif

void main(void)
{
    const struct device *const dev = DEVICE_DT_GET_ANY(microchip_mcp9808);
    int rc;

    if (dev == NULL) {
        printf("Device not found.\n");
        return;
    }
    if (!device_is_ready(dev)) {
        printf("Device \%s is not ready.\n", dev->name);
        return;
    }

#ifdef CONFIG_MCP9808_TRIGGER
    rc = set_window_ucel(dev, TEMP_INITIAL_CEL * UCEL_PER_CEL);
    if (rc == 0) {
        trig.type = SENSOR_TRIG_THRESHOLD;
        trig.chan = SENSOR_CHAN_AMBIENT_TEMP;
        rc = sensor_trigger_set(dev, &trig, trigger_handler);
    }
    if (rc != 0) {
        printf("Trigger set failed: %d\n", rc);
        return;
    }
    printk("Trigger set got %d\n", rc);
#endif

    while (1) {
        struct sensor_value temp;
```

(continues on next page)
rc = sensor_sample_fetch(dev);
if (rc != 0) {
    printf("sensor_sample_fetch error: %d\n", rc);
    break;
}

rc = sensor_channel_get(dev, SENSOR_CHAN_AMBIENT_TEMP, &temp);
if (rc != 0) {
    printf("sensor_channel_get error: %d\n", rc);
    break;
}

printf("%s: %g C\n", now_str(),
     sensor_value_to_double(&temp));
k_sleep(K_SECONDS(2));
}

API Reference

group sensor_interface

Sensor Interface.

Defines

SENSOR_G
The value of gravitational constant in micro m/s^2.

SENSOR_PI
The value of constant PI in micros.

SENSOR_INFO_DEFINE(name, ...)
SENSOR_INFO_DT_DEFINE(node_id)
SENSOR_DEVICE_DT_DEFINE(node_id, init_fn, pm_device, data_ptr, cfg_ptr, level, prio, api_ptr, ...)
Like DEVICE_DT_DEFINE() with sensor specifics.

Defines a device which implements the sensor API. May define an element in the sensor info iterable section used to enumerate all sensor devices.

Parameters

• node_id – The devicetree node identifier.
• init_fn – Name of the init function of the driver.
• pm_device – PM device resources reference – (NULL if device does not use PM).
• data_ptr – Pointer to the device’s private data.
• cfg_ptr – The address to the structure containing the configuration information for this instance of the driver.
• level – The initialization level. See SYS_INIT() for details.
• **prio** – Priority within the selected initialization level. See SYS_INIT() for details.

• **api_ptr** – Provides an initial pointer to the API function struct used by the driver. Can be NULL.

```c
SENSOR_DEVICE_DT_INST_DEFINE(inst, ...
```

Like `SENSOR_DEVICE_DT_DEFINE()` for an instance of a DT_DRV_COMPAT compatible.

**Parameters**

• **inst** – instance number. This is replaced by DT_DRV_COMPAT(inst) in the call to `SENSOR_DEVICE_DT_DEFINE()`.

• **...** – other parameters as expected by `SENSOR_DEVICE_DT_DEFINE()`.

**Typedefs**

typedef void (*sensor_trigger_handler_t)(const struct device *dev, const struct sensor_trigger *trigger)

Callback API upon firing of a trigger.

**Param dev**

Pointer to the sensor device

**Param trigger**

The trigger

typedef int (*sensor_attr_set_t)(const struct device *dev, enum sensor_channel chan, enum sensor_attribute attr, const struct sensor_value *val)

Callback API upon setting a sensor’s attributes.

See `sensor_attr_set()` for argument description

typedef int (*sensor_attr_get_t)(const struct device *dev, enum sensor_channel chan, enum sensor_attribute attr, struct sensor_value *val)

Callback API upon getting a sensor’s attributes.

See `sensor_attr_get()` for argument description

typedef int (*sensor_trigger_set_t)(const struct device *dev, const struct sensor_trigger *trig, sensor_trigger_handler_t handler)

Callback API for setting a sensor’s trigger and handler.

See `sensor_trigger_set()` for argument description

typedef int (*sensor_sample_fetch_t)(const struct device *dev, enum sensor_channel chan)

Callback API for fetching data from a sensor.

See `sensor_sample_fetch()` for argument description

typedef int (*sensor_channel_get_t)(const struct device *dev, enum sensor_channel chan, struct sensor_value *val)

Callback API for getting a reading from a sensor.

See `sensor_channel_get()` for argument description
Enums

```c
enum sensor_channel
{
    SENSOR_CHAN_ACCEL_X
        Acceleration on the X axis, in m/s^2.
    SENSOR_CHAN_ACCEL_Y
        Acceleration on the Y axis, in m/s^2.
    SENSOR_CHAN_ACCEL_Z
        Acceleration on the Z axis, in m/s^2.
    SENSOR_CHAN_ACCEL_XYZ
        Acceleration on the X, Y and Z axes.
    SENSOR_CHAN_GYRO_X
        Angular velocity around the X axis, in radians/s.
    SENSOR_CHAN_GYRO_Y
        Angular velocity around the Y axis, in radians/s.
    SENSOR_CHAN_GYRO_Z
        Angular velocity around the Z axis, in radians/s.
    SENSOR_CHAN_GYRO_XYZ
        Angular velocity around the X, Y and Z axes.
    SENSOR_CHAN_MAGN_X
        Magnetic field on the X axis, in Gauss.
    SENSOR_CHAN_MAGN_Y
        Magnetic field on the Y axis, in Gauss.
    SENSOR_CHAN_MAGN_Z
        Magnetic field on the Z axis, in Gauss.
    SENSOR_CHAN_MAGN_XYZ
        Magnetic field on the X, Y and Z axes.
    SENSOR_CHAN_DIE_TEMP
        Device die temperature in degrees Celsius.
    SENSOR_CHAN_AMBIENT_TEMP
        Ambient temperature in degrees Celsius.
};
```
enumerator SENSOR_CHAN_PRESS
    Pressure in kilopascal.

enumerator SENSOR_CHAN_PROX
    Proximity. Adimensional. A value of 1 indicates that an object is close.

enumerator SENSOR_CHAN_HUMIDITY
    Humidity, in percent.

enumerator SENSOR_CHAN_LIGHT
    Illuminance in visible spectrum, in lux.

enumerator SENSOR_CHAN_IR
    Illuminance in infra-red spectrum, in lux.

enumerator SENSOR_CHAN_RED
    Illuminance in red spectrum, in lux.

enumerator SENSOR_CHAN_GREEN
    Illuminance in green spectrum, in lux.

enumerator SENSOR_CHAN_BLUE
    Illuminance in blue spectrum, in lux.

enumerator SENSOR_CHAN_ALTITUDE
    Altitude, in meters

enumerator SENSOR_CHAN_PM_1_0
    1.0 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_PM_2_5
    2.5 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_PM_10
    10 micro-meters Particulate Matter, in ug/m^3

enumerator SENSOR_CHAN_DISTANCE
    Distance. From sensor to target, in meters

enumerator SENSOR_CHAN_CO2
    CO2 level, in parts per million (ppm)

enumerator SENSOR_CHAN_VOC
    VOC level, in parts per billion (ppb)

enumerator SENSOR_CHAN_GAS_RES
    Gas sensor resistance in ohms.
enumerator SENSOR_CHAN_VOLTAGE
   Voltage, in volts

denumerator SENSOR_CHAN_CURRENT
   Current, in amps

denumerator SENSOR_CHAN_POWER
   Power in watts

denumerator SENSOR_CHAN_RESISTANCE
   Resistance, in Ohm

denumerator SENSOR_CHAN_ROTATION
   Angular rotation, in degrees

denumerator SENSOR_CHAN_POS_DX
   Position change on the X axis, in points.

denumerator SENSOR_CHAN_POS_DY
   Position change on the Y axis, in points.

denumerator SENSOR_CHAN_POS_DZ
   Position change on the Z axis, in points.

denumerator SENSOR_CHAN_RPM
   Revolutions per minute, in RPM.

denumerator SENSOR_CHAN_GAUGE_VOLTAGE
   Voltage, in volts

enumerator SENSOR_CHAN_GAUGE_AVG_CURRENT
   Average current, in amps

enumerator SENSOR_CHAN_GAUGE_STDBY_CURRENT
   Standby current, in amps

enumerator SENSOR_CHAN_GAUGE_MAX_LOAD_CURRENT
   Max load current, in amps

enumerator SENSOR_CHAN_GAUGE_TEMP
   Gauge temperature

enumerator SENSOR_CHAN_GAUGE_STATE_OF_CHARGE
   State of charge measurement in %

enumerator SENSOR_CHAN_GAUGE_FULL_CHARGE_CAPACITY
   Full Charge Capacity in mAh
enumerator SENSOR_CHAN_GAUGE_REMAINING_CHARGE_CAPACITY
   Remaining Charge Capacity in mAh
enumerator SENSOR_CHAN_GAUGE_NOM_AVAIL_CAPACITY
   Nominal Available Capacity in mAh
enumerator SENSOR_CHAN_GAUGE_FULL_AVAIL_CAPACITY
   Full Available Capacity in mAh
enumerator SENSOR_CHAN_GAUGE_AVG_POWER
   Average power in mW
enumerator SENSOR_CHAN_GAUGE_STATE_OF_HEALTH
   State of health measurement in %
enumerator SENSOR_CHAN_GAUGE_TIME_TO_EMPTY
   Time to empty in minutes
enumerator SENSOR_CHAN_GAUGE_TIME_TO_FULL
   Time to full in minutes
enumerator SENSOR_CHAN_GAUGE_CYCLE_COUNT
   Cycle count (total number of charge/discharge cycles)
enumerator SENSOR_CHAN_GAUGE_DESIGN_VOLTAGE
   Design voltage of cell in V (max voltage)
enumerator SENSOR_CHAN_GAUGE_DESIRED_VOLTAGE
   Desired voltage of cell in V (nominal voltage)
enumerator SENSOR_CHAN_GAUGE_DESIRED_CHARGING_CURRENT
   Desired charging current in mA
enumerator SENSOR_CHAN_ALL
   All channels.
enumerator SENSOR_CHAN_COMMON_COUNT
   Number of all common sensor channels.
enumerator SENSOR_CHAN_PRIV_START = SENSOR_CHAN_COMMON_COUNT
   This and higher values are sensor specific. Refer to the sensor header file.
enumerator SENSOR_CHAN_MAX = INT16_MAX
   Maximum value describing a sensor channel type.

enum sensor_trigger_type
   Sensor trigger types.
   Values:
enumerator SENSOR_TRIG_TIMER
    Timer-based trigger, useful when the sensor does not have an interrupt line.

e enumerator SENSOR_TRIG_DATA_READY
    Trigger fires whenever new data is ready.

e enumerator SENSOR_TRIG_DELTA
    Trigger fires when the selected channel varies significantly. This includes any-motion
detection when the channel is acceleration or gyro. If detection is based on slope
between successive channel readings, the slope threshold is configured via the SENSOR_ATTR_SLOPE_TH and SENSOR_ATTR_SLOPE_DUR attributes.

e enumerator SENSOR_TRIG_NEAR_FAR
    Trigger fires when a near/far event is detected.

e enumerator SENSOR_TRIG_THRESHOLD
    Trigger fires when channel reading transitions configured thresholds. The thresholds are
configured via the SENSOR_ATTR_LOWER_THRESH, SENSOR_ATTR_UPPER_THRESH, and SENSOR_ATTR_HYSERESIS attributes.

e enumerator SENSOR_TRIG_TAP
    Trigger fires when a single tap is detected.

e enumerator SENSOR_TRIG_DOUBLE_TAP
    Trigger fires when a double tap is detected.

e enumerator SENSOR_TRIG_FREEFALL
    Trigger fires when a free fall is detected.

e enumerator SENSOR_TRIG_MOTION
    Trigger fires when motion is detected.

e enumerator SENSOR_TRIG_STATIONARY
    Trigger fires when no motion has been detected for a while.

e enumerator SENSOR_TRIG_COMMON_COUNT
    Number of all common sensor triggers.

e enumerator SENSOR_TRIG_PRIV_START = SENSOR_TRIG_COMMON_COUNT
    This and higher values are sensor specific. Refer to the sensor header file.

e enumerator SENSOR_TRIG_MAX = INT16_MAX
    Maximum value describing a sensor trigger type.

e enum sensor_attribute
    Sensor attribute types.
    Values:
enumerator SENSOR_ATTR_SAMPLING_FREQUENCY
   Sensor sampling frequency, i.e. how many times a second the sensor takes a measurement.

enumerator SENSOR_ATTR_LOWER_THRESH
   Lower threshold for trigger.

enumerator SENSOR_ATTR_UPPER_THRESH
   Upper threshold for trigger.

enumerator SENSOR_ATTR_SLOPE_TH
   Threshold for any-motion (slope) trigger.

enumerator SENSOR_ATTR_SLOPE_DUR
   Duration for which the slope values needs to be outside the threshold for the trigger to fire.

enumerator SENSOR_ATTR_HYSTERESIS

enumerator SENSOR_ATTR_OVERSAMPLING
   Oversampling factor

enumerator SENSOR_ATTR_FULL_SCALE
   Sensor range, in SI units.

enumerator SENSOR_ATTR_OFFSET
   The sensor value returned will be altered by the amount indicated by offset: final_value = sensor_value + offset.

enumerator SENSOR_ATTR_CALIB_TARGET
   Calibration target. This will be used by the internal chip's algorithms to calibrate itself on a certain axis, or all of them.

enumerator SENSOR_ATTR_CONFIGURATION
   Configure the operating modes of a sensor.

enumerator SENSOR_ATTR_CALIBRATION
   Set a calibration value needed by a sensor.

enumerator SENSOR_ATTR_FEATURE_MASK
   Enable/disable sensor features

enumerator SENSOR_ATTR_ALERT
   Alert threshold or alert enable/disable

enumerator SENSOR_ATTR_FF_DUR
   Free-fall duration represented in milliseconds. If the sampling frequency is changed during runtime, this attribute should be set to adjust freefall duration to the new sampling frequency.
enumerator SENSOR_ATTR_COMMON_COUNT
   Number of all common sensor attributes.

denumerator SENSOR_ATTR_PRIV_START = SENSOR_ATTR_COMMON_COUNT
   This and higher values are sensor specific. Refer to the sensor header file.

denumerator SENSOR_ATTR_MAX = INT16_MAX
   Maximum value describing a sensor attribute type.

Functions

int sensor_attr_set(const struct device *dev, enum sensor_channel chan, enum sensor_attribute attr, const struct sensor_value *val)
Set an attribute for a sensor.

Parameters

• dev – Pointer to the sensor device
• chan – The channel the attribute belongs to, if any. Some attributes may only be set for all channels of a device, depending on device capabilities.
• attr – The attribute to set
• val – The value to set the attribute to

Returns

0 if successful, negative errno code if failure.

int sensor_attr_get(const struct device *dev, enum sensor_channel chan, enum sensor_attribute attr, struct sensor_value *val)
Get an attribute for a sensor.

Parameters

• dev – Pointer to the sensor device
• chan – The channel the attribute belongs to, if any. Some attributes may only be set for all channels of a device, depending on device capabilities.
• attr – The attribute to get
• val – Pointer to where to store the attribute

Returns

0 if successful, negative errno code if failure.

static inline int sensor_trigger_set(const struct device *dev, const struct sensor_trigger *trig, sensor_trigger_handler_t handler)
Activate a sensor’s trigger and set the trigger handler.

The handler will be called from a thread, so I2C or SPI operations are safe. However, the thread’s stack is limited and defined by the driver. It is currently up to the caller to ensure that the handler does not overflow the stack.

Function properties (list may not be complete)
supervisor

Parameters

• dev – Pointer to the sensor device
• trig – The trigger to activate
• handler – The function that should be called when the trigger fires

Returns
0 if successful, negative errno code if failure.

int sensor_sample_fetch(const struct device *dev)
Fetch a sample from the sensor and store it in an internal driver buffer.
Read all of a sensor's active channels and, if necessary, perform any additional operations
necessary to make the values useful. The user may then get individual channel values by
calling sensor_channel_get.
Since the function communicates with the sensor device, it is unsafe to call it in an ISR if the
device is connected via I2C or SPI.

Parameters
• dev – Pointer to the sensor device

Returns
0 if successful, negative errno code if failure.

int sensor_sample_fetch_chan(const struct device *dev, enum sensor_channel type)
Fetch a sample from the sensor and store it in an internal driver buffer.
Read and compute compensation for one type of sensor data (magnetometer, accelerometer,
etc). The user may then get individual channel values by calling sensor_channel_get.
This is mostly implemented by multi function devices enabling reading at different sampling
rates.
Since the function communicates with the sensor device, it is unsafe to call it in an ISR if the
device is connected via I2C or SPI.

Parameters
• dev – Pointer to the sensor device
• type – The channel that needs updated

Returns
0 if successful, negative errno code if failure.

int sensor_channel_get(const struct device *dev, enum sensor_channel chan, struct sensor_value *val)
Get a reading from a sensor device.
Return a useful value for a particular channel, from the driver's internal data. Before
calling this function, a sample must be obtained by calling sensor_sample_fetch or sen-
sor_sample_fetch_chan. It is guaranteed that two subsequent calls of this function for the
same channels will yield the same value, if sensor_sample_fetch or sensor_sample_fetch_chan
has not been called in the meantime.
For vectorial data samples you can request all axes in just one call by passing the specific
channel with _XYZ suffix. The sample will be returned at val[0], val[1] and val[2] (X, Y and
Z in that order).

Parameters
• dev – Pointer to the sensor device
• chan – The channel to read
• val – Where to store the value

Returns
0 if successful, negative errno code if failure.
static inline int32_t sensor_ms2_to_g(const struct sensor_value *ms2)
    Helper function to convert acceleration from m/s^2 to Gs.

    Parameters
    • ms2 – A pointer to a sensor_value struct holding the acceleration, in m/s^2.

    Returns
    The converted value, in Gs.

dynamic inline void sensor_g_to_ms2(int32_t g, struct sensor_value *ms2)
    Helper function to convert acceleration from Gs to m/s^2.

    Parameters
    • g – The G value to be converted.
    • ms2 – A pointer to a sensor_value struct, where the result is stored.

dynamic inline int32_t sensor_rad_to_degrees(const struct sensor_value *rad)
    Helper function for converting radians to degrees.

    Parameters
    • rad – A pointer to a sensor_value struct, holding the value in radians.

    Returns
    The converted value, in degrees.

dynamic inline void sensor_degrees_to_rad(int32_t d, struct sensor_value *rad)
    Helper function for converting degrees to radians.

    Parameters
    • d – The value (in degrees) to be converted.
    • rad – A pointer to a sensor_value struct, where the result is stored.

dynamic inline double sensor_value_to_double(const struct sensor_value *val)
    Helper function for converting struct sensor_value to double.

    Parameters
    • val – A pointer to a sensor_value struct.

    Returns
    The converted value.

dynamic inline int sensor_value_from_double(struct sensor_value *val, double inp)
    Helper function for converting double to struct sensor_value.

    Parameters
    • val – A pointer to a sensor_value struct.
    • inp – The converted value.

    Returns
    0 if successful, negative errno code if failure.

struct sensor_value

#include <sensor.h> Representation of a sensor readout value.

The value is represented as having an integer and a fractional part, and can be obtained using
the formula val1 + val2 * 10^-6. Negative values also adhere to the above formula, but
may need special attention. Here are some examples of the value representation:
<table>
<thead>
<tr>
<th>0.5:</th>
<th>val1 = 0, val2 = 500000</th>
</tr>
</thead>
<tbody>
<tr>
<td>-0.5:</td>
<td>val1 = 0, val2 = -500000</td>
</tr>
<tr>
<td>-1.0:</td>
<td>val1 = -1, val2 = 0</td>
</tr>
<tr>
<td>-1.5:</td>
<td>val1 = -1, val2 = -500000</td>
</tr>
</tbody>
</table>

**Public Members**

```c
int32_t val1
  Integer part of the value.
```

```c
int32_t val2
  Fractional part of the value (in one-millionth parts).
```

```c
struct sensor_trigger
  #include <sensor.h>  Sensor trigger spec.
```

**Public Members**

```c
enum sensor_trigger_type type
  Trigger type.
```

```c
enum sensor_channel chan
  Channel the trigger is set on.
```

```c
struct sensor_driver_api
  #include <sensor.h>
```

### 7.3.35 SPI

**Overview**

**API Reference**

```c
group spi_interface
  SPI Interface.
```

**SPI operational mode**

```c
SPI_OP_MODE_MASTER

SPI_OP_MODE_SLAVE

SPI_OP_MODE_MASK

SPI_OP_MODE_GET(_operation_)
```
SPI Polarity & Phase Modes

SPI_MODE_CPOL

Clock Polarity: if set, clock idle state will be 1 and active state will be 0. If untouched, the inverse will be true which is the default.

SPI_MODE_CPHA

Clock Phase: this dictates when is the data captured, and depends clock's polarity. When SPI_MODE_CPOL is set and this bit as well, capture will occur on low to high transition and high to low if this bit is not set (default). This is fully reversed if CPOL is not set.

SPI_MODE_LOOP

Whatever data is transmitted is looped-back to the receiving buffer of the controller. This is fully controller dependent as some may not support this, and can be used for testing purposes only.

SPI_MODE_MASK

SPI_MODE_GET(_mode_)

SPI Transfer modes (host controller dependent)

SPI_TRANSFER_MSB

SPI_TRANSFER_LSB

SPI word size

SPI_WORD_SIZE_SHIFT

SPI_WORD_SIZE_MASK

SPI_WORD_SIZE_GET(_operation_)

SPI_WORD_SET(_word_size_)

Specific SPI devices control bits

SPI_HOLD_ON_CS

SPI_LOCK_ON

SPI_CS_ACTIVE_HIGH
SPI MISO lines (if \htmlonly <code>CONFIG_SPI_EXTENDED_MODES</code> \endhtmlonly \xmlonly <verbatim>embed:rst:inline :kconfig:option: 'CONFIG_SPI_EXTENDED_MODES' </verbatim> \endxmlonly is enabled)

Some controllers support dual, quad or octal MISO lines connected to slaves. Default is single, which is the case most of the time. Without \htmlonly<code>CONFIG_SPI_EXTENDED_MODES</code>\endhtmlonly being enabled, single is the only supported one.

SPI_LINES_SINGLE

SPI_LINES_DUAL

SPI_LINES_QUAD

SPI_LINES_OCTAL

SPI_LINES_MASK

SPI duplex mode

Some controllers support half duplex transfer, which results in 3-wire usage. By default, full duplex will prevail.

SPI_FULL_DUPLEX

SPI_HALF_DUPLEX

SPI Frame Format

2 frame formats are exposed: Motorola and TI. The main difference is the behavior of the CS line. In Motorola it stays active the whole transfer. In TI, it’s active only one serial clock period prior to actually make the transfer, it is thus inactive during the transfer, which ends when the clocks ends as well. By default, as it is the most commonly used, the Motorola frame format will prevail.

SPI_FRAME_FORMAT_MOTOROLA

SPI_FRAME_FORMAT_TI

Defines

SPI_CS_GPIOS_DT_SPEC_GET(spi_dev)

Get a struct \htmlonly<code>gpio_dt_spec</code>\endhtmlonly for a SPI device’s chip select pin.

Example devicetree fragment:

```c
gpio1: gpio@abcd0001 { ... };
gpio2: gpio@abcd0002 { ... };
```

(continues on next page)
spi@abcd0003 {
    compatible = "vnd.spi";
    cs-gpios = <&gpio1 10 GPIO_ACTIVE_LOW>,<&gpio2 20 GPIO_ACTIVE_LOW>;

    a: spi-dev-a@0 {
        reg = <0>;
    };

    b: spi-dev-b@1 {
        reg = <1>;
    };
};

Example usage:

SPI_CS_GPIOS_DT_SPEC_GET(DT_NODELABEL(a)) \ 
    // { DEVICE_DT_GET(DT_NODELABEL(gpio1)), 10, GPIO_ACTIVE_LOW } 
SPI_CS_GPIOS_DT_SPEC_GET(DT_NODELABEL(b)) \ 
    // { DEVICE_DT_GET(DT_NODELABEL(gpio2)), 20, GPIO_ACTIVE_LOW }

Parameters

• spi_dev – a SPI device node identifier

Returns

gpio_dt_spec struct corresponding with spi_dev's chip select

SPI_CS_GPIOS_DT_SPEC_INST_GET(inst)
Get a struct gpio_dt_spec for a SPI device's chip select pin.

This is equivalent to SPI_CS_GPIOS_DT_SPEC_GET(DT_DRV_INST(inst)).

Parameters

• inst – Devicetree instance number

Returns

gpio_dt_spec struct corresponding with spi_dev's chip select

SPI_CS_CONTROL_PTR_DT(node_id, delay_)
Initialize and get a pointer to a spi_cs_control from a devicetree node identifier.

This helper is useful for initializing a device on a SPI bus. It initializes a struct spi_cs_control
and returns a pointer to it. Here, node_id is a node identifier for a SPI device, not a SPI
controller.

Example devicetree fragment:

spi@... {
    cs-gpios = <&gpio0 1 GPIO_ACTIVE_LOW>;
    spidev: spi-device@0 { ... };
};

Assume that gpio0 follows the standard convention for specifying GPIOs, i.e. it has the
following in its binding:

7.3. Peripherals
gpio-cells:
- pin
- flags

Example usage:

```c
struct spi_cs_control *ctrl =
  SPI_CS_CONTROL_PTR_DT(DT_NODELABEL(spidev), 2);
```

This example is equivalent to:

```c
struct spi_cs_control *ctrl =
  & (struct spi_cs_control) {
    .gpio_dev = DEVICE_DT_GET(DT_NODELABEL(gpio0)),
    .delay = 2,
    .gpio_pin = 1,
    .gpio_dt_flags = GPIO_ACTIVE_LOW
  };
```

This macro is not available in C++.

**Parameters**

- `node_id` – Devicetree node identifier for a device on a SPI bus
- `delay_` – The delay field to set in the `spi_cs_control`

**Returns**

a pointer to the `spi_cs_control` structure

```c
SPI_CS_CONTROL_PTR_DT_INST(inst, delay_)
```

Get a pointer to a `spi_cs_control` from a devicetree node.

This is equivalent to `SPI_CS_CONTROL_PTR_DT(DT_DRV_INST(inst), delay)`.

Therefore, `DT_DRV_COMPAT` must already be defined before using this macro.

This macro is not available in C++.

**Parameters**

- `inst` – Devicetree node instance number
- `delay_` – The delay field to set in the `spi_cs_control`

**Returns**

a pointer to the `spi_cs_control` structure

```c
SPI_CONFIG_DT(node_id, operation_, delay_)
```

Structure initializer for `spi_config` from devicetree.

This helper macro expands to a static initializer for a struct `spi_config` by reading the relevant frequency, slave, and cs data from the devicetree.

Important: the cs field is initialized using `SPI_CS_CONTROL_PTR_DT()`. The gpio_dev value pointed to by this structure must be checked using `device_is_ready()` before use.

This macro is not available in C++.

**Parameters**

- `node_id` – Devicetree node identifier for the SPI device whose struct `spi_config` to create an initializer for
- `operation_` – the desired operation field in the struct `spi_config`
- `delay_` – the desired delay field in the struct `spi_config`'s `spi_cs_control`, if there is one
SPI_CONFIG_DT_INST(inst, operation_, delay_)
Structure initializer for spi_config from devicetree instance.
This is equivalent to SPI_CONFIG_DT(DT_DRV_INST(inst), operation_, delay_).
This macro is not available in C++.

Parameters
- inst – Devicetree instance number
- operation_ – the desired operation field in the struct spi_config
- delay_ – the desired delay field in the struct spi_config's spi_cs_control, if there is one

SPI_DT_SPEC_GET(node_id, operation_, delay_)
Structure initializer for spi_dt_spec from devicetree.
This helper macro expands to a static initializer for a struct spi_dt_spec by reading the relevant bus, frequency, slave, and cs data from the devicetree.
Important: multiple fields are automatically constructed by this macro which must be checked before use. spi_is_ready performs the required device_is_ready checks.
This macro is not available in C++.

Parameters
- node_id – Devicetree node identifier for the SPI device whose struct spi_dt_spec to create an initializer for
- operation_ – the desired operation field in the struct spi_config
- delay_ – the desired delay field in the struct spi_config's spi_cs_control, if there is one

SPI_DT_SPEC_INST_GET(inst, operation_, delay_)
Structure initializer for spi_dt_spec from devicetree instance.
This is equivalent to SPI_DT_SPEC_GET(DT_DRV_INST(inst), operation_, delay_).
This macro is not available in C++.

Parameters
- inst – Devicetree instance number
- operation_ – the desired operation field in the struct spi_config
- delay_ – the desired delay field in the struct spi_config's spi_cs_control, if there is one

Typedefs

typedef int (*spi_api_io)(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)
Callback API for I/O See spi_transceive() for argument descriptions.
Callback API for asynchronous I/O See spi_transceive_async() for argument descriptions.

typedef void (*spi_callback_t)(const struct device *dev, int result, void *data)
SPI callback for asynchronous transfer requests.

Param dev
SPI device which is notifying of transfer completion or error
**Param result**
Result code of the transfer request. 0 is success, -errno for failure.

**Param data**
Transfer requester supplied data which is passed along to the callback.

typedef int (*spi_api_io_async)(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, spi_callback_t cb, void *userdata)

typedef int (*spi_api_release)(const struct device *dev, const struct spi_config *config)
Callback API for unlocking SPI device. See *spi_release()* for argument descriptions.

**Functions**

static inline bool spi_is_ready(const struct spi_dt_spec *spec)
Validate that SPI bus is ready.

**Parameters**
- spec – SPI specification from devicetree

**Return values**
- true – if the SPI bus is ready for use.
- false – if the SPI bus is not ready for use.

int spi_transceive(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)
Read/write the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Parameters**
- dev – Pointer to the device structure for the driver instance
- config – Pointer to a valid *spi_config* structure instance. Pointer-comparison may be used to detect changes from previous operations.
- tx_bufs – Buffer array where data to be sent originates from, or NULL if none.
- rx_bufs – Buffer array where data to be read will be written to, or NULL if none.

**Return values**
- frames – Positive number of frames received in slave mode.
- 0 – If successful in master mode.
- -errno – Negative errno code on failure.

static inline int spi_transceive_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs)
Read/write data from an SPI bus specified in *spi_dt_spec*.
This is equivalent to:

```c
spi_transceive(spec->bus, &spec->config, tx_bufs, rx_bufs);
```

**Parameters**
• **spec** – SPI specification from devicetree
• **tx_bufs** – Buffer array where data to be sent originates from, or NULL if none.
• **rx_bufs** – Buffer array where data to be read will be written to, or NULL if none.

**Returns**
a value from `spi_transceive()`.

```c
static inline int spi_read(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *rx_bufs)
```
Read the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Note:** This function is an helper function calling `spi_transceive()`.

**Parameters**
• **dev** – Pointer to the device structure for the driver instance
• **config** – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.
• **rx_bufs** – Buffer array where data to be read will be written to.

**Return values**
• **0** – If successful.
• **-errno** – Negative errno code on failure.

```c
static inline int spi_read_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *rx_bufs)
```
Read data from a SPI bus specified in `spi_dt_spec`.

This is equivalent to:

```c
spi_read(spec->bus, &spec->config, rx_bufs);
```

**Parameters**
• **spec** – SPI specification from devicetree
• **rx_bufs** – Buffer array where data to be read will be written to.

**Returns**
a value from `spi_read()`.

```c
static inline int spi_write(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs)
```
Write the specified amount of data from the SPI driver.

**Note:** This function is synchronous.

**Note:** This function is an helper function calling `spi_transceive()`.

**Parameters**
• dev – Pointer to the device structure for the driver instance
• config – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.
• tx_bufs – Buffer array where data to be sent originates from.

**Return values**
• 0 – If successful.
• -errno – Negative errno code on failure.

```c
static inline int spi_write_dt(const struct spi_dt_spec *spec, const struct spi_buf_set *tx_bufs);
```

*Write data to a SPI bus specified in `spi_dt_spec`.

This is equivalent to:
```
spi_write(spec->bus, &spec->config, tx_bufs);
```

**Parameters**
• spec – SPI specification from devicetree
• tx_bufs – Buffer array where data to be sent originates from.

**Returns**
• A value from `spi_write()`.

```c
static inline int spi_transceive_cb(const struct device *dev, const struct spi_config *config, const struct spi_buf_set *tx_bufs, const struct spi_buf_set *rx_bufs, spi_callback_t callback, void *userdata);
```

*Read/write the specified amount of data from the SPI driver.*

**Note:** This function is asynchronous.

**Note:** This function is available only if `CONFIG_SPI_ASYNC` is selected.

**Parameters**
• dev – Pointer to the device structure for the driver instance
• config – Pointer to a valid `spi_config` structure instance. Pointer-comparison may be used to detect changes from previous operations.
• tx_bufs – Buffer array where data to be sent originates from, or NULL if none.
• rx_bufs – Buffer array where data to be read will be written to, or NULL if none.
• callback – Function pointer to completion callback. (Note: if NULL this function will not notify the end of the transaction, and whether it went successfully or not).
• userdata – Userdata passed to callback

**Return values**
• frames – Positive number of frames received in slave mode.
• 0 – If successful in master mode.
• -errno – Negative errno code on failure.
int spi_release(const struct device *dev, const struct spi_config *config)
Release the SPI device locked on and/or the CS by the current config.

Note: This synchronous function is used to release either the lock on the SPI device and/or the CS line that was kept if, and if only, given config parameter was the last one to be used (in any of the above functions) and if it has the SPI_LOCK_ON bit set and/or the SPI_HOLD_ON_CS bit set into its operation bits field. This can be used if the caller needs to keep its hand on the SPI device for consecutive transactions and/or if it needs the device to stay selected. Usually both bits will be used along each other, so the device is locked and stays on until another operation is necessary or until it gets released with the present function.

Parameters
- dev – Pointer to the device structure for the driver instance
- config – Pointer to a valid spi_config structure instance.

Return values
- 0 – If successful.
- -errno – Negative errno code on failure.

static inline int spi_release_dt(const struct spi_dt_spec *spec)
Release the SPI device specified in spi_dt_spec.
This is equivalent to:
spi_release(spec->bus, &spec->config);

Parameters
- spec – SPI specification from devicetree

Returns
a value from spi_release().

struct spi_cs_control
#include <spi.h> SPI Chip Select control structure.
This can be used to control a CS line via a GPIO line, instead of using the controller inner CS logic.

Public Members

struct gpio_dt_spec gpio
GPIO devicetree specification of CS GPIO. The device pointer can be set to NULL to fully inhibit CS control if necessary. The GPIO flags GPIO_ACTIVE_LOW/GPIO_ACTIVE_HIGH should be equivalent to SPI_CS_ACTIVE_HIGH/SPI_CS_ACTIVE_LOW options in struct spi_config.

uint32_t delay
Delay in microseconds to wait before starting the transmission and before releasing the CS line.

struct spi_config
#include <spi.h> SPI controller configuration structure.
**Warning:** Most drivers use pointer comparison to determine whether a passed configuration is different from one used in a previous transaction. Changes to fields in the structure may not be detected.

**Param frequency**

is the bus frequency in Hertz

**Param operation**

is a bit field with the following parts:

<table>
<thead>
<tr>
<th>Field</th>
<th>Bit Range</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>operational mode</td>
<td>[ 0 ]</td>
<td>- master or slave.</td>
</tr>
<tr>
<td>mode</td>
<td>[ 1 : 3 ]</td>
<td>- Polarity, phase and loop mode.</td>
</tr>
<tr>
<td>word_size</td>
<td>[ 5 : 10 ]</td>
<td>- Size of a data frame in bits.</td>
</tr>
<tr>
<td>cs_hold</td>
<td>[ 12 ]</td>
<td>- Hold on the CS line if possible.</td>
</tr>
<tr>
<td>cs_active_high</td>
<td>[ 14 ]</td>
<td>- Active high CS logic.</td>
</tr>
<tr>
<td>format</td>
<td>[ 15 ]</td>
<td>- Motorola or TI frame format.</td>
</tr>
</tbody>
</table>


**Param slave**

is the slave number from 0 to host controller slave limit.

**Param cs**

is a valid pointer on a struct `spi_cs_control` if CS line is emulated through a gpio line, or NULL otherwise.

```c
struct spi_dt_spec
    #include <spi.h> Complete SPI DT information.

Param bus
    is the SPI bus

Param config
    is the slave specific configuration
```

```c
struct spi_buf
    #include <spi.h> SPI buffer structure.

Param buf
    is a valid pointer on a data buffer, or NULL otherwise.

Param len
    is the length of the buffer or, if buf is NULL, will be the length which as to be sent as dummy bytes (as TX buffer) or the length of bytes that should be skipped (as RX buffer).
```

```c
struct spi_buf_set
    #include <spi.h> SPI buffer array structure.

Param buffers
    is a valid pointer on an array of `spi_buf`, or NULL.
```
Param count
is the length of the array pointed by buffers.

```c
struct spi_driver_api
    #include <spi.h> SPI driver API This is the mandatory API any SPI driver needs to expose.
```

## 7.3.36 TCPC

### Overview

**TCPC** (USB Type-C Port Controller) The TCPC is a device used to simplify the implementation of a USB-C system by providing the following three function:

- **VBUS and VCONN control** *USB Type-C:* The TCPC may provide a Source device, the mechanism to control VBUS sourcing, and a Sink device, the mechanism to control VBUS sinking. A similar mechanism is provided for the control of VCONN.
- **CC control and sensing:** The TCPC implements logic for controlling the CC pin pull-up and pull-down resistors. It also provides a way to sense and report what resistors are present on the CC pin.
- **Power Delivery message reception and transmission** *USB Power Delivery:* The TCPC sends and receives messages constructed in the TCPM and places them on the CC lines.

**TCPC API** The TCPC device driver functions as the liaison between the TCPC device and the application software; this is accomplished by the Zephyr's API provided by the device driver that's used to communicate with and control the TCPC device.

### Configuration Options

Related configuration options:

- `CONFIG_USBC_TCPC_DRIVER`

### API Reference

```c
group usb_type_c
    USB Type-C.
```

### Defines

- `TC_V_SINK_DISCONNECT_MIN_MV`
  VBUS minimum for a sink disconnect detection. See Table 4-3 VBUS Sink Characteristics.

- `TC_V_SINK_DISCONNECT_MAX_MV`
  VBUS maximum for a sink disconnect detection. See Table 4-3 VBUS Sink Characteristics.

- `TC_T_VBUS_ON_MAX_MS`
  From entry to Attached.SRC until VBUS reaches the minimum vSafe5V threshold as measured at the source's receptacle See Table 4-29 VBUS and VCONN Timing Parameters.
TC_T_VBUS_OFF_MAX_MS
From the time the Sink is detached until the Source removes VBUS and reaches vSafe0V (See USB PD). See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_VCONN_ON_MAX_MS
From the time the Source supplied VBUS in the Attached.SRC state. See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_VCONN_ON_PA_MAX_MS
From the time a Sink with accessory support enters the PoweredAccessory state until the Sink sources minimum VCONN voltage (see Table 4-5) See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_VCONN_OFF_MAX_MS
From the time that a Sink is detached or as directed until the VCONN supply is disconnected. See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_SINK_ADJ_MAX_MS
Response time for a Sink to adjust its current consumption to be in the specified range due to a change in USB Type-C Current advertisement See Table 4-29 VBUS and VCONN Timing Parameters.

TC_T_DRP_MIN_MS
The minimum period a DRP shall complete a Source to Sink and back advertisement See Table 4-30 DRP Timing Parameters.

TC_T_DRP_MAX_MS
The maximum period a DRP shall complete a Source to Sink and back advertisement See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRANSITION_MIN_MS
The minimum time a DRP shall complete transitions between Source and Sink roles during role resolution See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRANSITION_MAX_MS
The maximum time a DRP shall complete transitions between Source and Sink roles during role resolution See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRY_MIN_MS
Minimum wait time associated with the Try.SRC state. See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRY_MAX_MS
Maximum wait time associated with the Try.SRC state. See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRY_WAIT_MIN_MS
Minimum wait time associated with the Try.SNK state. See Table 4-30 DRP Timing Parameters.

TC_T_DRP_TRY_WAIT_MAX_MS
Maximum wait time associated with the Try.SNK state. See Table 4-30 DRP Timing Parameters.
TC_T_TRY_TIMEOUT_MIN_MS
Minimum timeout for transition from Try.SRC to TryWait.SNK. See Table 4-30 DRP Timing Parameters.

TC_T_TRY_TIMEOUT_MAX_MS
Maximum timeout for transition from Try.SRC to TryWait.SNK. See Table 4-30 DRP Timing Parameters.

TC_T_VPD_DETACH_MIN_MS
Minimum Time for a DRP to detect that the connected Charge-Through VCONNPowered USB Device has been detached, after VBUS has been removed. See Table 4-30 DRP Timing Parameters.

TC_T_VPD_DETACH_MAX_MS
Maximum Time for a DRP to detect that the connected Charge-Through VCONNPowered USB Device has been detached, after VBUS has been removed. See Table 4-30 DRP Timing Parameters.

TC_T_CC_DEBOUNCE_MIN_MS
Minimum time a port shall wait before it can determine it is attached See Table 4-31 CC Timing.

TC_T_CC_DEBOUNCE_MAX_MS
Maximum time a port shall wait before it can determine it is attached See Table 4-31 CC Timing.

TC_T_PD_DEBOUNCE_MIN_MS
Minimum time a Sink port shall wait before it can determine it is detached due to the potential for USB PD signaling on CC as described in the state definitions. See Table 4-31 CC Timing.

TC_T_PD_DEBOUNCE_MAX_MS
Maximum time a Sink port shall wait before it can determine it is detached due to the potential for USB PD signaling on CC as described in the state definitions. See Table 4-31 CC Timing.

TC_T_TRY_CC_DEBOUNCE_MIN_MS
Minimum Time a port shall wait before it can determine it is re-attached during the try-wait process. See Table 4-31 CC Timing.

TC_T_TRY_CC_DEBOUNCE_MAX_MS
Maximum Time a port shall wait before it can determine it is re-attached during the try-wait process. See Table 4-31 CC Timing.

TC_T_ERROR_RECOVERY_SELFPOWERED_MIN_MS
Minimum time a self-powered port shall remain in the ErrorRecovery state. See Table 4-31 CC Timing.

TC_T_ERROR_RECOVERY_SOURCE_MIN_MS
Minimum time a source shall remain in the ErrorRecovery state if it was sourcing VCONN in the previous state. See Table 4-31 CC Timing.
TC_T_RP_VALUE_CHANGE_MIN_MS
Minimum time a Sink port shall wait before it can determine there has been a change in Rp where CC is not BMC Idle or the port is unable to detect BMC Idle. See Table 4-31 CC Timing.

TC_T_RP_VALUE_CHANGE_MAX_MS
Maximum time a Sink port shall wait before it can determine there has been a change in Rp where CC is not BMC Idle or the port is unable to detect BMC Idle. See Table 4-31 CC Timing.

TC_T_SRC_DISCONNECT_MIN_MS
Minimum time a Source shall detect the SRC.Open state. The Source should detect the SRC.Open state as quickly as practical. See Table 4-31 CC Timing.

TC_T_SRC_DISCONNECT_MAX_MS
Maximum time a Source shall detect the SRC.Open state. The Source should detect the SRC.Open state as quickly as practical. See Table 4-31 CC Timing.

TC_T_NO_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when neither Port Partner is toggling. See Table 4-31 CC Timing.

TC_T_NO_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when neither Port Partner is toggling. See Table 4-31 CC Timing.

TC_T_ONE_PORT_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when one Port Partner is toggling 0ms ... dcSRC.DRP max * tDRP max + 2 * tNoToggleConnect). See Table 4-31 CC Timing.

TC_T_ONE_PORT_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when one Port Partner is toggling 0ms ... dcSRC.DRP max * tDRP max + 2 * tNoToggleConnect). See Table 4-31 CC Timing.

TC_T_TWO_PORT_TOGGLE_CONNECT_MIN_MS
Minimum time to detect connection when both Port Partners are toggling (0ms ... 5 * tDRP max + 2 * tNoToggleConnect). See Table 4-31 CC Timing.

TC_T_TWO_PORT_TOGGLE_CONNECT_MAX_MS
Maximum time to detect connection when both Port Partners are toggling (0ms ... 5 * tDRP max + 2 * tNoToggleConnect). See Table 4-31 CC Timing.

TC_T_VPDCTDD_MIN_US
Minimum time for a Charge-Through VCONN-Powered USB Device to detect that the Charge-Through source has disconnected from CC after VBUS has been removed, transition to CTU-nattached.VPD, and re-apply its Rp termination advertising 3.0 A on the host port CC. See Table 4-31 CC Timing.

TC_T_VPDCTDD_MAX_MS
Maximum time for a Charge-Through VCONN-Powered USB Device to detect that the Charge-Through source has disconnected from CC after VBUS has been removed, transition to CTU-nattached.VPD, and re-apply its Rp termination advertising 3.0 A on the host port CC. See Table 4-31 CC Timing.
TC_T_VPDDISABLE_MIN_MS
    Minimum time for a Charge-Through VCONN-Powered USB Device shall remain in CTDisabled.VPD state. See Table 4-31 CC Timing.

Enums

define tc_cc_voltage_state
    CC Voltage status.
    Values:

    enumerator TC_CC_VOLT_OPEN = 0
        No port partner connection

    enumerator TC_CC_VOLT_RA = 1
        Port partner is applying Ra

    enumerator TC_CC_VOLT_RD = 2
        Port partner is applying Rd

    enumerator TC_CC_VOLT_RP_DEF = 5
        Port partner is applying Rp (0.5A)

    enumerator TC_CC_VOLT_RP_1A5 = 6

    enumerator TC_CC_VOLT_RP_3A0 = 7
        Port partner is applying Rp (3.0A)

define tc_vbus_level
    VBUS level voltages.
    Values:

    enumerator TC_VBUS_SAFE0V = 0
        VBUS is less than vSafe0V max

    enumerator TC_VBUS_PRESENT = 1
        VBUS is at least vSafe5V min

    enumerator TC_VBUS_REMOVED = 2
        VBUS is less than vSinkDisconnect max

define tc_rp_value
    Pull-Up resistor values.
    Values:

    enumerator TC_RP_USB = 0
        Pull-Up resistor for a current of 900mA

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enumerator TC_RP_1A5 = 1
  Pull-Up resistor for a current of 1.5A

enumerator TC_RP_3A0 = 2
  Pull-Up resistor for a current of 3.0A

enumerator TC_RP_RESERVED = 3
  No Pull-Up resistor is applied

enum tc_cc_pull
  CC pull resistors.
  \textit{Values:}

  enumerator TC_CC_RA = 0
    Ra Pull-Down resistor

  enumerator TC_CC_RP = 1
    Rp Pull-Up resistor

  enumerator TC_CC_RD = 2
    Rd Pull-Down resistor

  enumerator TC_CC_OPEN = 3
    No CC resistor

  enumerator TC_RA_RD = 4
    Ra and Rd Pull-Down resistor

enum tc_cable_plug
  Cable plug. See 6.2.1.1.7 Cable Plug. Only applies to SOP' and SOP". Replaced by\npd_power_role for SOP packets.
  \textit{Values:}

  enumerator PD_PLUG_FROM_DFP_UFP = 0

  enumerator PD_PLUG_FROM_CABLE_VPD = 1

enum tc_power_role
  Power Delivery Power Role.
  \textit{Values:}

  enumerator TC_ROLE_SINK = 0
    Power role is a sink

  enumerator TC_ROLE_SOURCE = 1
    Power role is a source
enum tc_data_role
    Power Delivery Data Role.
    Values:

    enumerator TC_ROLE_UFP = 0
        Data role is an Upstream Facing Port

    enumerator TC_ROLE_DFP = 1
        Data role is a Downstream Facing Port

    enumerator TC_ROLE_DISCONNECTED = 2
        Port is disconnected

enum tc_cc_polarity
    Polarity of the CC lines.
    Values:

    enumerator TC_POLARITY_CC1 = 0
        Use CC1 IO for Power Delivery communication

    enumerator TC_POLARITY_CC2 = 1
        Use CC2 IO for Power Delivery communication

enum tc_cc_states
    Possible port partner connections based on CC line states.
    Values:

    enumerator TC_CC_NONE = 0
        No port partner attached

    enumerator TC_CC_UFP_NONE = 1
        From DFP perspective No UFP accessory connected

    enumerator TC_CC_UFP_AUDIO_ACC = 2
        UFP Audio accessory connected

    enumerator TC_CC_UFP_DEBUG_ACC = 3
        UFP Debug accessory connected

    enumerator TC_CC_UFP_ATTACHED = 4
        Plain UFP attached

    enumerator TC_CC_DFP.Attach = 5
        From UFP perspective Plain DFP attached

    enumerator TC_CC_DFP_DEBUG_ACC = 6
        DFP debug accessory connected

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USB Type-C Port Controller API.

**Typedefs**

typedef int (*tcpc_vconn_control_cb_t)(const struct device *dev, bool enable)

typedef void (*tcpc_alert_handler_cb_t)(const struct device *dev, void *data, enum tcpc_alert alert)

**Enums**

enum tcpc_alert
   TCPC Alert bits.
   Values:

   enumerator TCPC_ALERT_CC_STATUS
      CC status changed

   enumerator TCPC_ALERT_POWER_STATUS
      Power status changed

   enumerator TCPC_ALERT_MSG_STATUS
      Receive Buffer register changed

   enumerator TCPC_ALERT_HARD_RESET_RECEIVED
      Received Hard Reset message

   enumerator TCPC_ALERT_TRANSMIT_MSG_FAILED
      SOP* message transmission not successful

   enumerator TCPC_ALERT_TRANSMIT_MSG_DISCARDED
      Reset or SOP* message transmission not sent due to an incoming receive message

   enumerator TCPC_ALERT_TRANSMIT_MSG_SUCCESS
      Reset or SOP* message transmission successful

   enumerator TCPC_ALERT_VBUS_ALARM_HI
      A high-voltage alarm has occurred

   enumerator TCPC_ALERT_VBUS_ALARM_LO
      A low-voltage alarm has occurred

   enumerator TCPC_ALERT_FAULT_STATUS
      A fault has occurred. Read the FAULT_STATUS register
enumerator TCPC_ALERT_RX_BUFFER_OVERFLOW
   TCPC RX buffer has overflowed

enumerator TCPC_ALERT_VBUS_SNK_DISCONNECT
   The TCPC in Attached.SNK state has detected a sink disconnect

enumerator TCPC_ALERT_BEGINNING_MSG_STATUS
   Receive buffer register changed

enumerator TCPC_ALERT_EXTENDED_STATUS
   Extended status changed

enumerator TCPC_ALERT_EXTENDED
   An extended interrupt event has occurred. Read the alert_extended register

enumerator TCPC_ALERT_VENDOR_DEFINED
   A vendor defined alert has been detected

enum tcpc_status_reg
   TCPC Status register.
   Values:

   enumerator TCPC_CC_STATUS
      The CC Status register

   enumerator TCPC_POWER_STATUS
      The Power Status register

   enumerator TCPC_FAULT_STATUS
      The Fault Status register

   enumerator TCPC_EXTENDED_STATUS
      The Extended Status register

   enumerator TCPC_EXTENDED_ALERT_STATUS
      The Extended Alert Status register

   enumerator TCPC_VENDOR_DEFINED_STATUS
      The Vendor Defined Status register

Functions

static inline int tcpc_is_cc_rp(enum tc_cc_voltage_state cc)
   Returns whether the sink has detected a Rp resistor on the other side.

static inline int tcpc_is_cc_open(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)
   Returns true if both CC lines are completely open.
static inline int tcpc_is_cc_snk_dbg_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)

Returns true if we detect the port partner is a snk debug accessory.

static inline int tcpc_is_cc_src_dbg_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)

Returns true if we detect the port partner is a src debug accessory.

static inline int tcpc_is_cc_audio_acc(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)

Returns true if the port partner is an audio accessory.

static inline int tcpc_is_cc_at_least_one_rd(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)

Returns true if the port partner is presenting at least one Rd.

static inline int tcpc_is_cc_only_one_rd(enum tc_cc_voltage_state cc1, enum tc_cc_voltage_state cc2)

Returns true if the port partner is presenting Rd on only one CC line.

static inline int tcpc_init(const struct device *dev)

Initializes the TCPC.

Parameters

• dev – Runtime device structure

Return values

• 0 – on success
• -EIO – on failure

static inline int tcpc_get_cc(const struct device *dev, enum tc_cc_voltage_state *cc1, enum tc_cc_voltage_state *cc2)

Reads the status of the CC lines.

Parameters

• dev – Runtime device structure
• cc1 – A pointer where the CC1 status is written
• cc2 – A pointer where the CC2 status is written

Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_select_rp_value(const struct device *dev, enum tc_rp_value rp)

Sets the value of CC pull up resistor used when operating as a Source.

Parameters

• dev – Runtime device structure
• rp – Value of the Pull-Up Resistor.

Return values

• 0 – on success
• -ENOSYS –
• -EIO – on failure
static inline int tcpc_get_rp_value(const struct device *dev, enum tc_rp_value *rp)

  Gets the value of the CC pull up resistor used when operating as a Source.

  **Parameters**
  - `dev` – Runtime device structure
  - `rp` – pointer where the value of the Pull-Up Resistor is stored

  **Return values**
  - 0 – on success
  - -ENOSYS –
  - -EIO – on failure

static inline int tcpc_set_cc(const struct device *dev, enum tc_cc_pull pull)

  Sets the CC pull resistor and sets the role as either Source or Sink.

  **Parameters**
  - `dev` – Runtime device structure
  - `pull` – The pull resistor to set

  **Return values**
  - 0 – on success
  - -EIO – on failure

static inline void tcpc_set_vconn_cb(const struct device *dev, tcpc_vconn_control_cb_t vconn_cb)

  Sets a callback that can enable or disable VCONN if the TCPC is unable to or the system is configured in a way that does not use the VCONN control capabilities of the TCPC.

  The callback is called in the tcpc_set_vconn function if vconn_cb isn’t NULL

  **Parameters**
  - `dev` – Runtime device structure
  - `vconn_cb` – pointer to the callback function that controls vconn

static inline int tcpc_set_vconn(const struct device *dev, bool enable)

  Enables or disables VCONN.

  This function uses the TCPC to measure VCONN if possible or calls the callback function set by tcpc_set_vconn_cb

  **Parameters**
  - `dev` – Runtime device structure
  - `enable` – VCONN is enabled when true, it’s disabled

  **Return values**
  - 0 – on success
  - -EIO – on failure
  - -ENOSYS – if not implemented

static inline int tcpc_set_roles(const struct device *dev, enum tc_power_role power_role, enum tc_data_role data_role)

  Sets the Power and Data Role of the PD message header.

  This function only needs to be called once per data / power role change

  **Parameters**
  - `dev` – Runtime device structure
• power_role – current power role
• data_role – current data role

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline bool tcpc_is_rx_pending_msg(const struct device *dev, enum pd_packet_type *type)
Tests if a received Power Delivery message is pending.

Parameters
• dev – Runtime device structure
• type – pointer to where message type is written. Can be NULL

Return values
• true – if message is pending, else false
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_receive_data(const struct device *dev, struct pd_msg *buf)
Retrieves the Power Delivery message from the TCPC.

Parameters
• dev – Runtime device structure
• buf – pointer where the pd_buf pointer is written

Return values
• Greater – or equal to 0 is the number of bytes received
• -EIO – on failure
• -EFAULT – on buf being NULL
• -ENOSYS – if not implemented

static inline int tcpc_set_rx_enable(const struct device *dev, bool enable)
Enables the reception of SOP* message types.

Parameters
• dev – Runtime device structure
• enable – Enable Power Delivery when true, else it’s disabled

Return values
• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_cc_polarity(const struct device *dev, enum tc_cc_polarity polarity)
Sets the polarity of the CC lines.

Parameters
• dev – Runtime device structure
• polarity – Polarity of the cc line

Return values
static inline int tcpc_transmit_data(const struct device *dev, struct pd_msg *msg)

Transmits a Power Delivery message.

Parameters

• dev – Runtime device structure
• msg – Power Delivery message to transmit

Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_dump_std_reg(const struct device *dev)

Dump a set of TCPC registers.

Parameters

• dev – Runtime device structure

Return values

• 0 – on success
• -EIO – on failure
• -ENOSYS – if not implemented

static inline int tcpc_set_alert_handler_cb(const struct device *dev, tcpc_alert_handler_cb_t handler, void *data)

Sets the alert function that's called when an interrupt is triggered due to an alert bit.

Calling this function enables the particular alert bit

Parameters

• dev – Runtime device structure
• handler – The callback function called when the bit is set
• data – user data passed to the callback

Return values

• 0 – on success
• -EINVAL – on failure

static inline int tcpc_get_status_register(const struct device *dev, enum tcpc_status_reg reg, int32_t *status)

Gets a status register.

Parameters

• dev – Runtime device structure
• reg – The status register to read
• status – Pointer where the status is stored

Return values

• 0 – on success
• -EIO – on failure
static inline int tcpc_clear_status_register(const struct device *dev, enum tcpc_status_reg reg, uint32_t mask)
Clears a TCPC status register.

Parameters
- dev – Runtime device structure
- reg – The status register to read
- mask – A bit mask of the status register to clear. A status bit is cleared when it’s set to 1.

Return values
- 0 – on success
- -EIO – on failure
- -ENOSYS – if not implemented

static inline int tcpc_mask_status_register(const struct device *dev, enum tcpc_status_reg reg, uint32_t mask)
Sets the mask of a TCPC status register.

Parameters
- dev – Runtime device structure
- reg – The status register to read
- mask – A bit mask of the status register to mask. The status bit is masked if it’s 0, else it’s unmasked.

Return values
- 0 – on success
- -EIO – on failure
- -ENOSYS – if not implemented

static inline int tcpc_set_debug_accessory(const struct device *dev, bool enable)
Manual control of TCPC DebugAccessory control.

Parameters
- dev – Runtime device structure
- enable – Enable Debug Accessory when true, else it’s disabled

Return values
- 0 – on success
- -EIO – on failure
- -ENOSYS – if not implemented

static inline int tcpc_set_debug_detach(const struct device *dev)
Detach from a debug connection.

Parameters
- dev – Runtime device structure

Return values
- 0 – on success
- -EIO – on failure
static inline int tcpc_set_drp_toggle(const struct device *dev, bool enable)

Enable TCPC auto dual role toggle.

Parameters
- dev – Runtime device structure
- enable – Auto dual role toggle is active when true, else it’s disabled

Return values
- 0 – on success
- -EINVAL – on failure
- -ENOSYS – if not implemented

static inline bool tcpc_get_snk_ctrl(const struct device *dev)

Queries the current sinking state of the TCPC.

Parameters
- dev – Runtime device structure

Return values
- true – if sinking power
- false – if not sinking power
- -ENOSYS – if not implemented

static inline bool tcpc_get_src_ctrl(const struct device *dev)

Queries the current sourcing state of the TCPC.

Parameters
- dev – Runtime device structure

Return values
- true – if sourcing power
- false – if not sourcing power
- -ENOSYS – if not implemented

static inline int tcpc_set_bist_test_mode(const struct device *dev, bool enable)

Controls the BIST Mode of the TCPC. It disables RX alerts while the mode is active.

Parameters
- dev – Runtime device structure
- enable – The TCPC enters BIST TEST Mode when true

Return values
- 0 – on success
- -EINVAL – on failure
- -ENOSYS – if not implemented

static inline int tcpc_get_chip_info(const struct device *dev, struct tcpc_chip_info *chip_info)

Gets the TCPC firmware version.

Parameters
- dev – Runtime device structure
- chip_info – Pointer to TCPC chip info where the version is stored
Return values
- 0 – on success
- -EIO – on failure
- -ENOSSYS – if not implemented

static inline int tcpc_set_low_power_mode(const struct device *dev, bool enable)
Instructs the TCPC to enter or exit low power mode.

Parameters
- dev – Runtime device structure
- enable – The TCPC enters low power mode when true, else it exits it

Return values
- 0 – on success
- -EIO – on failure
- -ENOSSYS – if not implemented

static inline int tcpc_sop_prime_enable(const struct device *dev, bool enable)
Enables the reception of SOP Prime messages.

Parameters
- dev – Runtime device structure
- enable – Can receive SOP Prime messages when true, else it can not

Return values
- 0 – on success
- -EIO – on failure
- -ENOSSYS – if not implemented

struct tcpc_chip_info
#include <usbc_tcpc.h> TCPC Chip Information.

Public Members

uint16_t vendor_id
Vendor Id

uint16_t product_id
Product Id

uint16_t device_id
Device Id

uint64_t fw_version_number
Firmware version number

uint8_t min_req_fw_version_string[8]
Minimum Required firmware version string
uint64_t min_req_fw_version_number
  Minimum Required firmware version number

struct tcpc_driver_api
  #include <usbc_tcpc.h>

group usb_power_delivery
  USB Power Delivery.

Defines

PD_MAX_EXTENDED_MSG_LEGACY_LEN
  Maximum length of a non-Extended Message in bytes. See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgLegacyLen.

PD_MAX_EXTENDED_MSG_LEN
  Maximum length of an Extended Message in bytes. See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgLen.

PD_MAX_EXTENDED_MSG_CHUNK_LEN
  Maximum length of a Chunked Message in bytes. When one of both Port Partners do not support Extended Messages of Data Size greater than PD_MAX_EXTENDED_MSG_LEGACY_LEN then the Protocol Layer supports a Chunking mechanism to break larger Messages into smaller Chunks of size PD_MAX_EXTENDED_MSG_CHUNK_LEN. See Table 6-75 Value Parameters Parameter Name: MaxExtendedMsgChunkLen.

PD_T_TYPEC_SINK_WAIT_CAP_MIN_MS
  Minimum time a sink shall wait for a Source_Capabilities message before sending a Hard Reset See Table 6-61 Time Values Parameter Name: tTypeCSinkWaitCap.

PD_T_TYPEC_SINK_WAIT_CAP_MAX_MS
  Minimum time a sink shall wait for a Source_Capabilities message before sending a Hard Reset See Table 6-61 Time Values Parameter Name: tTypeCSinkWaitCap.

PD_V_SAFE_0V_MAX_MV
  VBUS maximum safe operating voltage at “zero volts”. See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: vSafe0V.

PD_V_SAFE_5V_MIN_MV
  VBUS minimum safe operating voltage at 5V. See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: vSafe5V.

PD_T_SAFE_0V_MAX_MS
  Time to reach PD_V_SAFE_0V_MAX_MV max in milliseconds. See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: tSafe0V.

PD_T_SAFE_5V_MAX_MS
  Time to reach PD_V_SAFE_5V_MIN_MV max in milliseconds. See Table 7-24 Common Source/Sink Electrical Parameters Parameter Name: tSafe5V.
PD_T_TX_TIMEOUT_MS
Time to wait for TCPC to complete transmit.

PD_T_HARD_RESET_COMPLETE_MIN_MS
Minimum time a Hard Reset must complete. See Table 6-68 Time Values.

PD_T_HARD_RESET_COMPLETE_MAX_MS
Maximum time a Hard Reset must complete. See Table 6-68 Time Values.

PD_T_SENDER_RESPONSE_MIN_MS
Minimum time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SENDER_RESPONSE_NOM_MS
Nominal time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SENDER_RESPONSE_MAX_MS
Maximum time a response must be sent from a Port Partner See Table 6-68 Time Values.

PD_T_SINK_REQUEST_MIN_MS
Minimum time to wait before sending another request after receiving a Wait message See Table 6-68 Time Values.

PD_T_CHUNKING_NOT_SUPPORTED_MIN_MS
Minimum time to wait before sending a Not_Supported message after receiving a Chunked message See Table 6-68 Time Values.
**PD_T_CHUNKING_NOT_SUPPORTED_NOM_MS**
Nominal time to wait before sending a Not_Supported message after receiving a Chunked message. See Table 6-68 Time Values.

**PD_T_CHUNKING_NOT_SUPPORTED_MAX_MS**
Maximum time to wait before sending a Not_Supported message after receiving a Chunked message. See Table 6-68 Time Values.

**PD_CONVERT_BYTES_TO_PD_HEADER_COUNT(c)**
Convert bytes to PD Header data object count, where a data object is 4-bytes.

**Parameters**
- c – number of bytes to convert

**PD_CONVERT_PD_HEADER_COUNT_TO_BYTES(c)**
Convert PD Header data object count to bytes.

**Parameters**
- c – number of PD Header data objects

**SINK_TX_OK**
Collision avoidance Rp values in REV 3.0 Sink Transmit “OK”.

**SINK_TX_NG**
Collision avoidance Rp values in REV 3.0 Sink Transmit “NO GO”.

**PD_GET_EXT_HEADER(c)**
Used to get extended header from the first 32-bit word of the message.

**Parameters**
- c – first 32-bit word of the message

**PDO_MAX_DATA_OBJECTS**
Maximum number of 32-bit data objects sent in a single request.

PDO - Power Data Object, RDO - Request Data Object

**PD_CONVERT_MA_TO_FIXED_PDO_CURRENT(c)**
Convert milliamps to Fixed PDO Current in 10mA units.

**Parameters**
- c – Current in milliamps

**PD_CONVERT_MV_TO_FIXED_PDO_VOLTAGE(v)**
Convert millivolts to Fixed PDO Voltage in 50mV units.

**Parameters**
- v – Voltage in millivolts

**PD_CONVERT_FIXED_PDO_CURRENT_TO_MA(c)**
Convert a Fixed PDO Current from 10mA units to milliamps.

**Parameters**
- c – Fixed PDO current in 10mA units.
PD_CONVERT_FIXED_PDO_VOLTAGE_TO_MV(v)
Convert a Fixed PDO Voltage from 50mV units to millivolts. Used for converting pd_fixed_supply_pdo_source.voltage and pd_fixed_supply_pdo_sink.voltage.

Parameters
• v – Fixed PDO voltage in 50mV units.

PD_CONVERT_MA_TO_VARIABLE_PDO_CURRENT(c)
Convert milliamps to Variable PDO Current in 10ma units.

Parameters
• c – Current in milliamps

PD_CONVERT_MV_TO_VARIABLE_PDO_VOLTAGE(v)
Convert millivolts to Variable PDO Voltage in 50mV units.

Parameters
• v – Voltage in millivolts

PD_CONVERT_VARIABLE_PDO_CURRENT_TO_MA(c)
Convert a Variable PDO Current from 10mA units to milliamps.

Parameters
• c – Variable PDO current in 10mA units.

PD_CONVERT_VARIABLE_PDO_VOLTAGE_TO_MV(v)
Convert a Variable PDO Voltage from 50mV units to millivolts.

Parameters
• v – Variable PDO voltage in 50mV units.

PD_CONVERT_MW_TO_BATTERY_PDO_POWER(c)
Convert milliwatts to Battery PDO Power in 250mW units.

Parameters
• c – Power in milliwatts

PD_CONVERT_MV_TO_BATTERY_PDO_VOLTAGE(v)
Convert milliwatts to Battery PDO Voltage in 50mV units.

Parameters
• v – Voltage in millivolts

PD_CONVERT_BATTERY_PDO_POWER_TO_MW(c)
Convert a Battery PDO Power from 250mW units to milliwatts.

Parameters
• c – Power in 250mW units.

PD_CONVERT_BATTERY_PDO_VOLTAGE_TO_MV(v)
Convert a Battery PDO Voltage from 50mV units to millivolts.

Parameters
• v – Voltage in 50mV units.

PD_CONVERT_MA_TO_AUGMENTED_PDO_CURRENT(c)
Convert milliamps to Augmented PDO Current in 50mA units.

Parameters
• c – Current in milliamps
PD_CONVERT_MV_TO_AUGMENTED_PDO_VOLTAGE(v)
Convert millivolts to Augmented PDO Voltage in 100mV units.

**Parameters**
- v – Voltage in millivolts

PD_CONVERT_AUGMENTED_PDO_CURRENT_TO_MA(c)
Convert an Augmented PDO Current from 50mA units to milliamps.

**Parameters**
- c – Augmented PDO current in 50mA units.

PD_CONVERT_AUGMENTED_PDO_VOLTAGE_TO_MV(v)
Convert an Augmented PDO Voltage from 100mV units to millivolts.

**Parameters**
- v – Augmented PDO voltage in 100mV units.

NUM_SOP_STAR_TYPES
Number of valid Transmit Types.

** Enums **

enum pdo_type
Power Data Object Type Table 6-7 Power Data Object.

* Values: *

- enumerator PDO_FIXED = 0
  Fixed supply (Vmin = Vmax)

- enumerator PDO_BATTERY = 1
  Battery

- enumerator PDO_VARIABLE = 2
  Variable Supply (non-Battery)

- enumerator PDO_AUGMENTED = 3
  Augmented Power Data Object (APDO)

enum pd_frs_type
Fast Role Swap Required for USB Type-C current.

* Values: *

- enumerator FRS_NOT_SUPPORTED
  Fast Swap not supported

- enumerator FRS_DEFAULT_USB_POWER
  Default USB Power

- enumerator FRS_1P5A_5V
  1.5A @ 5V
enumerator FRS_3P0A_5V
   3.0A @ 5V

defined

enum pd_rev_type
   Protocol revision.
   \textit{Values:}

   enumerator PD_REV10 = 0
      PD revision 1.0

   enumerator PD_REV20 = 1
      PD revision 2.0

   enumerator PD_REV30 = 2
      PD revision 3.0

enum pd_packet_type
   Power Delivery packet type See USB Type-C Port Controller Interface Specification, Revision
   2.0, Version 1.2, Table 4-38 TRANSMIT Register Definition.
   \textit{Values:}

   enumerator PD_PACKET_SOP = 0
      Port Partner message

   enumerator PD_PACKET_SOP_PRIME = 1
      Cable Plug message

   enumerator PD_PACKET_PRIME_PRIME = 2
      Cable Plug message far end

   enumerator PD_PACKET_DEBUG_PRIME = 3
      Currently undefined in the PD specification

   enumerator PD_PACKET_DEBUG_PRIME_PRIME = 4
      Currently undefined in the PD specification

   enumerator PD_PACKET_TX_HARD_RESET = 5
      Hard Reset message to the Port Partner

   enumerator PD_PACKET_CABLE_RESET = 6
      Cable Reset message to the Cable

   enumerator PD_PACKET_TX_BIST_MODE_2 = 7
      BIST_MODE_2 message to the Port Partner

   enumerator PD_PACKET_MSG_INVALID = 0xf
      USED ONLY FOR RECEPTION OF UNKNOWN MSG TYPES
enum pd_ctrl_msg_type
    Control Message type See Table 6-5 Control Message Types.
    Values:

    enumerator PD_CTRL_GOOD_CRC = 1
        0 Reserved GoodCRC Message

    enumerator PD_CTRL_GOTO_MIN = 2
        GotoMin Message

    enumerator PD_CTRL_ACCEPT = 3
        Accept Message

    enumerator PD_CTRL_REJECT = 4
        Reject Message

    enumerator PD_CTRL_PING = 5
        Ping Message

    enumerator PD_CTRL_PS_RDY = 6
        PS_RDY Message

    enumerator PD_CTRL_GET_SOURCE_CAP = 7
        Get_Source_Cap Message

    enumerator PD_CTRL_GET_SINK_CAP = 8
        Get_Sink_Cap Message

    enumerator PD_CTRL_DR_SWAP = 9
        DR_Swap Message

    enumerator PD_CTRL_PR_SWAP = 10
        PR_Swap Message

    enumerator PD_CTRL_VCONN_SWAP = 11
        VCONN_Swap Message

    enumerator PD_CTRL_WAIT = 12
        Wait Message

    enumerator PD_CTRL_SOFT_RESET = 13
        Soft Reset Message

    enumerator PD_CTRL_DATA_RESET = 14
        Used for REV 3.0 Data_Reset Message

    enumerator PD_CTRL_DATA_RESET_COMPLETE = 15
        Data_Reset_Complete Message
enumerator PD_CTRL_NOT_SUPPORTED = 16
   Not_Supported Message
enumerator PD_CTRL_GET_SOURCE_CAP_EXT = 17
   Get_Source_Cap_Extended Message
enumerator PD_CTRL_GET_STATUS = 18
   Get_Status Message
enumerator PD_CTRL_FR_SWAP = 19
   FR_Swap Message
enumerator PD_CTRL_GET_PPS_STATUS = 20
   Get_PPS_Status Message
enumerator PD_CTRL_GET_COUNTRY_CODES = 21
   Get_Country_Codes Message
enumerator PD_CTRL_GET_SINK_CAP_EXT = 22
   Get_Sink_Cap_Extended Message

enum pd_data_msg_type
   Data message type See Table 6-6 Data Message Types.
   Values:
   enumerator PD_DATA_SOURCE_CAP = 1
      0 Reserved Source_Capabilities Message
   enumerator PD_DATA_REQUEST = 2
      Request Message
   enumerator PD_DATA_BIST = 3
      BIST Message
   enumerator PD_DATA_SINK_CAP = 4
      Sink Capabilities Message
   enumerator PD_DATA_BATTERY_STATUS = 5
      5-14 Reserved for REV 2.0
   enumerator PD_DATA_ALERT = 6
      Alert Message
   enumerator PD_DATA_GET_COUNTRY_INFO = 7
      Get Country Info Message
   enumerator PD_DATA_ENTER_USB = 8
      8-14 Reserved for REV 3.0 Enter USB message
enumerator PD_DATA_VENDOR_DEF = 15
Vendor Defined Message

denum pd_ext_msg_type
    Extended message type for REV 3.0 See Table 6-48 Extended Message Types.
    Values:

enumerator PD_EXT_SOURCE_CAP = 1
    0 Reserved Source_Capabilities_Extended Message

enumerator PD_EXT_STATUS = 2
    Status Message

enumerator PD_EXT_GET_BATTERY_CAP = 3
    Get_Battery_Cap Message

enumerator PD_EXT_GET_BATTERY_STATUS = 4
    Get_Battery_Status Message

enumerator PD_EXT_BATTERY_CAP = 5
    Battery_Capabilities Message

enumerator PD_EXT_GET_MANUFACTURER_INFO = 6
    Get_Manufacturer_Info Message

enumerator PD_EXT_MANUFACTURER_INFO = 7
    Manufacturer_Info Message

enumerator PD_EXT_SECURITY_REQUEST = 8
    Security_Request Message

enumerator PD_EXT_SECURITY_RESPONSE = 9
    Security_Response Message

enumerator PD_EXT_FIRMWARE_UPDATE_REQUEST = 10
    Firmware_Update_Request Message

enumerator PD_EXT_FIRMWARE_UPDATE_RESPONSE = 11
    Firmware_Update_Response Message

enumerator PD_EXT_PPS_STATUS = 12
    PPS_Status Message

enumerator PD_EXT_COUNTRY_INFO = 13
    Country_Codes Message

enumerator PD_EXT_COUNTRY_CODES = 14
    Country_Info Message

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enum usbpd_cc_pin
   Active PD CC pin.

   Values:

   enumerator USBPD_CC_PIN_1 = 0
      PD is active on CC1

   enumerator USBPD_CC_PIN_2 = 1
      PD is active on CC2

union pd_header
   #include <usbc_pd.h> Build a PD message header See Table 6-1 Message Header.

   Public Members

   uint16_t message_type
      Type of message

   uint16_t port_data_role
      Port Data role

   uint16_t specification_revision
      Specification Revision

   uint16_t port_power_role
      Port Power Role

   uint16_t message_id
      Message ID

   uint16_t number_of_data_objects
      Number of Data Objects

   uint16_t extended
      Extended Message

struct pd_header.[anonymous] [anonymous]

   union raw_value

union pd_ext_header
   #include <usbc_pd.h> Build an extended message header See Table 6-3 Extended Message Header.

   Public Members
uint16_t data_size
   Number of total bytes in data block

uint16_t reserved0
   Reserved

uint16_t request_chunk
   1 for a chunked message, else 0

uint16_t chunk_number
   Chunk number when chkd = 1, else 0

uint16_t chunked
   1 for chunked messages

struct pd_ext_header.[anonymous] [anonymous]

uint16_t raw_value
   Raw PD Ext Header value

union pd_fixed_supply_pdo_source
   #include <usbc_pd.h> Create a Fixed Supply PDO Source value See Table 6-9 Fixed Supply PDO - Source.

Public Members

uint32_t max_current
   Maximum Current in 10mA units

uint32_t voltage
   Voltage in 50mV units

uint32_t peak_current
   Peak Current

uint32_t reserved0
   Reserved – Shall be set to zero.

uint32_t unchunked_ext_msg_supported
   Unchunked Extended Messages Supported

uint32_t dual_role_data
   Dual-Role Data

uint32_t usb_comms_capable
   USB Communications Capable

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```c
uint32_t unconstrained_power
    Unconstrained Power

uint32_t usb_suspend_supported
    USB Suspend Supported

uint32_t dual_role_power
    Dual-Role Power

enum pdo_type
    Fixed supply. SET TO PDO_FIXED

struct pd_fixed_supply_pdo_source.

uint32_t raw_value
    Raw PDO value

union pd_fixed_supply_pdo_sink
    #include <usbc_pd.h> Create a Fixed Supply PDO Sink value See Table 6-14 Fixed Supply PDO - Sink.

Public Members

uint32_t operational_current
    Operational Current in 10mA units

uint32_t voltage
    Voltage in 50mV units

uint32_t reserved0
    Reserved – Shall be set to zero.

dual_role_data
    Dual-Role Data

uint32_t usb_comms_capable
    USB Communications Capable

uint32_t unconstrained_power
    Unconstrained Power

uint32_t higher_capability
    Higher Capability
```


```c
uint32_t dual_role_power

    Dual-Role Power

enum pdo_type type
    Fixed supply. SET TO PDO_FIXED

struct pd_fixed_supply_pdo_sink.

uint32_t raw_value
    Raw PDO value

union pd_variable_supply_pdo_source
    #include <usbc_pd.h> Create a Variable Supply PDO Source value See Table 6-11 Variable Supply (non-Battery) PDO - Source.

Public Members

uint32_t max_current
    Maximum Current in 10mA units

uint32_t min_voltage
    Minimum Voltage in 50mV units

uint32_t max_voltage
    Maximum Voltage in 50mV units

enum pdo_type type
    Variable supply. SET TO PDO_VARIABLE

struct pd_variable_supply_pdo_source.

uint32_t raw_value
    Raw PDO value

union pd_variable_supply_pdo_sink
    #include <usbc_pd.h> Create a Variable Supply PDO Sink value See Table 6-15 Variable Supply (non-Battery) PDO - Sink.

Public Members

uint32_t operational_current
    operational Current in 10mA units

uint32_t min_voltage
    Minimum Voltage in 50mV units
```

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```c
uint32_t max_voltage
    Maximum Voltage in 50mV units

enum pdo_type type
    Variable supply. SET TO PDO_VARIABLE

struct pd_variable_supply_pdo_sink
    Raw PDO value

union pd_battery_supply_pdo_source
    #include <usbc_pd.h> Create a Battery Supply PDO Source value See Table 6-12 Battery Supply PDO - Source.

Public Members

uint32_t max_power
    Maximum Allowable Power in 250mW units

uint32_t min_voltage
    Minimum Voltage in 50mV units

uint32_t max_voltage
    Maximum Voltage in 50mV units

enum pdo_type type
    Battery supply. SET TO PDO_BATTERY

struct pd_battery_supply_pdo_source
    Raw PDO value

union pd_battery_supply_pdo_sink
    #include <usbc_pd.h> Create a Battery Supply PDO Sink value See Table 6-16 Battery Supply PDO - Sink.

Public Members

uint32_t operational_power
    Operational Power in 250mW units

uint32_t min_voltage
    Minimum Voltage in 50mV units
```
```c
#include <usbc_pd.h>  // Create Augmented Supply PDO Source value
// See Table 6-13 Programmable Power Supply APDO - Source.

Public Members

uint32_t max_current
  Maximum Current in 50mA increments

uint32_t reserved0
  Reserved – Shall be set to zero

uint32_t min_voltage
  Minimum Voltage in 100mV increments

uint32_t reserved1
  Reserved – Shall be set to zero

uint32_t max_voltage
  Maximum Voltage in 100mV increments

uint32_t reserved2
  Reserved – Shall be set to zero

uint32_t pps_power_limited
  PPS Power Limited

uint32_t reserved3
  00b – Programmable Power Supply 01b...11b - Reserved, Shall Not be used Setting as
  reserved because it defaults to 0 when not set.

enum pdo_type type
  Augmented Power Data Object (APDO). SET TO PDO_AUGMENTED
```

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uint32_t raw_value
   Raw PDO value

union pd_augmented_supply PDO_sink
   #include <usbc_pd.h> Create Augmented Supply PDO Sink value See Table 6-17 Programmable Power Supply APDO - Sink.

Public Members

uint32_t max_current
   Maximum Current in 50mA increments

uint32_t reserved0
   Reserved – Shall be set to zero

uint32_t min_voltage
   Minimum Voltage in 100mV increments

uint32_t reserved1
   Reserved – Shall be set to zero

uint32_t max_voltage
   Maximum Voltage in 100mV increments

uint32_t reserved2
   Reserved – Shall be set to zero

uint32_t reserved3
   00b – Programmable Power Supply 01b...11b - Reserved, Shall Not be used Setting as reserved because it defaults to 0 when not set.

enum pdo_type type
   Augmented Power Data Object (APDO). SET TO PDO_AUGMENTED

struct pd_augmented_supply PDO_sink.

uint32_t raw_value
   Raw PDO value

union pd_rdo
   #include <usbc_pd.h> The Request Data Object (RDO) Shall be returned by the Sink making a request for power. See Section 6.4.2 Request Message.

Public Members

uint32_t min_or_max_operating_current
   Operating Current 10mA units NOTE: If Give Back Flag is zero, this field is the Maximum Operating Current. If Give Back Flag is one, this field is the Minimum Operating Current.
```c
uint32_t operating_current
    Operating current in 10mA units
    Operating Current 50mA units

uint32_t reserved0
    Reserved - Shall be set to zero.

uint32_t unchunked_ext_msg_supported
    Unchunked Extended Messages Supported

uint32_t no_usb_suspend
    No USB Suspend

uint32_t usb_comm_capable
    USB Communications Capable

uint32_t cap_mismatch
    Capability Mismatch

uint32_t giveback
    Give Back Flag

uint32_t object_pos
    Object Position (000b is Reserved and Shall Not be used)

uint32_t reserved1
    Reserved - Shall be set to zero.

struct pd_rdo.[anonymous] fixed
    Create a Fixed RDO value See Table 6-19 Fixed and Variable Request Data Object.

struct pd_rdo.[anonymous] variable
    Create a Variable RDO value See Table 6-19 Fixed and Variable Request Data Object.

uint32_t min_operating_power
    Minimum Operating Power in 250mW units

uint32_t operating_power
    Operating power in 250mW units

struct pd_rdo.[anonymous] battery
    Create a Battery RDO value See Table 6-20 Battery Request Data Object.

uint32_t output_voltage
    Output Voltage in 20mV units

uint32_t reserved2
    Reserved - Shall be set to zero
```

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uint32_t reserved3
    Reserved - Shall be set to zero.

struct pd_rdo[anonymous] augmented
    Create an Augmented RDO value See Table 6-22 Programmable Request Data Object.

uint32_t raw_value
    Raw RDO value

struct pd_msg
    #include <usbc_pd.h> Power Delivery message.

Public Members

datatype pd_packet_type type
    Type of this packet

union pd_header header
    Header of this message

uint32_t len
    Length of bytes in data

uint8_t data[260]
    Message data

7.3.37 UART

Overview

Zephyr provides three different ways to access the UART peripheral. Depending on the method, different API functions are used according to below sections:

1. Polling API
2. Interrupt-driven API
3. Asynchronous API using DMA

Polling is the most basic method to access the UART peripheral. The reading function, uart_poll_in, is a non-blocking function and returns a character or -1 when no valid data is available. The writing function, uart_poll_out, is a blocking function and the thread waits until the given character is sent.

With the Interrupt-driven API, possibly slow communication can happen in the background while the thread continues with other tasks. The Kernel’s Data Passing features can be used to communicate between the thread and the UART driver.

The Asynchronous API allows to read and write data in the background using DMA without interrupting the MCU at all. However, the setup is more complex than the other methods.
Configuration Options

Most importantly, the Kconfig options define whether the polling API (default), the interrupt-driven API or the asynchronous API can be used. Only enable the features you need in order to minimize memory footprint.

Related configuration options:

- CONFIG_SERIAL
- CONFIG_UART_INTERRUPT_DRIVEN
- CONFIG_UART_ASYNC_API
- CONFIG_UART_WIDE_DATA
- CONFIG_UART_USE_RUNTIME_CONFIGURE
- CONFIG_UART_LINE_CTRL
- CONFIG_UART_DRV_CMD

API Reference

group uart_interface

   UART Interface.

 Enums

enum uart_line_ctrl
   Line control signals.

Values:

enumerator UART_LINE_CTRL_BAUD_RATE = BIT(0)
enumerator UART_LINE_CTRL_RTS = BIT(1)
enumerator UART_LINE_CTRL_DTR = BIT(2)
enumerator UART_LINE_CTRL_DCD = BIT(3)
enumerator UART_LINE_CTRL_DSR = BIT(4)

enum uart_rx_stop_reason
   Reception stop reasons.

Values that correspond to events or errors responsible for stopping receiving.

Values:

enumerator UART_ERROR_OVERRUN = (1 << 0)
   Overrun error.
enumerator UART_ERROR_PARITY = (1 << 1)
    Parity error.

denumerator UART_ERROR_FRAMING = (1 << 2)
    Framing error.

denumerator UART_BREAK = (1 << 3)
    Break interrupt.

    A break interrupt was received. This happens when the serial input is held at a logic ‘0’
    state for longer than the sum of start time + data bits + parity + stop bits.

denumerator UART_ERROR_COLLISION = (1 << 4)
    Collision error.

    This error is raised when transmitted data does not match received data. Typically this is
    useful in scenarios where the TX and RX lines maybe connected together such as RS-485
    half-duplex. This error is only valid on UARTs that support collision checking.

denum uart_config_parity
    Parity modes.

Values:

enumerator UART_CFG_PARITY_NONE
enumerator UART_CFG_PARITY_ODD
enumerator UART_CFG_PARITY_EVEN
enumerator UART_CFG_PARITY_MARK
enumerator UART_CFG_PARITY_SPACE

denum uart_config_stop_bits
    Number of stop bits.

Values:

enumerator UART_CFG_STOP_BITS_0_5
enumerator UART_CFG_STOP_BITS_1
enumerator UART_CFG_STOP_BITS_1_5
enumerator UART_CFG_STOP_BITS_2

denum uart_config_data_bits
    Number of data bits.

Values:
enumerator UART_CFG_DATA_BITS_5
enumerator UART_CFG_DATA_BITS_6
enumerator UART_CFG_DATA_BITS_7
enumerator UART_CFG_DATA_BITS_8
enumerator UART_CFG_DATA_BITS_9

enum uart_config_flow_control
Hardware flow control options.
With flow control set to none, any operations related to flow control signals can be managed by user with uart_line_ctrl functions. In other cases, flow control is managed by hardware/driver.

Values:

enumerator UART_CFG_FLOW_CTRL_NONE
enumerator UART_CFG_FLOW_CTRL_RTS_CTS
enumerator UART_CFG_FLOW_CTRL_DTR_DSR

Functions

int uart_err_check(const struct device *dev)
Check whether an error was detected.

Parameters
• dev – UART device instance.

Return values
• 0 – If no error was detected.
• err – Error flags as defined in uart_rx_stop_reason
• -ENOSYS – If not implemented.

int uart_configure(const struct device *dev, const struct uart_config *cfg)
Set UART configuration.
Sets UART configuration using data from *cfg.

Parameters
• dev – UART device instance.
• cfg – UART configuration structure.

Return values
• 0 – If successful.
• -errno – Negative errno code in case of failure.
- **-ENOSYS** – If configuration is not supported by device or driver does not support setting configuration in runtime.

```c
int uart_config_get(const struct device *dev, struct uart_config *cfg)
```

Get UART configuration.

Stores current UART configuration to `*cfg`, can be used to retrieve initial configuration after device was initialized using data from DTS.

**Parameters**
- `dev` – UART device instance.
- `cfg` – UART configuration structure.

**Return values**
- 0 – If successful.
- -errno – Negative errno code in case of failure.
- -ENOSYS – If driver does not support getting current configuration.

```c
int uart_line_ctrl_set(const struct device *dev, uint32_t ctrl, uint32_t val)
```

Manipulate line control for UART.

**Parameters**
- `dev` – UART device instance.
- `ctrl` – The line control to manipulate (see enum uart_line_ctrl).
- `val` – Value to set to the line control.

**Return values**
- 0 – If successful.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.
- -errno – Other negative errno value in case of failure.

```c
int uart_line_ctrl_get(const struct device *dev, uint32_t ctrl, uint32_t *val)
```

Retrieve line control for UART.

**Parameters**
- `dev` – UART device instance.
- `ctrl` – The line control to retrieve (see enum uart_line_ctrl).
- `val` – Pointer to variable where to store the line control value.

**Return values**
- 0 – If successful.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.
- -errno – Other negative errno value in case of failure.

```c
int uart_drv_cmd(const struct device *dev, uint32_t cmd, uint32_t p)
```

Send extra command to driver.

Implementation and accepted commands are driver specific. Refer to the drivers for more information.

**Parameters**
- `dev` – UART device instance.
• `cmd` – Command to driver.
• `p` – Parameter to the command.

**Return values**
• 0 – If successful.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.
• -errno – Other negative errno value in case of failure.

```c
struct uart_config

#include <uart.h> UART controller configuration structure.

**Param baudrate**
Baudrate setting in bps

**Param parity**
Parity bit, use `uart_config_parity`

**Param stop_bits**
Stop bits, use `uart_config_stop_bits`

**Param data_bits**
Data bits, use `uart_config_data_bits`

**Param flow_ctrl**
Flow control setting, use `uart_config_flow_control`
```

**Polling API**

```c
group uart_polling

**Functions**

```c
int uart_poll_in(const struct device *dev, unsigned char *p_char)
```

Read a character from the device for input.

This routine checks if the receiver has valid data. When the receiver has valid data, it reads a character from the device, stores to the location pointed to by `p_char`, and returns 0 to the calling thread. It returns -1, otherwise. This function is a non-blocking call.

**Parameters**
• `dev` – UART device instance.
• `p_char` – Pointer to character.

**Return values**
• 0 – If a character arrived.
• -1 – If no character was available to read (i.e. the UART input buffer was empty).
• -ENOSYS – If the operation is not implemented.
• -EBUSY – If async reception was enabled using `uart_rx_enable`
int uart_poll_in_u16(const struct device *dev, uint16_t *p_u16)

Read a 16-bit datum from the device for input.

This routine checks if the receiver has valid data. When the receiver has valid data, it reads a 16-bit datum from the device, stores to the location pointed to by p_u16, and returns 0 to the calling thread. It returns -1, otherwise. This function is a non-blocking call.

Parameters

• dev – UART device instance.
• p_u16 – Pointer to 16-bit data.

Return values

• 0 – If data arrived.
• -1 – If no data was available to read (i.e., the UART input buffer was empty).
• -ENOTSUP – If API is not enabled.
• -ENOSYS – If the function is not implemented.
• -EBUSY – If async reception was enabled using uart_rx_enable

void uart_poll_out(const struct device *dev, unsigned char out_char)

Write a character to the device for output.

This routine checks if the transmitter is full. When the transmitter is not full, it writes a character to the data register. It waits and blocks the calling thread, otherwise. This function is a blocking call.

To send a character when hardware flow control is enabled, the handshake signal CTS must be asserted.

Parameters

• dev – UART device instance.
• out_char – Character to send.

void uart_poll_out_u16(const struct device *dev, uint16_t out_u16)

Write a 16-bit datum to the device for output.

This routine checks if the transmitter is full. When the transmitter is not full, it writes a 16-bit datum to the data register. It waits and blocks the calling thread, otherwise. This function is a blocking call.

To send a datum when hardware flow control is enabled, the handshake signal CTS must be asserted.

Parameters

• dev – UART device instance.
• out_u16 – Wide data to send.

Interrupt-driven API

group uart_interrupt

Typedefs
typedef void (*uart_irq_callback_user_data_t)(const struct device *dev, void *user_data)

Define the application callback function signature for uart_irq_callback_user_data_set() function.

**Param dev**

UART device instance.

**Param user_data**

Arbitrary user data.

typedef void (*uart_irq_config_func_t)(const struct device *dev)

For configuring IRQ on each individual UART device.

**Param dev**

UART device instance.

**Functions**

static inline int uart_fifo_fill(const struct device *dev, const uint8_t *tx_data, int size)

Fill FIFO with data.

This function is expected to be called from UART interrupt handler (ISR), if uart_irq_tx_ready() returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). Likewise, not calling this function from an ISR if uart_irq_tx_ready() returns true may lead to undefined behavior, e.g. infinite interrupt loops. It's mandatory to test return value of this function, as different hardware has different FIFO depth (oftentimes just 1).

**Parameters**

- dev – UART device instance.
- tx_data – Data to transmit.
- size – Number of bytes to send.

**Return values**

- -ENOSYS – if this function is not supported
- -ENOTSUP – If API is not enabled.

**Returns**

Number of bytes sent.

static inline int uart_fifo_fill_u16(const struct device *dev, const uint16_t *tx_data, int size)

Fill FIFO with wide data.

This function is expected to be called from UART interrupt handler (ISR), if uart_irq_tx_ready() returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). Likewise, not calling this function from an ISR if uart_irq_tx_ready() returns true may lead to undefined behavior, e.g. infinite interrupt loops. It's mandatory to test return value of this function, as different hardware has different FIFO depth (oftentimes just 1).

**Parameters**

- dev – UART device instance.
- tx_data – Wide data to transmit.
- size – Number of datum to send.

**Return values**
• -ENOSYS – If this function is not implemented
• -ENOTSUP – If API is not enabled.

### Returns
Number of datum sent.

```
static inline int uart_fifo_read(const struct device *dev, uint8_t *rx_data, const int size)
```

Read data from FIFO.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_rx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). It’s unspecified whether “RX ready” condition as returned by `uart_irq_rx_ready()` is level- or edge- triggered. That means that once `uart_irq_rx_ready()` is detected, `uart_fifo_read()` must be called until it reads all available data in the FIFO (i.e. until it returns less data than was requested).

Note that the calling context only applies to physical UARTs and no to the virtual ones found in USB CDC ACM code.

### Parameters
- `dev` – UART device instance.
- `rx_data` – Data container.
- `size` – Container size.

### Return values
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

### Returns
Number of bytes read.

```
static inline int uart_fifo_read_u16(const struct device *dev, uint16_t *rx_data, const int size)
```

Read wide data from FIFO.

This function is expected to be called from UART interrupt handler (ISR), if `uart_irq_rx_ready()` returns true. Result of calling this function not from an ISR is undefined (hardware-dependent). It’s unspecified whether “RX ready” condition as returned by `uart_irq_rx_ready()` is level- or edge- triggered. That means that once `uart_irq_rx_ready()` is detected, `uart_fifo_read()` must be called until it reads all available data in the FIFO (i.e. until it returns less data than was requested).

Note that the calling context only applies to physical UARTs and no to the virtual ones found in USB CDC ACM code.

### Parameters
- `dev` – UART device instance.
- `rx_data` – Wide data container.
- `size` – Container size.

### Return values
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

### Returns
Number of datum read.

```
void uart_irq_tx_enable(const struct device *dev)
```

Enable TX interrupt in IER.
Parameters

- `dev` – UART device instance.

```c
void uart_irq_tx_disable(const struct device *dev)
```

Disable TX interrupt in IER.

Parameters

- `dev` – UART device instance.

```c
static inline int uart_irq_tx_ready(const struct device *dev)
```

Check if UART TX buffer can accept a new char.

Check if UART TX buffer can accept at least one character for transmission (i.e. `uart_fifo_fill()` will succeed and return non-zero). This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, `uart_irq_update()` must be called once per the handler invocation.

Parameters

- `dev` – UART device instance.

Return values

- 1 – If TX interrupt is enabled and at least one char can be written to UART.
- 0 – If device is not ready to write a new byte.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

```c
void uart_irq_rx_enable(const struct device *dev)
```

Enable RX interrupt.

Parameters

- `dev` – UART device instance.

```c
void uart_irq_rx_disable(const struct device *dev)
```

Disable RX interrupt.

Parameters

- `dev` – UART device instance.

```c
static inline int uart_irq_tx_complete(const struct device *dev)
```

Check if UART TX block finished transmission.

Check if any outgoing data buffered in UART TX block was fully transmitted and TX block is idle. When this condition is true, UART device (or whole system) can be power off. Note that this function is not useful to check if UART TX can accept more data, use `uart_irq_tx_ready()` for that. This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, `uart_irq_update()` must be called once per the handler invocation.

Parameters

- `dev` – UART device instance.

Return values

- 1 – If nothing remains to be transmitted.
- 0 – If transmission is not completed.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.
static inline int uart_irq_rx_ready(const struct device *dev)
    
    Check if UART RX buffer has a received char. Check if UART RX buffer has at least one pending character (i.e. uart_fifo_read() will succeed and return non-zero). This function must be called in a UART interrupt handler, or its result is undefined. Before calling this function in the interrupt handler, uart_irq_update() must be called once per the handler invocation. It's unspecified whether condition as returned by this function is level- or edge- triggered (i.e. if this function returns true when RX FIFO is non-empty, or when a new char was received since last call to it). See description of uart_fifo_read() for implication of this.

Parameters

- dev – UART device instance.

Return values

- 1 – If a received char is ready.
- 0 – If a received char is not ready.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

void uart_irq_err_enable(const struct device *dev)
    
    Enable error interrupt.

Parameters

- dev – UART device instance.

void uart_irq_err_disable(const struct device *dev)
    
    Disable error interrupt.

Parameters

- dev – UART device instance.

int uart_irq_is_pending(const struct device *dev)
    
    Check if any IRQs is pending.

Parameters

- dev – UART device instance.

Return values

- 1 – If an IRQ is pending.
- 0 – If an IRQ is not pending.
- -ENOSYS – If this function is not implemented.
- -ENOTSUP – If API is not enabled.

int uart_irq_update(const struct device *dev)
    
    Start processing interrupts in ISR.

This function should be called the first thing in the ISR. Calling uart_irq_rx_ready(), uart_irq_tx_ready(), uart_irq_tx_complete() allowed only after this.

The purpose of this function is:

- For devices with auto-acknowledge of interrupt status on register read to cache the value of this register (rx_ready, etc. then use this case).
- For devices with explicit acknowledgment of interrupts, to ack any pending interrupts and likewise to cache the original value.
• For devices with implicit acknowledgment, this function will be empty. But the ISR must perform the actions needs to ack the interrupts (usually, call `uart_fifo_read()` on rx_ready, and `uart_fifo_fill()` on tx_ready).

**Parameters**

• dev – UART device instance.

**Return values**

• 1 – On success.
• -ENOSYS – If this function is not implemented.
• -ENOTSUP – If API is not enabled.

```c
static inline void uart_irq_callback_user_data_set(const struct device *dev, uart_irq_callback_user_data_t cb, void *user_data)
```

Set the IRQ callback function pointer.

This sets up the callback for IRQ. When an IRQ is triggered, the specified function will be called with specified user data. See description of `uart_irq_update()` for the requirements on ISR.

**Parameters**

• dev – UART device instance.
• cb – Pointer to the callback function.
• user_data – Data to pass to callback function.

```c
static inline void uart_irq_callback_set(const struct device *dev, uart_irq_callback_user_data_t cb)
```

Set the IRQ callback function pointer (legacy).

This sets up the callback for IRQ. When an IRQ is triggered, the specified function will be called with the device pointer.

**Parameters**

• dev – UART device instance.
• cb – Pointer to the callback function.

**Asynchronous API**

group uart_async

**Typedefs**

typedef void (*uart_callback_t)(const struct device *dev, struct uart_event *evt, void *user_data)

Define the application callback function signature for `uart_callback_set()` function.

**Param dev**

UART device instance.

**Param evt**

Pointer to `uart_event` instance.

**Param user_data**

Pointer to data specified by user.
Enums

enum uart_event_type

Types of events passed to callback in UART_ASYNC_API.

Receiving:

a. To start receiving, uart_rx_enable has to be called with first buffer
b. When receiving starts to current buffer, UART_RX_BUF_REQUEST will be generated, in response to that user can either:
   • Provide second buffer using uart_rx_buf_rsp, when first buffer is filled, receiving will automatically start to second buffer.
   • Ignore the event, this way when current buffer is filled UART_RX_RDY event will be generated and receiving will be stopped.
c. If some data was received and timeout occurred UART_RX_RDY event will be generated. It can happen multiples times for the same buffer. RX timeout is counted from last byte received i.e. if no data was received, there won’t be any timeout event.
d. After buffer is filled UART_RX_RDY will be generated, immediately followed by UART_RX_BUF_RELEASED indicating that current buffer is no longer used.
e. If there was second buffer provided, it will become current buffer and we start again at point 2. If no second buffer was specified receiving is stopped and UART_RX_DISABLED event is generated. After that whole process can be repeated.

Any time during reception UART_RX_STOPPED event can occur. if there is any data received, UART_RX_RDY event will be generated. It will be followed by UART_RX_BUF_RELEASED event for every buffer currently passed to driver and finally by UART_RX_DISABLED event.

Receiving can be disabled using uart_rx_disable, after calling that function, if there is any data received, UART_RX_RDY event will be generated. UART_RX_BUF_RELEASED event will be generated for every buffer currently passed to driver and finally UART_RX_DISABLED event will occur.

Transmitting:

a. Transmitting starts by uart_tx function.
b. If whole buffer was transmitted UART_TX_DONE is generated. If timeout occurred UART_TX_ABORTED will be generated.

Transmitting can be aborted using uart_tx_abort, after calling that function UART_TX_ABORTED event will be generated.

Values:

enumerator UART_TX_DONE

Whole TX buffer was transmitted.

enumerator UART_TX_ABORTED

Transmitting aborted due to timeout or uart_tx_abort call.

When flow control is enabled, there is a possibility that TX transfer won’t finish in the allotted time. Some data may have been transferred, information about it can be found in event data.

d. Any time during reception UART_RX_STOPPED event can occur. if there is any data received, UART_RX_RDY event will be generated. It will be followed by UART_RX_BUF_RELEASED event for every buffer currently passed to driver and finally by UART_RX_DISABLED event.

Receiving can be disabled using uart_rx_disable, after calling that function, if there is any data received, UART_RX_RDY event will be generated. UART_RX_BUF_RELEASED event will be generated for every buffer currently passed to driver and finally UART_RX_DISABLED event will occur.
• When RX timeout occurred, and data was stored in provided buffer. This can happen multiple times in the same buffer.
• When provided buffer is full.
• After `uart_rx_disable()`.
• After stopping due to external event (`UART_RX_STOPPED`).

enumerator UART_RX_BUF_REQUEST
Driver requests next buffer for continuous reception.

This event is triggered when receiving has started for a new buffer, i.e. it’s time to provide a next buffer for a seamless switchover to it. For continuous reliable receiving, user should provide another RX buffer in response to this event, using `uart_rx_buf_rsp` function. If `uart_rx_buf_rsp` is not called before current buffer is filled up, receiving will stop.

enumerator UART_RX_BUF_RELEASED
Buffer is no longer used by UART driver.

enumerator UART_RX_DISABLED
RX has been disabled and can be reenabled.

This event is generated whenever receiver has been stopped, disabled or finished its operation and can be enabled again using `uart_rx_enable`.

enumerator UART_RX_STOPPED
RX has stopped due to external event.

Reason is one of `uart_rx_stop_reason`.

Functions

static inline int uart_callback_set(const struct device *dev, uart_callback_t callback, void *user_data)
Set event handler function.

Since it is mandatory to set callback to use other asynchronous functions, it can be used to detect if the device supports asynchronous API. Remaining API does not have that detection.

Parameters

• `dev` – UART device instance.
• `callback` – Event handler.
• `user_data` – Data to pass to event handler function.

Return values

• 0 – If successful.
• -ENOSYS – If not supported by the device.
• -ENOTSUP – If API not enabled.

int uart_tx(const struct device *dev, const uint8_t *buf, size_t len, int32_t timeout)
Send given number of bytes from buffer through UART.

Function returns immediately and event handler, set using `uart_callback_set`, is called after transfer is finished.

Parameters

• `dev` – UART device instance.
• `buf` – Pointer to transmit buffer.
• `len` – Length of transmit buffer.
• `timeout` – Timeout in microseconds. Valid only if flow control is enabled. SYS_FOREVER_US disables timeout.

**Return values**
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EBUSY – If there is already an ongoing transfer.
• -errno – Other negative errno value in case of failure.

```c
int uart_tx_u16(const struct device *dev, const uint16_t *buf, size_t len, int32_t timeout)
```

Send given number of datum from buffer through UART.

Function returns immediately and event handler, set using `uart_callback_set`, is called after transfer is finished.

**Parameters**
• `dev` – UART device instance.
• `buf` – Pointer to wide data transmit buffer.
• `len` – Length of wide data transmit buffer.
• `timeout` – Timeout in milliseconds. Valid only if flow control is enabled. SYS_FOREVER_MS disables timeout.

**Return values**
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EBUSY – If there is already an ongoing transfer.
• -errno – Other negative errno value in case of failure.

```c
int uart_tx_abort(const struct device *dev)
```

Abort current TX transmission.

`UART_TX_DONE` event will be generated with amount of data sent.

**Parameters**
• `dev` – UART device instance.

**Return values**
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EFAULT – There is no active transmission.
• -errno – Other negative errno value in case of failure.

```c
int uart_rx_enable(const struct device *dev, uint8_t *buf, size_t len, int32_t timeout)
```

Start receiving data through UART.

Function sets given buffer as first buffer for receiving and returns immediately. After that event handler, set using `uart_callback_set`, is called with `UART_RX_RDY` or `UART_RX_BUF_REQUEST` events.

**Parameters**
• `dev` – UART device instance.
buf – Pointer to receive buffer.
len – Buffer length.

timeout – Inactivity period after receiving at least a byte which triggers UART_RX_RDY event. Given in microseconds. SYS_FOREVER_US disables timeout. See uart_event_type for details.

Return values
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EBUSY – RX already in progress.
• -errno – Other negative errno value in case of failure.

static inline int uart_rx_buf_rsp(const struct device *dev, uint8_t *buf, size_t len)

Provide receive buffer in response to UART_RX_BUF_REQUEST event. Provide pointer to RX buffer, which will be used when current buffer is filled.

Note: Providing buffer that is already in usage by driver leads to undefined behavior. Buffer can be reused when it has been released by driver.

Parameters
• dev – UART device instance.
• buf – Pointer to receive buffer.
• len – Buffer length.

Return values
• 0 – If successful.
• -ENOTSUP – If API is not enabled.
• -EBUSY – Next buffer already set.
- **EACCES** – Receiver is already disabled (function called too late?).
- **-errno** – Other negative errno value in case of failure.

static inline int uart_rx_buf_rsp_u16(const struct device *dev, uint16_t *buf, size_t len)

Provide wide data receive buffer in response to `UART_RX_BUF_REQUEST` event.
Provide pointer to RX buffer, which will be used when current buffer is filled.

**Note:** Providing buffer that is already in usage by driver leads to undefined behavior. Buffer can be reused when it has been released by driver.

**Parameters**

- **dev** – UART device instance.
- **buf** – Pointer to wide data receive buffer.
- **len** – Buffer length.

**Return values**

- **0** – If successful.
- **-ENOTSUP** – If API is not enabled
- **-EBUSY** – Next buffer already set.
- **-EACCES** – Receiver is already disabled (function called too late?).
- **-errno** – Other negative errno value in case of failure.

```c
int uart_rx_disable(const struct device *dev)
```

Disable RX.

`UART_RX_BUF_RELEASED` event will be generated for every buffer scheduled, after that `UART_RX_DISABLED` event will be generated. Additionally, if there is any pending received data, the `UART_RX_RDY` event for that data will be generated before the `UART_RX_BUF_RELEASED` events.

**Parameters**

- **dev** – UART device instance.

**Return values**

- **0** – If successful.
- **-ENOTSUP** – If API is not enabled.
- **-EFAULT** – There is no active reception.
- **-errno** – Other negative errno value in case of failure.

```c
struct uart_event_tx
```

#include `<uart.h>` UART TX event data.

**Public Members**

```c
const uint8_t *buf
```

Pointer to current buffer.
size_t len
   Number of bytes sent.

struct uart_event_rx
   #include <uart.h> UART RX event data.
   The data represented by the event is stored in rx.buf[rx.offset] to rx.buf[rx.offset+rx.len].
   That is, the length is relative to the offset.

Public Members

uint8_t *buf
   Pointer to current buffer.

size_t offset
   Currently received data offset in bytes.

size_t len
   Number of new bytes received.

struct uart_event_rx_buf
   #include <uart.h> UART RX buffer released event data.

struct uart_event_rx_stop
   #include <uart.h> UART RX stopped data.

Public Members

denum uart_rx_stop_reason reason
   Reason why receiving stopped.

struct uart_event_rx data
   Last received data.

struct uart_event
   #include <uart.h> Structure containing information about current event.

Public Members

enum uart_event_type type
   Type of event.

union uart_event_data
   #include <uart.h> Event data.
Public Members

struct uart_event_tx tx
    UART_TX_DONE and UART_TX_ABORTED events data.

struct uart_event_rx rx
    UART_RX_RDY event data.

struct uart_event_rx_buf rx_buf
    UART_RX_BUFRELEASED event data.

struct uart_event_rx_stop rx_stop
    UART_RX_STOPPED event data.

7.3.38 USB-C VBUS

Overview

USB-C VBUS is the line in a USB Type-C connection that delivers power from a Source to a Sink device.

USB-C VBUS API The USB-C VBUS device driver presents an API that’s used to control and measure VBUS.

Configuration Options

Related configuration options:

• CONFIG_USBC_VBUS_DRIVER

API Reference

group usbc_vbus_api
    USB-C VBUS API.

Functions

static inline bool usbc_vbus_check_level(const struct device *dev, enum tc_vbus_level level)
    Checks if VBUS is at a particular level.

Parameters

• dev – Runtime device structure
• level – The level voltage to check against

Return values

• true – if VBUS is at the level voltage
• false – if VBUS is not at that level voltage
static inline int usbc_vbus_measure(const struct device *dev, int *meas)

Reads and returns VBUS measured in mV.

**Parameters**

- `dev` – Runtime device structure
- `meas` – pointer where the measured VBUS voltage is stored

**Return values**

- 0 – on success
- -EIO – on failure

static inline int usbc_vbus_discharge(const struct device *dev, bool enable)

Controls a pin that discharges VBUS.

**Parameters**

- `dev` – Runtime device structure
- `enable` – Discharge VBUS when true

**Return values**

- 0 – on success
- -EIO – on failure
- -ENOENT – if discharge pin isn’t defined

static inline int usbc_vbus_enable(const struct device *dev, bool enable)

Controls a pin that enables VBUS measurements.

**Parameters**

- `dev` – Runtime device structure
- `enable` – enable VBUS measurements when true

**Return values**

- 0 – on success
- -EIO – on failure
- -ENOENT – if enable pin isn’t defined

```c
#include <usbc_vbus.h>
```

#7.3.39 MDIO

**Overview**

MDIO is a bus that is commonly used to communicate with ethernet PHY devices. Many ethernet MAC controllers also provide hardware to communicate over MDIO bus with a peripheral device.

This API is intended to be used primarily by PHY drivers but can also be used by user firmware.

**API Reference**

```c
group mdio_interface
    MDIO Interface.
```
Functions

void mdio_bus_enable(const struct device *dev)
    Enable MDIO bus.

Parameters
    • dev – [in] Pointer to the device structure for the controller

void mdio_bus_disable(const struct device *dev)
    Disable MDIO bus and tri-state drivers.

Parameters
    • dev – [in] Pointer to the device structure for the controller

int mdio_read(const struct device *dev, uint8_t prtad, uint8_t devad, uint16_t *data)
    Read from MDIO Bus.
    This routine provides a generic interface to perform a read on the MDIO bus.

Parameters
    • dev – [in] Pointer to the device structure for the controller
    • prtad – [in] Port address
    • devad – [in] Device address
    • data – Pointer to receive read data

Return values
    • 0 – If successful.
    • -EIO – General input / output error.
    • -ETIMEDOUT – If transaction timed out on the bus

int mdio_write(const struct device *dev, uint8_t prtad, uint8_t devad, uint16_t data)
    Write to MDIO Bus.
    This routine provides a generic interface to perform a write on the MDIO bus.

Parameters
    • dev – [in] Pointer to the device structure for the controller
    • prtad – [in] Port address
    • devad – [in] Device address
    • data – [in] Data to write

Return values
    • 0 – If successful.
    • -EIO – General input / output error.
    • -ETIMEDOUT – If transaction timed out on the bus

7.3.40 Watchdog

Overview

API Reference
group watchdog_interface

Watchdog Interface.

Watchdog options

WDT_OPT_PAUSE_IN_SLEEP
   Pause watchdog timer when CPU is in sleep state.

WDT_OPT_PAUSE_HALTED_BY_DBG
   Pause watchdog timer when CPU is halted by the debugger.

Watchdog behavior flags

WDT_FLAG_RESET_NONE
   Reset: none

WDT_FLAG_RESET_CPU_CORE
   Reset: CPU core

WDT_FLAG_RESET_SOC
   Reset: SoC

Typedefs

typedef void (*wdt_callback_t)(const struct device *dev, int channel_id)
   Watchdog callback.

   Param dev
      Watchdog device instance.

   Param channel_id
      Channel identifier.

Functions

int wdt_setup(const struct device *dev, uint8_t options)
   Set up watchdog instance.
   This function is used for configuring global watchdog settings that affect all timeouts. It should be called after installing timeouts. After successful return, all installed timeouts are valid and must be serviced periodically by calling wdt_feed().

   Parameters
      • dev – Watchdog device instance.
      • options – Configuration options (see WDT_OPT).

   Return values
int wdt_disable(const struct device *dev)

Disable watchdog instance.

This function disables the watchdog instance and automatically uninstalls all timeouts. To set up a new watchdog, install timeouts and call wdt_setup() again. Not all watchdogs can be restarted after they are disabled.

Parameters
• dev – Watchdog device instance.

Return values
• 0 – If successful.
• -ENOTSUP – If any of the set options is not supported.
• -EBUSY – If watchdog instance has been already setup.
• -errno – In case of any other failure.

static inline int wdt_install_timeout(const struct device *dev, const struct wdt_timeout_cfg *cfg)

Install a new timeout.

Note: This function must be used before wdt_setup(). Changes applied here have no effects until wdt_setup() is called.

Parameters
• dev – Watchdog device instance.
• cfg – [in] Timeout configuration.

Return values
• channel_id – If successful, a non-negative value indicating the index of the channel to which the timeout was assigned. This value is supposed to be used as the parameter in calls to wdt_feed().
• -EBUSY – If timeout can not be installed while watchdog has already been setup.
• -ENOMEM – If no more timeouts can be installed.
• -ENOTSUP – If any of the set flags is not supported.
• -EINVAL – If any of the window timeout value is out of possible range. This value is also returned if watchdog supports only one timeout value for all timeouts and the supplied timeout window differs from windows for alarms installed so far.
• -errno – In case of any other failure.

int wdt_feed(const struct device *dev, int channel_id)

Feed specified watchdog timeout.

Parameters
• dev – Watchdog device instance.
• channel_id – Channel index.

**Return values**

• 0 – If successful.
• -EAGAIN – If completing the feed operation would stall the caller, for example due to an in-progress watchdog operation such as a previous `wdt_feed()` call.
• -EINVAL – If there is no installed timeout for supplied channel.
• -errno – In case of any other failure.

```c
struct wdt_window
    #include <watchdog.h> Watchdog timeout window.
```

Each installed timeout needs feeding within the specified time window, otherwise the watchdog will trigger. If the watchdog instance does not support window timeouts then min value must be equal to 0.

**Note:** If specified values can not be precisely set they are always rounded up.

### Public Members

```c
uint32_t min
    Lower limit of watchdog feed timeout in milliseconds.
```

```c
uint32_t max
    Upper limit of watchdog feed timeout in milliseconds.
```

```c
struct wdt_timeout_cfg
    #include <watchdog.h> Watchdog timeout configuration.
```

### Public Members

```c
struct wdt_window window
    Timing parameters of watchdog timeout.
```

```c
wdt_callback_t callback
    Timeout callback (can be NULL).
```

```c
struct wdt_timeout_cfg *next
    Pointer to the next timeout configuration.
```

This field is only available if `CONFIG_WDT_MULTISTAGE` is enabled (watchdogs with staged timeouts functionality). Value must be NULL for single stage timeout.

```c
uint8_t flags
    Flags (see `WDT_FLAGS`).
```

### 7.3.41 Video

The video driver API offers a generic interface to video devices.
Basic Operation

**Video Device** A video device is the abstraction of a hardware or software video function, which can produce, process, consume or transform video data. The video API is designed to offer flexible way to create, handle and combine various video devices.

**Endpoint** Each video device can have one or more endpoints. Output endpoints configure video output function and generate data. Input endpoints configure video input function and consume data.

**Video Buffer** A video buffer provides the transport mechanism for the data. There is no particular requirement on the content. The requirement for the content is defined by the endpoint format. A video buffer can be queued to a device endpoint for filling (input ep) or consuming (output ep) operation, once the operation is achieved, buffer can be dequeued for post-processing, release or reuse.

**Controls** A video control is accessed and identified by a CID (control identifier). It represents a video control property. Different devices will have different controls available which can be generic, related to a device class or vendor specific. The set/get control functions provide a generic scalable interface to handle and create controls.

**Configuration Options**

Related configuration options:

- `CONFIG_VIDEO`

**API Reference**

```c

*group* video_interface

Video Interface.

**Defines**

`video_fourcc(a, b, c, d)`

`VIDEO_PIX_FMT_BGGR8`

`VIDEO_PIX_FMT_GBRG8`

`VIDEO_PIX_FMT_GRBG8`

`VIDEO_PIX_FMT_RGGB8`

`VIDEO_PIX_FMT_RGB565`

`VIDEO_PIX_FMT_JPEG`
```
Typedefs

typedef int (*video_api_set_format_t)(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)

Set video format See video_set_format() for argument descriptions.

typedef int (*video_api_get_format_t)(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)

get current video format See video_get_format() for argument descriptions.

typedef int (*video_api_enqueue_t)(const struct device *dev, enum video_endpoint_id ep, struct video_buffer *buf)

Enqueue a buffer in the driver's incoming queue. See video_enqueue() for argument descriptions.

typedef int (*video_api_dequeue_t)(const struct device *dev, enum video_endpoint_id ep, struct video_buffer **buf, k_timeout_t timeout)

Dequeue a buffer from the driver's outgoing queue. See video_dequeue() for argument descriptions.

typedef int (*video_api_flush_t)(const struct device *dev, enum video_endpoint_id ep, bool cancel)

Flush endpoint buffers, buffer are moved from incoming queue to outgoing queue. See video_flush() for argument descriptions.

typedef int (*video_api_stream_start_t)(const struct device *dev)

Start the capture or output process. See video_stream_start() for argument descriptions.

typedef int (*video_api_stream_stop_t)(const struct device *dev)

Stop the capture or output process. See video_stream_stop() for argument descriptions.

typedef int (*video_api_set_ctrl_t)(const struct device *dev, unsigned int cid, void *value)

set a video control value. See video_set_ctrl() for argument descriptions.

typedef int (*video_api_get_ctrl_t)(const struct device *dev, unsigned int cid, void *value)

get a video control value. See video_get_ctrl() for argument descriptions.

typedef int (*video_api_get_caps_t)(const struct device *dev, enum video_endpoint_id ep, struct video_caps *caps)

Get capabilities of a video endpoint. See video_get_caps() for argument descriptions.

typedef int (*video_api_set_signal_t)(const struct device *dev, enum video_endpoint_id ep, struct k_poll_signal *signal)

Register/Unregister poll signal for buffer events. See video_set_signal() for argument descriptions.

Enums

enum video_endpoint_id

video_endpoint_id enum Identify the video device endpoint.

Values:
enumerator VIDEO_EP_NONE
enumerator VIDEO_EP_ANY
enumerator VIDEO_EP_IN
enumerator VIDEO_EP_OUT

enum video_signal_result
  video_event enum Identify video event.
  Values:
  enumerator VIDEO_BUF_DONE
  enumerator VIDEO_BUF_ABORTED
  enumerator VIDEO_BUF_ERROR

Functions

static inline int video_set_format(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)
  Set video format.
  Configure video device with a specific format.
  Parameters
  • dev – Pointer to the device structure for the driver instance.
  • ep – Endpoint ID.
  • fmt – Pointer to a video format struct.
  Return values
  • 0 – Is successful.
  • -EINVAL – If parameters are invalid.
  • -ENOTSUP – If format is not supported.
  • -EIO – General input / output error.

static inline int video_get_format(const struct device *dev, enum video_endpoint_id ep, struct video_format *fmt)
  Get video format.
  Get video device current video format.
  Parameters
  • dev – Pointer to the device structure for the driver instance.
  • ep – Endpoint ID.
  • fmt – Pointer to video format struct.
  Return values
  pointer – to video format
static inline int video_enqueue(const struct device *dev, enum video_endpoint_id ep, struct video_buffer *buf)

Enqueue a video buffer.
Enqueue an empty (capturing) or filled (output) video buffer in the driver's endpoint incoming queue.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `ep` – Endpoint ID.
- `buf` – Pointer to the video buffer.

**Return values**

- 0 – Is successful.
- -EINVAL – If parameters are invalid.
- -EIO – General input / output error.

static inline int video_dequeue(const struct device *dev, enum video_endpoint_id ep, struct video_buffer **buf, k_timeout_t timeout)

Dequeue a video buffer.
Dequeue a filled (capturing) or displayed (output) buffer from the driver's endpoint outgoing queue.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `ep` – Endpoint ID.
- `buf` – Pointer a video buffer pointer.
- `timeout` – Timeout

**Return values**

- 0 – Is successful.
- -EINVAL – If parameters are invalid.
- -EIO – General input / output error.

static inline int video_flush(const struct device *dev, enum video_endpoint_id ep, bool cancel)

Flush endpoint buffers.
A call to flush finishes when all endpoint buffers have been moved from incoming queue to outgoing queue. Either because canceled or fully processed through the video function.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `ep` – Endpoint ID.
- `cancel` – If true, cancel buffer processing instead of waiting for completion.

**Return values**

0 – Is successful, -ERRNO code otherwise.

static inline int video_stream_start(const struct device *dev)

Start the video device function.
video_stream_start is called to enter ‘streaming’ state (capture, output...). The driver may receive buffers with `video_enqueue()` before `video_stream_start` is called. If driver/device needs a minimum number of buffers before being able to start streaming, then driver set the min_vbuf_count to the related endpoint capabilities.
Return values

• 0 – Is successful.
• -EIO – General input / output error.

static inline int video_stream_stop(const struct device *dev)
Stop the video device function.
On video_stream_stop, driver must stop any transactions or wait until they finish.

Return values

• 0 – Is successful.
• -EIO – General input / output error.

static inline int video_get_caps(const struct device *dev, enum video_endpoint_id ep, struct video_caps *caps)
Get the capabilities of a video endpoint.

Parameters

• dev – Pointer to the device structure for the driver instance.
• ep – Endpoint ID.
• caps – Pointer to the video_caps struct to fill.

Return values

0 – Is successful, -ERRNO code otherwise.

static inline int video_set_ctrl(const struct device *dev, unsigned int cid, void *value)
Set the value of a control.
This set the value of a video control, value type depends on control ID, and must be interpreted accordingly.

Parameters

• dev – Pointer to the device structure for the driver instance.
• cid – Control ID.
• value – Pointer to the control value.

Return values

• 0 – Is successful.
• -EINVAL – If parameters are invalid.
• -ENOTSUP – If format is not supported.
• -EIO – General input / output error.

static inline int video_get_ctrl(const struct device *dev, unsigned int cid, void *value)
Get the current value of a control.
This retrieve the value of a video control, value type depends on control ID, and must be interpreted accordingly.

Parameters

• dev – Pointer to the device structure for the driver instance.
• cid – Control ID.
• value – Pointer to the control value.

Return values

• 0 – Is successful.
static inline int video_set_signal(const struct device *dev, enum video_endpoint_id ep, struct k_poll_signal *signal)

Register/Unregister k_poll signal for a video endpoint.

Register a poll signal to the endpoint, which will be signaled on frame completion (done, aborted, error). Registering a NULL poll signal unregisters any previously registered signal.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ep – Endpoint ID.
• signal – Pointer to k_poll_signal

Return values
0 – Is successful, -ERRNO code otherwise.

struct video_buffer *video_buffer_alloc(size_t size)

Allocate video buffer.

Parameters
• size – Size of the video buffer.

Return values
pointer – to allocated video buffer

void video_buffer_release(struct video_buffer *buf)

Release a video buffer.

Parameters
• buf – Pointer to the video buffer to release.

struct video_format

#include <video.h> video format structure

Used to configure frame format.

Param pixelformat
is the fourcc pixel format value.

Param width
is the frame width in pixels.

Param height
is the frame height in pixels.

Param pitch
is the line stride, the number of bytes that needs to be added to the address in the first pixel of a row in order to go to the address of the first pixel of the next row (>=width).

struct video_format_cap

#include <video.h> video format capability

Used to describe a video endpoint format capability.

Param pixelformat
is a list of supported pixel formats (0 terminated).
Param width_min
is the minimum supported frame width.

Param width_max
is the maximum supported frame width.

Param height_min
is the minimum supported frame width.

Param height_max
is the maximum supported frame width.

Param width_step
is the width step size.

Param height_step
is the height step size.

struct video_caps
#include <video.h> video capabilities
Used to describe video endpoint capabilities.

Param format_caps
is a list of video format capabilities (zero terminated).

Param min_vbuf_count
is the minimal count of video buffers to enqueue before being able to start the stream.

struct video_buffer
#include <video.h> video buffer structure
Represent a video frame.

Param driver_data
is a pointer to driver specific data.

Param buffer
is a pointer to the start of the buffer.

Param size
is the size in bytes of the buffer.

Param bytesused
is the number of bytes occupied by the valid data in the buffer.

Param timestamp
is a time reference in milliseconds at which the last data byte was actually received for input endpoints or to be consumed for output endpoints.

struct video_driver_api
#include <video.h>

group video_controls
Video controls.

Defines

VIDEO_CTRL_CLASS_GENERIC
7.3.42  eSPI

Overview

The eSPI (enhanced serial peripheral interface) is a serial bus that is based on SPI. It also features a four-wire interface (receive, transmit, clock and slave select) and three configurations: single IO, dual IO and quad IO.

The technical advancements include lower voltage signal levels (1.8V vs. 3.3V), lower pin count, and the frequency is twice as fast (66MHz vs. 33MHz) Because of its enhancements, the eSPI is used to replace the LPC (lower pin count) interface, SPI, SMBus and sideband signals.

See eSPI interface specification for additional details.

API Reference

7.3.  Peripherals
group espi_interface

  eSPI Driver APIs
  eSPI SAF Driver APIs

Defines

HOST_KBC_EVT_IBF

HOST_KBC_EVT_OBE

Typedefs

typedef void (*espi_callback_handler_t)(const struct device *dev, struct espi_callback *cb, struct espi_event espi_evt)

  Define the application callback handler function signature.

  **Param dev**
  Device struct for the eSPI device.

  **Param cb**
  Original struct espi_callback owning this handler.

  **Param espi_evt**
  event details that trigger the callback handler.

Enums

enum espi_io_mode
  eSPI I/O mode capabilities

  **Values:**

  enumerator ESPI_IO_MODE_SINGLE_LINE = **BIT**(0)

  enumerator ESPI_IO_MODE_DUAL_LINES = **BIT**(1)

  enumerator ESPI_IO_MODE_QUAD_LINES = **BIT**(2)

enum espi_channel
  eSPI channel.

|--+-----------------------------+-----------------------------+-----------------------------|
| eSPI host | Power | GPIO |
| +---------+-------+------|
| Out of band | management | sources |
| +---------+-------+------|
| SPI flash | processor | controller |
| +---------+-------+------|

(continues on next page)
Identifies each eSPI logical channel supported by eSPI controller. Each channel allows independent traffic, but the assignment of channel type to channel number is fixed.

Note that generic commands are not associated with any channel, so traffic over eSPI can occur if all channels are disabled or not ready.

Values:

enumerator ESPI_CHANNEL_PERIPHERAL = \textit{BIT}(0)

enumerator ESPI_CHANNEL_VWIRE = \textit{BIT}(1)

enumerator ESPI_CHANNEL_OOB = \textit{BIT}(2)

enumerator ESPI_CHANNEL_FLASH = \textit{BIT}(3)
eSPI bus event.
eSPI bus event to indicate events for which user can register callbacks

Values:

enumerator ESPI_BUS_RESET = BIT(0)
enumerator ESPI_BUS_EVENT_CHANNEL_READY = BIT(1)
enumerator ESPI_BUS_EVENT_VWIRE_RECEIVED = BIT(2)
enumerator ESPI_BUS_EVENT_OOB_RECEIVED = BIT(3)
enumerator ESPI_BUS_PERIPHERAL_NOTIFICATION = BIT(4)
enumerator ESPI_BUS_SAF_NOTIFICATION = BIT(5)

enum espi_pc_event
  eSPI peripheral channel events.
eSPI peripheral channel event types to indicate users.

Values:

enumerator ESPI_PC_EVT_BUS_CHANNEL_READY = BIT(0)
enumerator ESPI_PC_EVT_BUS_MASTER_ENABLE = BIT(1)

enum espi_virtual_peripheral
  eSPI peripheral notification type.
eSPI peripheral notification event details to indicate which peripheral trigger the eSPI callback

Values:

enumerator ESPI_PERIPHERAL_UART
enumerator ESPI_PERIPHERAL_8042_KBC
enumerator ESPI_PERIPHERAL_HOST_IO
enumerator ESPI_PERIPHERAL_DEBUG_PORT80
enumerator ESPI_PERIPHERAL_HOST_IO_PVT

enum espi_cycle_type
  eSPI cycle types supported over eSPI peripheral channel

Values:
enumerator ESPI_CYCLE_MEMORY_READ32
enumerator ESPI_CYCLE_MEMORY_READ64
enumerator ESPI_CYCLE_MEMORY_WRITE32
enumerator ESPI_CYCLE_MEMORY_WRITE64
enumerator ESPI_CYCLE_MESSAGE_NODATA
enumerator ESPI_CYCLE_MESSAGE_DATA
enumerator ESPI_CYCLE_OK_COMPLETION_NODATA
enumerator ESPI_CYCLE_OK_COMPLETION_DATA
enumerator ESPI_CYCLE_NOK_COMPLETION_NODATA

enum espi_vwire_signal
    eSPI system platform signals that can be send or receive through virtual wire channel

    Values:
    enumerator ESPI_VWIRE_SIGNAL_SLP_S3
    enumerator ESPI_VWIRE_SIGNAL_SLP_S4
    enumerator ESPI_VWIRE_SIGNAL_SLP_S5
    enumerator ESPI_VWIRE_SIGNAL_OOB_RST_WARN
    enumerator ESPI_VWIRE_SIGNAL_PLTRST
    enumerator ESPI_VWIRE_SIGNAL_SUS_STAT
    enumerator ESPI_VWIRE_SIGNAL_NMIOUT
    enumerator ESPI_VWIRE_SIGNAL_SMIOUT
    enumerator ESPI_VWIRE_SIGNAL_HOST_RST_WARN
    enumerator ESPI_VWIRE_SIGNAL_SLP_A
    enumerator ESPI_VWIRE_SIGNAL_SUS_PWRDN_ACK
    enumerator ESPI_VWIRE_SIGNAL_SUS_WARN

7.3. Peripherals 2417
enumerator ESPI_VWIRE_SIGNAL_SLP_WLAN
enumerator ESPI_VWIRE_SIGNAL_SLP_LAN
enumerator ESPI_VWIRE_SIGNAL_HOST_C10
enumerator ESPI_VWIRE_SIGNAL_DNX_WARN
enumerator ESPI_VWIRE_SIGNAL_PME
enumerator ESPI_VWIRE_SIGNAL_WAKE
enumerator ESPI_VWIRE_SIGNAL_OOB_RST_ACK
enumerator ESPI_VWIRE_SIGNAL_SLV_BOOT_STS
enumerator ESPI_VWIRE_SIGNAL_ERR_NON_FATAL
enumerator ESPI_VWIRE_SIGNAL_ERR_FATAL
enumerator ESPI_VWIRE_SIGNAL_SLV_BOOT_DONE
enumerator ESPI_VWIRE_SIGNAL_HOST_RST_ACK
enumerator ESPI_VWIRE_SIGNAL_RST_CPU_INIT
enumerator ESPI_VWIRE_SIGNAL_SMI
enumerator ESPI_VWIRE_SIGNAL_SCI
enumerator ESPI_VWIRE_SIGNAL_DNX_ACK
enumerator ESPI_VWIRE_SIGNAL_SUS_ACK
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_0
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_1
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_2
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_3
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_4
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_5
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_6
enumerator ESPI_VWIRE_SIGNAL_SLV_GPIO_7
enumerator ESPI_VWIRE_SIGNAL_OCB_0
enumerator ESPI_VWIRE_SIGNAL_OCB_1
enumerator ESPI_VWIRE_SIGNAL_OCB_2
enumerator ESPI_VWIRE_SIGNAL_OCB_3
enumerator ESPI_VWIRE_SIGNAL_COUNT

enum lpc_peripheral_opcode
  Values:
    enumerator E8042_OBF_HAS_CHAR = 0x50
    enumerator E8042_IBF_HAS_CHAR
    enumerator E8042_WRITE_KB_CHAR
    enumerator E8042_WRITE_MB_CHAR
    enumerator E8042_RESUME_IRQ
    enumerator E8042_PAUSE_IRQ
    enumerator E8042_CLEAR_OBF
    enumerator E8042_READ_KB_STS
    enumerator E8042_SET_FLAG
    enumerator E8042_CLEAR_FLAG
    enumerator EACPI_OBF_HAS_CHAR = EACPI_START_OPCODE
    enumerator EACPI_IBF_HAS_CHAR
    enumerator EACPI_WRITE_CHAR
    enumerator EACPI_READ_STS
    enumerator EACPI_WRITE_STS
Functions

```c
int espi_config(const struct device *dev, struct espi_cfg *cfg)
```

Configure operation of a eSPI controller.

This routine provides a generic interface to override eSPI controller capabilities.

If this eSPI controller is acting as slave, the values set here will be discovered as part through the GET_CONFIGURATION command issued by the eSPI master during initialization.

If this eSPI controller is acting as master, the values set here will be used by eSPI master to determine minimum common capabilities with eSPI slave then send via SET_CONFIGURATION command.

```
+--------+ +---------+ +------+ +---------+ +---------+
| eSPI | | eSPI | | eSPI | | eSPI | | eSPI |
| slave | | driver | | bus | | driver | | host |
+--------+ +---------+ +------+ +---------+ +---------+

<table>
<thead>
<tr>
<th>espi_config</th>
<th>Set eSPI</th>
<th>Set eSPI</th>
<th>espi_config</th>
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<tr>
<td>+------------+ ctrl regs</td>
<td>cap ctrl reg</td>
<td>+-----------</td>
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<tr>
<td>+---------+</td>
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<tr>
<td>GET_CONFIGURATION</td>
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| +-+--+-+---+--+-+--+-+--+-+--+-+--+-+--+-+--+-+--+-+--+-+--+-+--+-+
| eSPI caps |
| +------------+ response +------------+ |

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `cfg` – the device runtime configuration for the eSPI controller.

Return values

- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
- -EINVAL – invalid capabilities, failed to configure device.
- -ENOTSUP – capability not supported by eSPI slave.

```c
bool espi_get_channel_status(const struct device *dev, enum espi_channel ch)
```

Query to see if it a channel is ready.

This routine allows to check if logical channel is ready before use. Note that queries for channels not supported will always return false.

Parameters
• dev – Pointer to the device structure for the driver instance.
• ch – the eSPI channel for which status is to be retrieved.

Return values
• true – If eSPI channel is ready.
• false – otherwise.

int espi_read_request(const struct device *dev, struct espi_request_packet *req)
Sends memory, I/O or message read request over eSPI.

This routines provides a generic interface to send a read request packet.

Parameters
• dev – Pointer to the device structure for the driver instance.
• req – Address of structure representing a memory, I/O or message read request.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI controller doesn't support raw packets and instead low memory transactions are handled by controller hardware directly.
• -EIO – General input / output error, failed to send over the bus.

int espi_write_request(const struct device *dev, struct espi_request_packet *req)
Sends memory, I/O or message write request over eSPI.

This routines provides a generic interface to send a write request packet.

Parameters
• dev – Pointer to the device structure for the driver instance.
• req – Address of structure representing a memory, I/O or message write request.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI controller doesn't support raw packets and instead low memory transactions are handled by controller hardware directly.
• -EINVAL – General input / output error, failed to send over the bus.

int espi_read_lpc_request(const struct device *dev, enum lpc_peripheral_opcode op, uint32_t *data)
Reads SOC data from a LPC peripheral with information updated over eSPI.

This routine provides a generic interface to read a block whose information was updated by an eSPI transaction. Reading may trigger a transaction. The eSPI packet is assembled by the HW block.

Parameters
• dev – Pointer to the device structure for the driver instance.
• op – Enum representing opcode for peripheral type and read request.
• data – Parameter to be read from to the LPC peripheral.

Return values
• 0 – If successful.
• -ENOTSUP – if eSPI peripheral is off or not supported.
-EINVAL – for unimplemented lpc opcode, but in range.

```c
int espi_write_lpc_request(const struct device *dev, enum lpc_peripheral_opcode op, uint32_t *data)
```

Writes data to a LPC peripheral which generates an eSPI transaction.

This routine provides a generic interface to write data to a block which triggers an eSPI transaction. The eSPI packet is assembled by the HW block.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `op` – Enum representing an opcode for peripheral type and write request.
- `data` – Represents the parameter passed to the LPC peripheral.

**Return values**

- `0` – If successful.
- `-ENOTSUP` – if eSPI peripheral is off or not supported.
- `-EINVAL` – for unimplemented lpc opcode, but in range.

```c
int espi_send_vwire(const struct device *dev, enum espi_vwire_signal signal, uint8_t level)
```

Sends system/platform signal as a virtual wire packet.

This routine provides a generic interface to send a virtual wire packet from slave to master.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `signal` – The signal to be send to eSPI master.
- `level` – The level of signal requested LOW or HIGH.

**Return values**

- `0` – If successful.
- `-EIO` – General input / output error, failed to send over the bus.

```c
int espi_receive_vwire(const struct device *dev, enum espi_vwire_signal signal, uint8_t *level)
```

Retrieves level status for a signal encapsulated in a virtual wire.

This routine provides a generic interface to request a virtual wire packet from eSPI master and retrieve the signal level.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `signal` – the signal to be requested from eSPI master.
- `level` – the level of signal requested 0b LOW, 1b HIGH.

**Return values**

- `-EIO` – General input / output error, failed request to master.

```c
int espi_send_oob(const struct device *dev, struct espi_oob_packet *pckt)
```

Sends SMBus transaction (out-of-band) packet over eSPI bus.

This routine provides an interface to encapsulate a SMBus transaction and send into packet over eSPI bus.

**Parameters**

- `dev` – Pointer to the device structure for the driver instance.
- `pckt` – Address of the packet representation of SMBus transaction.
Return values
-EIO – General input / output error, failed request to master.

int espi_receive_oob(const struct device *dev, struct espi_oob_packet *pckt)
Receives SMBus transaction (out-of-band) packet from eSPI bus.
This routines provides an interface to receive and decoded a SMBus transaction from eSPI bus

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the packet representation of SMBus transaction.

Return values
-EIO – General input / output error, failed request to master.

int espi_read_flash(const struct device *dev, struct espi_flash_packet *pckt)
Sends a read request packet for shared flash.
This routines provides an interface to send a request to read the flash component shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the representation of read flash transaction.

Return values
• -ENOTSUP – eSPI flash logical channel transactions not supported.
• -EBUSY – eSPI flash channel is not ready or disabled by master.
• -EIO – General input / output error, failed request to master.

int espi_write_flash(const struct device *dev, struct espi_flash_packet *pckt)
Sends a write request packet for shared flash.
This routines provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the representation of write flash transaction.

Return values
• -ENOTSUP – eSPI flash logical channel transactions not supported.
• -EBUSY – eSPI flash channel is not ready or disabled by master.
• -EIO – General input / output error, failed request to master.

int espi_flash_erase(const struct device *dev, struct espi_flash_packet *pckt)
Sends a write request packet for shared flash.
This routines provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

Parameters
• dev – Pointer to the device structure for the driver instance.
• pckt – Address of the representation of write flash transaction.

Return values
• -ENOTSUP – eSPI flash logical channel transactions not supported.
-EBUSY – eSPI flash channel is not ready or disabled by master.

-EIO – General input / output error, failed request to master.

static inline void espi_init_callback(struct espi_callback *callback, espi_callback_handler_t handler, enum espi_bus_event evt_type)

Helper to initialize a struct espi_callback properly.

Callback model

(continues on next page)
Parameters

- callback – A valid Application's callback structure pointer.
- handler – A valid handler function pointer.
- evt_type – indicates the eSPI event relevant for the handler. For VWIRE_RECEIVED event the data will indicate the new level asserted.

```
static inline int espi_add_callback(const struct device *dev, struct espi_callback *callback)
```

Add an application callback.

Note: enables to add as many callback as needed on the same device.

---

**Note:** Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current eSPI event is not specified.

---

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback – A valid Application's callback structure pointer.

Returns

0 if successful, negative errno code on failure.

```
static inline int espi_remove_callback(const struct device *dev, struct espi_callback *callback)
```

Remove an application callback.

Note: enables to remove as many callbacks as added through `espi_add_callback()`.

---

**Warning:** It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. callback. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

---

Parameters

- dev – Pointer to the device structure for the driver instance.
- callback – A valid application's callback structure pointer.

Returns

0 if successful, negative errno code on failure.
int espi_saf_config(const struct device *dev, const struct espi_saf_cfg *cfg)
Configure operation of a eSPI controller.

This routine provides a generic interface to override eSPI controller capabilities.

If this eSPI controller is acting as slave, the values set here will be discovered as part through the GET_CONFIGURATION command issued by the eSPI master during initialization.

If this eSPI controller is acting as master, the values set here will be used by eSPI master to determine minimum common capabilities with eSPI slave then send via SET_CONFIGURATION command.

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- **cfg** – the device runtime configuration for the eSPI controller.

Return values

- **0** – If successful.
- **-EIO** – General input / output error, failed to configure device.
- **-EINVAL** – invalid capabilities, failed to configure device.
- **-ENOTSUP** – capability not supported by eSPI slave.

int espi_saf_set_protection_regions(const struct device *dev, const struct espi_saf_protection *pr)
Set one or more SAF protection regions.

This routine provides an interface to override the default flash protection regions of the SAF controller.

Parameters

- **dev** – Pointer to the device structure for the driver instance.
- pr – Pointer to the SAF protection region structure.

**Return values**
- 0 – If successful.
- -EIO – General input / output error, failed to configure device.
- -EINVAL – invalid capabilities, failed to configure device.
- -ENOTSUP – capability not supported by eSPI slave.

```c
int espi_saf_activate(const struct device *dev)
```
Activate SAF block.

This routine activates the SAF block and should only be called after SAF has been configured and the eSPI Master has enabled the Flash Channel.

**Parameters**
- dev – Pointer to the device structure for the driver instance.

**Return values**
- 0 – If successful
- -EINVAL – if failed to activate SAF.

```c
bool espi_saf_get_channel_status(const struct device *dev)
```
Query to see if SAF is ready.

This routine allows to check if SAF is ready before use.

**Parameters**
- dev – Pointer to the device structure for the driver instance.

**Return values**
- true – If eSPI SAF is ready.
- false – otherwise.

```c
int espi_saf_flash_read(const struct device *dev, struct espi_saf_packet *pckt)
```
Sends a read request packet for slave attached flash.

This routines provides an interface to send a request to read the flash component shared between the eSPI master and eSPI slaves.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- pckt – Address of the representation of read flash transaction.

**Return values**
- -ENOTSUP – eSPI flash logical channel transactions not supported.
- -EBUSY – eSPI flash channel is not ready or disabled by master.
- -EIO – General input / output error, failed request to master.

```c
int espi_saf_flash_write(const struct device *dev, struct espi_saf_packet *pckt)
```
Sends a write request packet for slave attached flash.

This routines provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

**Parameters**
- dev – Pointer to the device structure for the driver instance.
- pckt – Address of the representation of write flash transaction.
Return values

- **-ENOTSUP** – eSPI flash logical channel transactions not supported.
- **-EBUSY** – eSPI flash channel is not ready or disabled by master.
- **-EIO** – General input / output error, failed request to master.

```c
int espi_saf_flash_erase(const struct device *dev, struct espi_saf_packet *pckt)
```

Sends a write request packet for slave attached flash.

This routine provides an interface to send a request to write to the flash components shared between the eSPI master and eSPI slaves.

### Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `pckt` – Address of the representation of erase flash transaction.

### Return values

- **-ENOTSUP** – eSPI flash logical channel transactions not supported.
- **-EBUSY** – eSPI flash channel is not ready or disabled by master.
- **-EIO** – General input / output error, failed request to master.

```c
static inline void espi_saf_init_callback(struct espi_callback *callback, espi_callback_handler_t handler, enum espi_bus_event evt_type)
```

Helper to initialize a struct espi_callback properly.

Callback model

(continues on next page)
Parameters

- `callback` – A valid Application's callback structure pointer.
- `handler` – A valid handler function pointer.
- `evt_type` – indicates the eSPI event relevant for the handler. for VWIRE_RECEIVED event the data will indicate the new level asserted.

static inline int espi_saf_add_callback(const struct device *dev, struct espi_callback *callback)
Add an application callback.

Note: enables to add as many callback as needed on the same device.

Note: Callbacks may be added to the device from within a callback handler invocation, but whether they are invoked for the current eSPI event is not specified.

Parameters

- `dev` – Pointer to the device structure for the driver instance.
- `callback` – A valid Application’s callback structure pointer.

Returns

0 if successful, negative errno code on failure.
static inline int espi_saf_remove_callback(const struct device *dev, struct espi_callback *callback)

Remove an application callback.

Note: enables to remove as many callbacks as added through espi_add_callback().

**Warning:** It is explicitly permitted, within a callback handler, to remove the registration for the callback that is running, i.e. callback. Attempts to remove other registrations on the same device may result in undefined behavior, including failure to invoke callbacks that remain registered and unintended invocation of removed callbacks.

**Parameters**

- dev – Pointer to the device structure for the driver instance.
- callback – A valid application’s callback structure pointer.

**Returns**

0 if successful, negative errno code on failure.

```
struct espi_evt_data_kbc
    #include <espi.h> Bit field definition of evt_data in struct espi_event for KBC.

struct espi_evt_data_acpi
    #include <espi.h> Bit field definition of evt_data in struct espi_event for ACPI.

struct espi_event
    #include <espi.h> eSPI event

Public Members

enum espi_bus_event evt_type
    Event type

uint32_t evt_details
    Additional details for bus event type

uint32_t evt_data
    Data associated to the event

struct espi_cfg
    #include <espi.h> eSPI bus configuration parameters

Public Members

enum espi_io_mode io_caps
    Supported I/O mode
enum espi_channel channel_caps
    Supported channels

    uint8_t max_freq
    Maximum supported frequency in MHz

struct espi_request_packet
    #include <espi.h> eSPI peripheral request packet format

struct espi_oob_packet
    #include <espi.h> eSPI out-of-band transaction packet format

struct espi_flash_packet
    #include <espi.h> eSPI flash transactions packet format

struct espi_saf_cfg
    #include <espi_saf.h> eSPI SAF configuration parameters

struct espi_saf_packet
    #include <espi_saf.h> eSPI SAF transaction packet format

7.3.43 MIPI-DSI

API Reference

group mipi_dsi_interface
    MIPI-DSI driver APIs.

    MIPI-DSI DCS (Display Command Set)

    MIPI_DCS_NOP

    MIPI_DCS_SOFT_RESET

    MIPI_DCS_GET_COMPRESSION_MODE

    MIPI_DCS_GET_DISPLAY_ID

    MIPI_DCS_GET_RED_CHANNEL

    MIPI_DCS_GET_GREEN_CHANNEL

    MIPI_DCS_GET_BLUE_CHANNEL

    MIPI_DCS_GET_DISPLAY_STATUS
MIPI_DCS_GET_POWER_MODE
MIPI_DCS_GET_ADDRESS_MODE
MIPI_DCS_GET_PIXEL_FORMAT
MIPI_DCS_GET_DISPLAY_MODE
MIPI_DCS_GET_SIGNAL_MODE
MIPI_DCS_GET_DIAGNOSTIC_RESULT
MIPI_DCS_ENTER_SLEEP_MODE
MIPI_DCS_EXIT_SLEEP_MODE
MIPI_DCS_ENTER_PARTIAL_MODE
MIPI_DCS_ENTER_NORMAL_MODE
MIPI_DCS_EXIT_INVERT_MODE
MIPI_DCS_ENTER_INVERT_MODE
MIPI_DCS_SET_GAMMA_CURVE
MIPI_DCS_SET_DISPLAY_OFF
MIPI_DCS_SET_DISPLAY_ON
MIPI_DCS_SET_COLUMN_ADDRESS
MIPI_DCS_SET_PAGE_ADDRESS
MIPI_DCS_WRITE_MEMORY_START
MIPI_DCS_WRITE_LUT
MIPI_DCS_READ_MEMORY_START
MIPI_DCS_SET_PARTIAL_ROWS
MIPI_DCS_SET_PARTIAL_COLUMNS
MIPI_DCS_SET_SCROLL_AREA
MIPI_DCS_SET_TEAR_OFF
MIPI_DCS_SET_TEAR_ON
MIPI_DCS_SET_ADDRESS_MODE
MIPI_DCS_SET_SCROLL_START
MIPI_DCS_EXIT_IDLE_MODE
MIPI_DCS_ENTER_IDLE_MODE
MIPI_DCS_SET_PIXEL_FORMAT
MIPI_DCS_WRITE_MEMORY_CONTINUE
MIPI_DCS_SET_3D_CONTROL
MIPI_DCS_READ_MEMORY_CONTINUE
MIPI_DCS_GET_3D_CONTROL
MIPI_DCS_SET_VSYNC_TIMING
MIPI_DCS_SET_TEAR_SCANLINE
MIPI_DCS_GET_SCANLINE
MIPI_DCS_SET_DISPLAY_BRIGHTNESS
MIPI_DCS_GET_DISPLAY_BRIGHTNESS
MIPI_DCS_WRITE_CONTROL_DISPLAY
MIPI_DCS_GET_CONTROL_DISPLAY
MIPI_DCS_WRITE_POWER_SAVE
MIPI_DCS_GET_POWER_SAVE
MIPI_DCS_SET_CABC_MIN_BRIGHTNESS
MIPI_DCS_GET_CABC_MIN_BRIGHTNESS
MIPI_DCS_READ_DDB_START
MIPI_DCS_READ_DDB_CONTINUE

MIPI_DCS_PIXEL_FORMAT_24BIT

MIPI_DCS_PIXEL_FORMAT_18BIT

MIPI_DCS_PIXEL_FORMAT_16BIT

MIPI_DCS_PIXEL_FORMAT_12BIT

MIPI_DCS_PIXEL_FORMAT_8BIT

MIPI_DCS_PIXEL_FORMAT_3BIT

MIPI-DSI Address mode register fields.

MIPI_DCS_ADDRESS_MODE_MIRROR_Y

MIPI_DCS_ADDRESS_MODE_MIRROR_X

MIPI_DCS_ADDRESS_MODE_SWAP_XY

MIPI_DCS_ADDRESS_MODE_REFRESH_BT

MIPI_DCS_ADDRESS_MODE_BGR

MIPI_DCS_ADDRESS_MODE_LATCH_RL

MIPI_DCS_ADDRESS_MODE_FLIP_X

MIPI_DCS_ADDRESS_MODE_FLIP_Y

MIPI-DSI Processor-to-Peripheral transaction types.

MIPI_DSI_V_SYNC_START

MIPI_DSI_V_SYNC_END

MIPI_DSI_H_SYNC_START

MIPI_DSI_H_SYNC_END

MIPI_DSI_COLOR_MODE_OFF
MIPI_DSI_COLOR_MODE_ON
MIPI_DSI_SHUTDOWN_PERIPHERAL
MIPI_DSI_TURN_ON_PERIPHERAL
MIPI_DSI_GENERIC_SHORT_WRITE_0_PARAM
MIPI_DSI_GENERIC_SHORT_WRITE_1_PARAM
MIPI_DSI_GENERIC_SHORT_WRITE_2_PARAM
MIPI_DSI_GENERIC_READ_REQUEST_0_PARAM
MIPI_DSI_GENERIC_READ_REQUEST_1_PARAM
MIPI_DSI_GENERIC_READ_REQUEST_2_PARAM
MIPI_DSI_DCS_SHORT_WRITE
MIPI_DSI_DCS_SHORT_WRITE_PARAM
MIPI_DSI_DCS_READ
MIPI_DSI_SET_MAXIMUM_RETURN_PACKET_SIZE
MIPI_DSI_END_OF_TRANSMISSION
MIPI_DSI_NULL_PACKET
MIPI_DSI_BLANKING_PACKET
MIPI_DSI_GENERIC_LONG_WRITE
MIPI_DSI_DCS_LONG_WRITE
MIPI_DSI_LOOSELY_PACKED_PIXEL_STREAM_YCBCR20
MIPI_DSI_PACKED_PIXEL_STREAM_YCBCR24
MIPI_DSI_PACKED_PIXEL_STREAM_YCBCR16
MIPI_DSI_PACKED_PIXEL_STREAM_30
MIPI_DSI_PACKED_PIXEL_STREAM_36

7.3. Peripherals
MIPI_DSI_PACKED PIXEL_STREAM_YCBCR12
MIPI_DSI_PACKED PIXEL_STREAM_16
MIPI_DSI_PACKED PIXEL_STREAM_18
MIPI_DSI PIXEL_STREAM_3BYTE_18
MIPI_DSI_PACKED PIXEL_STREAM_24

MIPI-DSI Device mode flags.

MIPI_DSI_MODE_VIDEO
Video mode

MIPI_DSI_MODE_VIDEO_BURST
Video burst mode

MIPI_DSI_MODE_VIDEO_SYNC_PULSE
Video pulse mode

MIPI_DSI_MODE_VIDEO_AUTO_VERT
Enable auto vertical count mode

MIPI_DSI_MODE_VIDEO_HSE
Enable hsync-end packets in vsync-pulse and v-porch area

MIPI_DSI_MODE_VIDEO_HFP
Disable hfront-porch area

MIPI_DSI_MODE_VIDEO_HBP
Disable hback-porch area

MIPI_DSI_MODE_VIDEO_HSA
Disable hsync-active area

MIPI_DSI_MODE_VSYNC_FLUSH
Flush display FIFO on vsync pulse

MIPI_DSI_MODE_EOT_PACKET
Disable EoT packets in HS mode

MIPI_DSI_CLOCK_NON_CONTINUOUS
Device supports non-continuous clock behavior (DSI spec 5.6.1)

MIPI_DSI_MODE_LPM
Transmit data in low power
MIPI-DSI Pixel formats.

MIPI_DSI_PIXFMT_RGB888
  RGB888 (24bpp).

MIPI_DSI_PIXFMT_RGB666
  RGB666 (24bpp).

MIPI_DSI_PIXFMT_RGB666_PACKED
  Packed RGB666 (18bpp).

MIPI_DSI_PIXFMT_RGB565
  RGB565 (16bpp).

Functions

static inline int miipi_dsi_attach(const struct device *dev, uint8_t channel, const struct miipi_dsi_device *mdev)

Attach a new device to the MIPI-DSI bus.

Parameters

• dev – MIPI-DSI host device.
• channel – Device channel (VID).
• mdev – MIPI-DSI device description.

Returns

0 on success, negative on error

static inline ssize_t miipi_dsi_transfer(const struct device *dev, uint8_t channel, struct miipi_dsi_msg *msg)

Transfer data to/from a device attached to the MIPI-DSI bus.

Parameters

• dev – MIPI-DSI device.
• channel – Device channel (VID).
• msg – Message.

Returns

Size of the transferred data on success, negative on error.

ssize_t miipi_dsi_generic_read(const struct device *dev, uint8_t channel, const void *params, size_t nparams, void *buf, size_t len)

MIPI-DSI generic read.

Parameters

• dev – MIPI-DSI host device.
• channel – Device channel (VID).
• params – Buffer containing request parameters.
• nparams – Number of parameters.
• buf – Buffer where read data will be stored.
• len – Length of the reception buffer.
Returns
Size of the read data on success, negative on error.

ssize_t mipi_dsi_generic_write(const struct device *dev, uint8_t channel, const void *buf, size_t len)

MIPI-DSI generic write.

Parameters
• dev – MIPI-DSI host device.
• channel – Device channel (VID).
• buf – Transmission buffer.
• len – Length of the transmission buffer

Returns
Size of the written data on success, negative on error.

ssize_t mipi_dsi_dcs_read(const struct device *dev, uint8_t channel, uint8_t cmd, void *buf, size_t len)

MIPI-DSI DCS read.

Parameters
• dev – MIPI-DSI host device.
• channel – Device channel (VID).
• cmd – DCS command.
• buf – Buffer where read data will be stored.
• len – Length of the reception buffer.

Returns
Size of the read data on success, negative on error.

ssize_t mipi_dsi_dcs_write(const struct device *dev, uint8_t channel, uint8_t cmd, const void *buf, size_t len)

MIPI-DSI DCS write.

Parameters
• dev – MIPI-DSI host device.
• channel – Device channel (VID).
• cmd – DCS command.
• buf – Transmission buffer.
• len – Length of the transmission buffer

Returns
Size of the written data on success, negative on error.

struct mipi_dsi_timings
#include <mipi_dsi.h> MIPI-DSI display timings.

Public Members

uint32_t hactive
Horizontal active video.
uint32_t hfp
    Horizontal front porch.

uint32_t hbp
    Horizontal back porch.

uint32_t hsync
    Horizontal sync length.

uint32_t vactive
    Vertical active video.

uint32_t vfp
    Vertical front porch.

uint32_t vbp
    Vertical back porch.

uint32_t vsync
    Vertical sync length.

struct mipi_dsi_device
    #include <mipi_dsi.h> MIPI-DSI device.

Public Members

uint8_t data_lanes
    Number of data lanes.

struct miopi_dsi_timings timings
    Display timings.

uint32_t pixfmt
    Pixel format.

uint32_t mode_flags
    Mode flags.

struct miopi_dsi_msg
    #include <mipi_dsi.h> MIPI-DSI read/write message.

Public Members

uint8_t type
    Payload data type.
uint16_t flags
Flags controlling message transmission.

uint8_t cmd
Command (only for DCS)

size_t tx_len
Transmission buffer length.

const void *tx_buf
Transmission buffer.

size_t rx_len
Reception buffer length.

void *rx_buf
Reception buffer.

struct mipi_dsi_driver_api
#include <mipi_dsi.h> MIPI-DSI host driver API.

7.3.44 W1: Dallas 1-Wire Interface

Overview

1-Wire is a low speed half-duplex serial bus using only a single wire plus ground for both data transmission and device power supply. Similarly to I2C, 1-Wire uses a bidirectional open-collector data line, and is a single master multidrop bus. This means one master initiates all data exchanges with the slave devices. The 1-Wire bus supports longer bus lines than I2C, while it reaches speeds of up to 15.4 kbps in standard mode and up to 125 kbps in overdrive mode. Reliable communication in standard speed configuration is possible with 10 nodes over a bus length of 100 meters. Using overdrive speed, 3 nodes on a bus of 10 meters length are expected to work solid. Optimized timing parameters and fewer nodes on the bus may allow to reach larger bus extents.

The implementation details are specified in the BOOK OF IBUTTON STANDARDS.

![Fig. 7.1: A typical 1-Wire bus topology](image)
Zephyr Project Documentation, Release 3.2.99

W1 Master API  Zephyr’s 1-Wire Master API is used to interact with 1-Wire slave devices like temperature sensors and serial memories.

In Zephyr this API is split into the following layers.

- The link layer handles basic communication functions such as bus reset, presence detect and bit transfer operations. It is the only hardware-dependent layer in Zephyr. This layer is supported by a driver using the Zephyr UART interface, which should work on most Zephyr platforms. In the future, a GPIO/Timer based driver and hardware specific drivers might be added.
- The 1-Wire network layer handles all means for slave identification and bus arbitration. This includes ROM commands like Match ROM, or Search ROM.
  - All slave devices have a unique 64-bit identification number, which includes a 8-bit 1-Wire Family Code and a 8-bit CRC.
  - In order to find slaves on the bus, the standard specifies an search algorithm which successively detects all slaves on the bus. This algorithm is described in detail by Maxim’s Applicationnote 187.
- Transport layer and Presentation layer functions are not implemented in the generic 1-Wire driver and therefore must be handled in individual slave drivers.

The 1-Wire API is considered experimental.

Configuration Options

Related configuration options:

- CONFIG_W1
- CONFIG_W1_NET

API Reference

1-Wire data link layer

group w1_data_link

1-Wire data link layer

Functions

int w1_reset_bus(const struct device *dev)
Reset the 1-Wire bus to prepare slaves for communication.

This routine resets all 1-Wire bus slaves such that they are ready to receive a command. Connected slaves answer with a presence pulse once they are ready to receive data.

In case the driver supports both standard speed and overdrive speed, the reset routine takes care of sendig either a short or a long reset pulse depending on the current state. The speed can be changed using w1_configure().

Parameters

- dev – [in] Pointer to the device structure for the driver instance.

Return values

- 0 – If no slaves answer with a present pulse.
- 1 – If at least one slave answers with a present pulse.
- -errno – Negative error code on error.
int w1_read_bit(const struct device *dev)
Read a single bit from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• rx_bit – The read bit value on success.
• -errno – Negative error code on error.

int w1_write_bit(const struct device *dev, const bool bit)
Write a single bit to the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• bit – Transmitting bit value 1 or 0.

Return values
• 0 – If successful.
• -errno – Negative error code on error.

int w1_read_byte(const struct device *dev)
Read a single byte from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• rx_byte – The read byte value on success.
• -errno – Negative error code on error.

int w1_write_byte(const struct device *dev, uint8_t byte)
Write a single byte to the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• byte – Transmitting byte.

Return values
• 0 – If successful.
• -errno – Negative error code on error.

int w1_read_block(const struct device *dev, uint8_t *buffer, size_t len)
Read a block of data from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• buffer – [out] Pointer to receive buffer.
• len – Length of receiving buffer (in bytes).

Return values
• 0 – If successful.
• -errno – Negative error code on error.
int w1_write_block(const struct device *dev, const uint8_t *buffer, size_t len)
Write a block of data from the 1-Wire bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• buffer – [in] Pointer to transmitting buffer.
• len – Length of transmitting buffer (in bytes).

Return values
• 0 – If successful.
• -errno – Negative error code on error.

size_t w1_get_slave_count(const struct device *dev)
Get the number of slaves on the bus.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• slave_count – Positive number of connected 1-Wire slaves on success.
• -errno – Negative error code on error.

int w1_configure(const struct device *dev, enum w1_settings_type type, uint32_t value)
Configure parameters of the 1-Wire master.

Allowed configuration parameters are defined in enum w1_settings_type, but master devices may not support all types.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• type – Enum specifying the setting type.
• value – The new value for the passed settings type.

Return values
• 0 – If successful.
• -ENOTSUP – The master doesn’t support the configuration of the supplied type.
• -EIO – General input / output error, failed to configure master devices.

1-Wire network layer

group w1_network

1-Wire network layer

1-Wire ROM Commands

W1_CMD_SKIP_ROM

W1_CMD_MATCH_ROM

W1_CMD_RESUME
W1_CMD_READ_ROM

W1_CMD_SEARCH_ROM

W1_CMD_SEARCH_ALARM

W1_CMD_OVERDRIVE_SKIP_ROM

W1_CMD_OVERDRIVE_MATCH_ROM

CRC Defines

W1_CRC8_SEED
Seed value used to calculate the 1-Wire 8-bit crc.

W1_CRC8_POLYNOMIAL
Polynomial used to calculate the 1-Wire 8-bit crc.

W1_CRC16_SEED
Seed value used to calculate the 1-Wire 16-bit crc.

W1_CRC16_POLYNOMIAL
Polynomial used to calculate the 1-Wire 16-bit crc.

Defines

W1_SEARCH_ALL_FAMILIES
This flag can be passed to searches in order to not filter on family ID.

W1_ROM_INIT_ZERO
Initialize all w1_rom struct members to zero.

Typedefs
typedef void (*w1_search_callback_t)(struct w1_rom *rom, void *user_data)
Define the application callback handler function signature for searches.

Param rom
found The ROM of the found slave.

Param user_data
User data provided to the w1_search_bus() call.
Functions

int w1_read_rom(const struct device *dev, struct w1_rom *rom)
Read Peripheral 64-bit ROM.

This procedure allows the 1-Wire bus master to read the peripherals' 64-bit ROM without using the Search ROM procedure. This command can be used as long as not more than a single peripheral is connected to the bus. Otherwise, data collisions occur, and a faulty ROM is read.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• rom – [out] Pointer to the ROM structure.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code in case of invalid crc and communication errors.

int w1_match_rom(const struct device *dev, const struct w1_slave_config *config)
Select a specific slave by broadcasting a selected ROM.

This routine allows the 1-Wire bus master to select a slave identified by its unique ROM, such that the next command will target only this single selected slave.

This command is only necessary in multidrop environments, otherwise, the Skip ROM command can be issued. Once a slave has been selected, to reduce the communication overhead, the resume command can be used instead of this command to communicate with the selected slave.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• config – [in] Pointer to the slave specific 1-Wire config.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code on error.

int w1_resume_command(const struct device *dev)
Select the slave last addressed with a Match ROM or Search ROM command.

This routine allows the 1-Wire bus master to re-select a slave device that was already addressed using a Match ROM or Search ROM command.

Parameters
• dev – Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code on error.
int w1_skip_rom(const struct device *dev, const struct w1_slave_config *config)
    Select all slaves regardless of ROM.

This routine sets up the bus slaves to receive a command. It is usually used when there is only
one peripheral on the bus to avoid the overhead of the Match ROM command. But it can also
be used to concurrently write to all slave devices.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• config – [in] Pointer to the slave specific 1-Wire config.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code on error.

int w1_reset_select(const struct device *dev, const struct w1_slave_config *config)
    In single drop configurations use Skip Select command, otherwise use Match ROM command.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• config – [in] Pointer to the slave specific 1-Wire config.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code on error.

int w1_write_read(const struct device *dev, const struct w1_slave_config *config, const uint8_t *write_buf,
    size_t write_len, uint8_t *read_buf, size_t read_len)
    Write then read data from the 1-Wire slave with matching ROM.

This routine uses w1_reset_select to select the given ROM. Then writes given data and reads
the response back from the slave.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.
• config – [in] Pointer to the slave specific 1-Wire config.
• write_buf – [in] Pointer to the data to be written.
• write_len – Number of bytes to write.
• read_buf – [out] Pointer to storage for read data.
• read_len – Number of bytes to read.

Return values
• 0 – If successful.
• -ENODEV – In case no slave responds to reset.
• -errno – Other negative error code on error.

int w1_search_bus(const struct device *dev, uint8_t command, uint8_t *family,
    w1_search_callback_t callback, void *user_data)
Search 1-wire slaves on the bus.

This function searches slaves on the 1-wire bus, with the possibility to search either all slaves or only slaves that have an active alarm state. If a callback is passed, the callback is called for each found slave.


Note: Filtering on families is not supported.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- command – Can either be W1_SEARCH_ALARM or W1_SEARCH_ROM.
- family – W1_SEARCH_ALL_FAMILIES searches all families, filtering on a specific family is not yet supported.
- callback – Application callback handler function to be called for each found slave.
- user_data – [in] User data to pass to the application callback handler function.

Return values

- slave_count – Number of slaves found.
- -errno – Negative error code on error.

static inline int w1_search_rom(const struct device *dev, w1_search_callback_t callback, void *user_data)

Search for 1-Wire slave on bus.

This routine can discover unknown slaves on the bus by scanning for the unique 64-bit registration number.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- callback – Application callback handler function to be called for each found slave.
- user_data – [in] User data to pass to the application callback handler function.

Return values

- slave_count – Number of slaves found.
- -errno – Negative error code on error.

static inline int w1_search_alarm(const struct device *dev, w1_search_callback_t callback, void *user_data)

Search for 1-Wire slaves with an active alarm.

This routine searches 1-Wire slaves on the bus, which currently have an active alarm.

Parameters

- dev – [in] Pointer to the device structure for the driver instance.
- callback – Application callback handler function to be called for each found slave.
- user_data – [in] User data to pass to the application callback handler function.

Return values

- slave_count – Number of slaves found.
- **-errno** – Negative error code on error.

```c
static inline uint64_t w1_rom_to_uint64(const struct w1_rom *rom)
```

Function to convert a `w1_rom` struct to an `uint64_t`.

**Parameters**

- `rom` – [in] Pointer to the ROM struct.

**Return values**

- `rom64` – The ROM converted to an unsigned integer in endianness.

```c
static inline void w1_uint64_to_rom(const uint64_t rom64, struct w1_rom *rom)
```

Function to write an `uint64_t` to struct `w1_rom` pointer.

**Parameters**

- `rom64` – Unsigned 64 bit integer representing the ROM in host endianness.
- `rom` – [out] The ROM struct pointer.

```c
static inline uint8_t w1_crc8(const uint8_t *src, size_t len)
```

Compute CRC-8 checksum as defined in the 1-Wire specification.

The 1-Wire CRC 8 variant is using 0x31 as its polynomial with the initial value set to 0x00. This CRC is used to check the correctness of the unique 56-bit ROM.

**Parameters**

- `src` – [in] Input bytes for the computation.
- `len` – Length of the input in bytes.

**Return values**

- `crc` – The computed CRC8 value.

```c
static inline uint16_t w1_crc16(const uint16_t seed, const uint8_t *src, const size_t len)
```

Compute 1-Wire variant of CRC 16.

The 16-bit 1-Wire crc variant is using the reflected polynomial function \(X^{\text{16}} + X^{\text{15}} + X^{\text{2}} + 1\) with the initial value set to 0x0000. See also APPLICATION NOTE 27: “UNDERSTANDING AND USING CYCLIC REDUNDANCY CHECKS WITH MAXIM 1-WIRE AND IBUTTON PRODUCTS” https://www.maximintegrated.com/en/design/technical-documents/app-notes/2/27.html

**Parameters**

- `seed` – Init value for the CRC, it is usually set to 0x0000.
- `src` – [in] Input bytes for the computation.
- `len` – Length of the input in bytes.

**Return values**

- `crc` – The computed CRC16 value.

```c
#include <w1.h> struct w1_rom
```

The 1-Wire family code identifying the slave device type.

An incomplete list of family codes is available at: https://www.maximintegrated.com/en/app-notes/index.mvp/id/155 others are documented in the respective device data sheet.
The serial together with the family code composes the unique 56-bit id.

uint8_t crc
8-bit checksum of the 56-bit unique id.

struct w1_slave_config
#include <w1.h> Node specific 1-wire configuration struct.
This struct is passed to network functions, such that they can configure the bus to address the specific slave using the selected speed.

Public Members

struct w1_rom rom
Unique 1-Wire ROM.

uint32_t overdrive
overdrive speed is used if set to 1.

1-Wire generic functions and helpers  Functions that are not directly related to any of the networking layers.

group w1_interface
1-Wire Interface

Enums

enum w1_settings_type
Defines the 1-Wire master settings types, which are runtime configurable.

Values:

enumerator W1_SETTING_SPEED
Overdrive speed is enabled in case a value of 1 is passed and disabled passing 0.

enumerator W1_SETTING_STRONG_PULLUP
The strong pullup resistor is activated immediately after the next written data block by passing a value of 1, and deactivated passing 0.

enumerator W1_SETTINGS_TYPE_COUNT
Number of different settings types.

Functions

7.3. Peripherals
static inline int w1_lock_bus(const struct device *dev)
Lock the 1-wire bus to prevent simultaneous access.

This routine locks the bus to prevent simultaneous access from different threads. The calling
thread waits until the bus becomes available. A thread is permitted to lock a mutex it has
already locked.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• -errno – Negative error code on error.

static inline int w1_unlock_bus(const struct device *dev)
Unlock the 1-wire bus.

This routine unlocks the bus to permit access to bus line.

Parameters
• dev – [in] Pointer to the device structure for the driver instance.

Return values
• 0 – If successful.
• -errno – Negative error code on error.

7.4 Pin Control

This is a high-level guide to pin control. See Pin Control API for API reference material.

7.4.1 Introduction

The hardware blocks that control pin multiplexing and pin configuration parameters such as pin direc-
tion, pull-up/down resistors, etc. are named pin controllers. The pin controller's main users are SoC
hardware peripherals, since the controller enables exposing peripheral signals, like for example, map
I2C0 SDA signal to pin PX0. Not only that, but it usually allows configuring certain pin settings that
are necessary for the correct functioning of a peripheral, for example, the slew-rate depending on the
operating frequency. The available configuration options are vendor/SoC dependent and can range from
simple pull-up/down options to more advanced settings such as debouncing, low-power modes, etc.

The way pin control is implemented in hardware is vendor/SoC specific. It is common to find a centralized
approach, that is, all pin configuration parameters are controlled by a single hardware block (typically
named pinmux), including signal mapping. Fig. 7.2 illustrates this approach. PX0 can be mapped to
UART0_TX, I2C0_SCK or SPI0_MOSI depending on the AF control bits. Other configuration parameters
such as pull-up/down are controlled in the same block via CONFIG bits. This model is used by several
SoC families, such as many from NXP and STM32.

Other vendors/SoCs use a distributed approach. In such case, the pin mapping and configuration are
controlled by multiple hardware blocks. Fig. 7.3 illustrates a distributed approach where pin mapping is
controlled by peripherals, such as in Nordic nRF SoCs.

From a user perspective, there is no difference in pin controller usage regardless of the hardware imple-
mentation: a user will always apply a state. The only difference lies in the driver implementation. In
general, implementing a pin controller driver for a hardware that uses a distributed approach requires
more effort, since the driver needs to gather knowledge of peripheral dependent registers.
Fig. 7.2: Example of pin control centralized into a single per-pin block

Fig. 7.3: Example pin control distributed between peripheral registers and per-pin block
Pin control vs. GPIO

Some functionality covered by a pin controller driver overlaps with GPIO drivers. For example, pull-up/down resistors can usually be enabled by both the pin control driver and the GPIO driver. In Zephyr context, the pin control driver purpose is to perform peripheral signal multiplexing and configuration of other pin parameters required for the correct operation of that peripheral. Therefore, the main users of the pin control driver are SoC peripherals. In contrast, GPIO drivers are for general purpose control of a pin, that is, when its logic level is read or controlled manually.

7.4.2 State model

For a device driver to operate correctly, a certain pin configuration needs to be applied. Some device drivers require a static configuration, usually set up at initialization time. Others need to change the configuration at runtime depending on the operating conditions, for example, to enable a low-power mode when suspending the device. Such requirements are modeled using states, a concept that has been adapted from the one in the Linux kernel. Each device driver owns a set of states. Each state has a unique name and contains a full pin configuration set (see Table 7.1). This effectively means that states are independent of each other, so they do not need to be applied in any specific order. Another advantage of the state model is that it isolates device drivers from pin configuration.

<table>
<thead>
<tr>
<th>UART0 peripheral</th>
<th>default state</th>
<th>sleep state</th>
</tr>
</thead>
<tbody>
<tr>
<td>TX</td>
<td>• Pin: PA0</td>
<td>• Pin: PA0</td>
</tr>
<tr>
<td></td>
<td>• Pull: NONE</td>
<td>• Pull: NONE</td>
</tr>
<tr>
<td></td>
<td>• Low Power: NO</td>
<td>• Low Power: YES</td>
</tr>
<tr>
<td>RX</td>
<td>• Pin: PA1</td>
<td>• Pin: PA1</td>
</tr>
<tr>
<td></td>
<td>• Pull: UP</td>
<td>• Pull: NONE</td>
</tr>
<tr>
<td></td>
<td>• Low Power: NO</td>
<td>• Low Power: YES</td>
</tr>
</tbody>
</table>

Standard states

The name assigned to pin control states or the number of them is up to the device driver requirements. In many cases a single state applied at initialization time will be sufficient, but in some other cases more will be required. In order to make things consistent, a naming convention has been established for the most common use cases. Table 7.2 details the standardized states and its purpose.

<table>
<thead>
<tr>
<th>State</th>
<th>Identifier</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>default</td>
<td>PINCTRL_STATE_DEFAULT</td>
<td>State of the pins when the device is in operational state</td>
</tr>
<tr>
<td>sleep</td>
<td>PINCTRL_STATE_SLEEP</td>
<td>State of the pins when the device is in low power or sleep modes</td>
</tr>
</tbody>
</table>

Note that other standard states could be introduced in the future.

Custom states

Some device drivers may require using custom states beyond the standard ones. To achieve that, the device driver needs to have in its scope definitions for the custom state identifiers named as
PINCTRL_STATE_{STATE_NAME}, where {STATE_NAME} is the capitalized state name. For example, if mystate has to be supported, a definition named PINCTRL_STATE_MYSTATE needs to be in the driver’s scope.

**Note:** It is important that custom state identifiers start from PINCTRL_STATE_PRIV_START

If custom states need to be accessed from outside the driver, for example to perform dynamic pin control, custom identifiers should be placed in a header that is publicly accessible.

### Skipping states

In most situations, the states defined in Devicetree will be the ones used in the compiled firmware. However, there are some cases where certain states will be conditionally used depending on a compilation flag. A typical case is the sleep state. This state is only used in practice if CONFIG_PM_DEVICE is enabled. If a firmware variant without device power management is needed, one should in theory remove the sleep state from Devicetree to not waste ROM space storing such unused state.

States can be skipped by the pinctrl Devicetree macros if a definition named PINCTRL_SKIP_{STATE_NAME} expanding to 1 is present when pin control configuration is defined. In case of the sleep state, the pinctrl API already provides such definition conditional to the availability of device power management:

```c
#ifndef CONFIG_PM_DEVICE
/** If device power management is not enabled, "sleep" state will be ignored. */
#define PINCTRL_SKIP_SLEEP 1
#endif
```

### 7.4.3 Dynamic pin control

Dynamic pin control refers to the capability of changing pin configuration at runtime. This feature can be useful in situations where the same firmware needs to run onto slightly different boards, each having a peripheral routed at a different set of pins. This feature can be enabled by setting CONFIG_PINCTRL_DYNAMIC.

**Note:** Dynamic pin control should only be used on devices that have not been initialized. Changing pin configurations while a device is operating may lead to unexpected behavior. Since Zephyr does not support device de-initialization yet, this functionality should only be used during early boot stages.

One of the effects of enabling dynamic pin control is that pinctrl_dev_config will be stored in RAM instead of ROM (not states or pin configurations, though). The user can then use pinctrl_update_states() to update the states stored in pinctrl_dev_config with a new set. This effectively means that the device driver will apply the pin configurations stored in the updated states when it applies a state.

### 7.4.4 Devicetree representation

Because Devicetree is meant to describe hardware, it is the natural choice when it comes to storing pin control configuration. In the following sections you will find an overview on how states and pin configurations are represented in Devicetree.
States

Given a device, each of its pin control state is represented in Devicetree by \texttt{pinctrl-N} properties, being \( N \) the state index starting from zero. The \texttt{pinctrl-names} property is then used to assign a unique identifier for each state property by index, for example, \texttt{pinctrl-names} list entry 0 is the name for \texttt{pinctrl-0}.

\begin{verbatim}
periph0: periph0 {  
  /* state 0 ("default") */  
pinctrl-0 = <...>;  
  ...  
  /* state N ("mystate") */  
pinctrl-N = <...>;  
  /* names for state 0 up to state N */  
pinctrl-names = "default", ..., "mystate";  
  ...  
};
\end{verbatim}

Pin configuration

There are multiple ways to represent the pin configurations in Devicetree. However, all end up encoding the same information: the pin multiplexing and the pin configuration parameters. For example, UART\_RX is mapped to PX0 and pull-up is enabled. The representation choice largely depends on each vendor/SoC, so the Devicetree binding files for the pin control drivers are the best place to look for details.

A popular and versatile option is shown in the example below. One of the advantages of this choice is the grouping capability based on shared pin configuration. This allows to reduce the verbosity of the pin control definitions. Another advantage is that the pin configuration parameters for a particular state are enclosed in a single Devicetree node.

\begin{verbatim}
/* board.dts */  
#include "board-pinctrl.dtsi"

&periph0 {  
    pinctrl-0 = <&periph0_default>;  
    pinctrl-names = "default";
};
\end{verbatim}

\begin{verbatim}
/* vnd-soc-pkgxx.h */  
* File with valid mappings for a specific package (may be autogenerated).  
* This file is optional, but recommended.  
*/  
...  
#define PERIPH0_SIGA_PX0 VNDSOC_PIN(X, 0, MUX0)  
#define PERIPH0_SIGB_PY7 VNDSOC_PIN(Y, 7, MUX4)  
#define PERIPH0_SIGC_PZ1 VNDSOC_PIN(Z, 1, MUX2)  
...  

/* board-pinctrl.dtsi */  
#include <vnd-soc-pkgxx.h>

&pinctrl {  
    /* Node with pin configuration for default state */  
pinctrl_default: periph0_default {  
        group1 {  
            /* Mappings: PERIPH0_SIGA -> PX0, PERIPH0_SIGC -> PZ1 */
        }
    }
}
\end{verbatim}

(continues on next page)
pinmux = <PERIPH0_SIGA_PX0>, <PERIPH0_SIGC_PZ1>;
    /* Pins PX0 and PZ1 have pull-up enabled */
    bias-pull-up;
};
...

Another popular model is based on having a node for each pin configuration and state. While this model
may lead to shorter board pin control files, it also requires to have one node for each pin mapping
and state, since in general, nodes can not be re-used for multiple states. This method is discouraged if
autogeneration is not an option.

Note: Because all Devicetree information is parsed into a C header, it is important to make sure its size is
kept to a minimum. For this reason it is important to prefix pre-generated nodes with /omit-if-no-ref/.
This prefix makes sure that the node is discarded when not used.

/* board.dts */
#include "board-pinctrl.dtsi"

&periph0 {
    pinctrl-0 = <&periph0_siga_px0_default &periph0_sigb_py7_default
                &periph0_sigc_pz1_default>;
    pinctrl-names = "default";
};

/* vnd-soc-pkgxx.dtsi
* File with valid nodes for a specific package (may be autogenerated).
* This file is optional, but recommended.
*/

&pinctrl {
    /* Mapping for PERIPH0_SIGA -> PX0, to be used for default state */
    /omit-if-no-ref/ periph0_siga_px0_default: periph0_siga_px0_default {
        pinmux = <VNDSOC_PIN(X, 0, MUX0)>;
    };

    /* Mapping for PERIPH0_SIGB -> PY7, to be used for default state */
    /omit-if-no-ref/ periph0_sigb_py7_default: periph0_sigb_py7_default {
        pinmux = <VNDSOC_PIN(Y, 7, MUX4)>;
    };

    /* Mapping for PERIPH0_SIGC -> PZ1, to be used for default state */
    /omit-if-no-ref/ periph0_sigc_pz1_default: periph0_sigc_pz1_default {
        pinmux = <VNDSOC_PIN(Z, 1, MUX2)>;
    };
};

/* board-pinctrl.dts */
#include <vnd-soc-pkgxx.dtsi>
/* Enable pull-up for PX0 (default state) */
&periph0_siga_px0_default {
    bias-pull-up;
};

/* Enable pull-up for PZ1 (default state) */
&periph0_sigm_pz1_default {
    bias-pull-up;
};

Note: It is discouraged to add pin configuration defaults in pre-defined nodes. In general, pin configurations depend on the board design or on the peripheral working conditions, so the decision should be made by the board. For example, enabling a pull-up by default may not always be desired because the board already has one or because its value depends on the operating bus speed. Another downside of defaults is that user may not be aware of them, for example:

/* not evident that "periph0_siga_px0_default" also implies "bias-pull-up" */
/omit-if-no-ref/ periph0_siga_px0_default: periph0_siga_px0_default {
    pinmux = <VNDSOC_PIN(X, 0, MUX0)>;
    bias-pull-up;
};

7.4.5 Implementation guidelines

Pin control drivers

Pin control drivers need to implement a single function: `pinctrl_configure_pins()`. This function receives an array of pin configurations that need to be applied. Furthermore, if `CONFIG_PINCTRL_STORE_REG` is set, it also receives the associated device register address for the given pins. This information may be required by some drivers to perform device specific actions.

The pin configuration is stored in an opaque type that is vendor/SoC dependent: `pinctrl_soc_pin_t`. This type needs to be defined in a header named `pinctrl_soc.h` file that is in the Zephyr's include path. It can range from a simple integer value to a struct with multiple fields. `pinctrl_soc.h` also needs to define a macro named `Z_PINCTRL_STATE_PINS_INIT` that accepts two arguments: a node identifier and a property name (`pinctrl-N`). With this information the macro needs to define an initializer for all pin configurations contained within the `pinctrl-N` property of the given node.

Regarding Devicetree pin configuration representation, vendors can decide which option is better for their devices. However, the following guidelines should be followed:

- Use `pinctrl-N (N=0, 1, …)` and `pinctrl-names` properties to define pin control states. These properties are defined in `dts/bindings/pinctrl/pinctrl-device.yaml`.
- Use standard pin configuration properties as defined in `dts/bindings/pinctrl/pincfg-node.yaml`.

Representations not following these guidelines may be accepted if they are already used by the same vendor in other operating systems, e.g. Linux.

Device drivers

In this section you will find some tips on how a device driver should use the `pinctrl` API to successfully configure the pins it needs.
The device compatible needs to be modified in the corresponding binding so that the pinctrl-device.yaml is included. For example:

```
include: [base.yaml, pinctrl-device.yaml]
```

This file is needed to add pinctrl-N and pinctrl-names properties to the device.

From a device driver perspective there are two steps that need to be performed to be able to use the pinctrl API. First, the pin control configuration needs to be defined. This includes all states and pins. `PINCTRL_DT_DEFINE` or `PINCTRL_DT_INST_DEFINE` macros should be used for this purpose. Second, a reference to the device instance `pinctrl_dev_config` needs to be stored, since it is required to later use the API. This can be achieved using the `PINCTRL_DT_DEV_CONFIG_GET` and `PINCTRL_DT_INST_DEV_CONFIG_GET` macros.

It is worth to note that the only relationship between a device and its associated pin control configuration is based on variable naming conventions. The way an instance of `pinctrl_dev_config` is named for a corresponding device instance allows to later obtain a reference to it given the device's Devicetree node identifier. This allows to minimize ROM usage, since only devices requiring pin control will own a reference to a pin control configuration.

Once the driver has defined the pin control configuration and kept a reference to it, it is ready to use the API. The most common way to apply a state is by using `pinctrl_apply_state()`. It is also possible to use the lower level function `pinctrl_apply_state_direct()` to skip state lookup if it is cached in advance (e.g. at init time). Since state lookup time is expected to be fast, it is recommended to use `pinctrl_apply_state()`.

The example below contains a complete example of a device driver that uses the pinctrl API.

```c
/* A driver for the "mydev" compatible device */
#define DT_DRV_COMPAT mydev

...
#include <zephyr/drivers/pinctrl.h>
...

struct mydev_config {
    ...
    /* Reference to mydev pinctrl configuration */
    const struct pinctrl_dev_config *pcfg;
    ...
};
...

static int mydev_init(const struct device *dev)
{
    const struct mydev_config *config = dev->config;
    int ret;
    ...
    /* Select "default" state at initialization time */
    ret = pinctrl_apply_state(config->pcfg, PINCTRL_STATE_DEFAULT);
    if (ret < 0) {
        return ret;
    }
    ...
}

#define MYDEV_DEFINE(i) 
    /* Define all pinctrl configuration for instance "i" */
    \PINCTRL_DT_INST_DEFINE(i);
```

(continues on next page)
static const struct mydev_config mydev_config_##i = {
  .pcf = PINCTRL_DT_INST_DEV_CONFIG_GET(i),
};

DEVICE_DT_INST_DEFINE(i, mydev_init, NULL, &mydev_data##i, &mydev_config##i, ...);

DT_INST_FOREACH_STATUS_OKAY(MYDEV_DEFINE)

### 7.4.6 Pin Control API

**group pinctrl_interface**

Pin Controller Interface.

**Pin control states**

**PINCTRL_STATE_DEFAULT**

Default state (state used when the device is in operational state).

**PINCTRL_STATE_SLEEP**

Sleep state (state used when the device is in low power mode).

**PINCTRL_STATE_PRIV_START**

This and higher values refer to custom private states.

**Defines**

**PINCTRL_REG_NONE**

Utility macro to indicate no register is used.

**PINCTRL_DT_DEV_CONFIG_DECLARE(node_id)**

Declare pin control configuration for a given node identifier.

This macro should be used by tests or applications using runtime pin control to declare the pin control configuration for a device. **PINCTRL_DT_DEV_CONFIG_GET** can later be used to obtain a reference to such configuration.

Only available if CONFIG_PINCTRL_NON_STATIC is selected.

**Parameters**

- node_id – Node identifier.
PINCTRL_DT_DEFINE(node_id)
Define all pin control information for the given node identifier.

This helper macro should be called together with device definition. It defines and initializes
the pin control configuration for the device represented by node_id. Each pin control state
(pinctrl-0, ..., pinctrl-N) is also defined and initialized. Note that states marked to be skipped
will not be defined (refer to Z_PINCTRL_SKIP_STATE for more details).

Parameters
• node_id – Node identifier.

PINCTRL_DT_INST_DEFINE(inst)
Define all pin control information for the given compatible index.

See also:
PINCTRL_DT_DEFINE
Parameters
• inst – Instance number.

PINCTRL_DT_DEV_CONFIG_GET(node_id)
Obtain a reference to the pin control configuration given a node identifier.

Parameters
• node_id – Node identifier.

PINCTRL_DT_INST_DEV_CONFIG_GET(inst)
Obtain a reference to the pin control configuration given current compatible instance number.

See also:
PINCTRL_DT_DEV_CONFIG_GET
Parameters
• inst – Instance number.

Functions

int pinctrl_lookup_state(const struct pinctrl_dev_config *config, uint8_t id, const struct pinctrl_state **state)
Find the state configuration for the given state id.

Parameters
• config – Pin controller configuration.
• id – Pin controller state id (see PINCTRL_STATES).
• state – Found state.

Return values
• 0 – If state has been found.
• -ENOTENT – If the state has not been found.
int pinctrl_configure_pins(const pinctrl_soc_pin_t *pins, uint8_t pin_cnt, uintptr_t reg)
Configure a set of pins.
This function will configure the necessary hardware blocks to make the configuration immediately effective.

**Warning:** This function must never be used to configure pins used by an instantiated device driver.

**Parameters**
- `pins` – List of pins to be configured.
- `pin_cnt` – Number of pins.
- `reg` – Device register (optional, use `PINCTRL_REG_NONE` if not used).

**Return values**
- 0 – If succeeded
- -errno – Negative errno for other failures.

static inline int pinctrl_apply_state_direct(const struct pinctrl_dev_config *config, const struct pinctrl_state *state)
Apply a state directly from the provided state configuration.

**Parameters**
- `config` – Pin control configuration.
- `state` – State.

**Return values**
- 0 – If succeeded
- -errno – Negative errno for other failures.

static inline int pinctrl_apply_state(const struct pinctrl_dev_config *config, uint8_t id)
Apply a state from the given device configuration.

**Parameters**
- `config` – Pin control configuration.
- `id` – Id of the state to be applied (see `PINCTRL_STATES`).

**Return values**
- 0 – If succeeded.
- -ENOENT – If given state id does not exist.
- -errno – Negative errno for other failures.

struct pinctrl_state

`#include <pinctrl.h>` Pin control state configuration.

**Public Members**

const pinctrl_soc_pin_t *pins
Pin configurations.
uint8_t pin_cnt
   Number of pin configurations.

uint8_t id
   State identifier (see PINCTRL_STATES).

struct pinctrl_dev_config
#include <pinctrl.h> Pin controller configuration for a given device.

Public Members

uintptr_t reg
   Device address (only available if CONFIG_PINCTRL_STORE_REG is enabled).

const struct pinctrl_state *states
   List of state configurations.

uint8_t state_cnt
   Number of state configurations.

Dynamic pin control

group pinctrl_interface_dynamic

Defines

PINCTRL_DT_STATE_PINS_DEFINE(node_id, prop)
   Helper macro to define the pins of a pin control state from Devicetree.

   The name of the defined state pins variable is the same used by prop. This macro is expected
   to be used in conjunction with PINCTRL_DT_STATE_INIT.

   See also:

PINCTRL_DT_STATE_INIT

Parameters

   • node_id – Node identifier containing prop.
   • prop – Property within node_id containing state configuration.

PINCTRL_DT_STATE_INIT(prop, state)
   Utility macro to initialize a pin control state.

   This macro should be used in conjunction with PINCTRL_DT_STATE_PINS_DEFINE when using
   dynamic pin control to define an alternative state configuration stored in Devicetree.

   Example:
// board.dts
/
{
  zephyr, user {
    // uart0_alt_default node contains alternative pin config
    uart0_alt_default = <&uart0_alt_default>;
  };
};

// application
PINCTRL_DT_STATE_PINS_DEFINE(DT_PATH(zephyr_user), uart0_alt_default);

static const struct pinctrl_state uart0_alt[] = {
  PINCTRL_DT_STATE_INIT(uart0_alt_default, PINCTRL_STATE_DEFAULT)
};

See also:
PINCTRL_DT_STATE_PINS_DEFINE

Parameters

- prop – Property name in Devicetree containing state configuration.
- state – State represented by prop (see PINCTRL_STATES).

Functions

int pinctrl_update_states(struct pinctrl_dev_config *config, const struct pinctrl_state *states,
                           uint8_t state_cnt)

Update states with a new set.

Note: In order to guarantee device drivers correct operation the same states have to be provided. For example, if default and sleep are in the current list of states, it is expected that the new array of states also contains both.

Parameters

- config – Pin control configuration.
- states – New states to be set.
- state_cnt – Number of new states to be set.

Return values

- EINVAL – If the new configuration does not contain the same states as the current active configuration.
- ENOSYS – If the functionality is not available.
- 0 – On success.
7.4.7 Other reference material

- Introduction to pin muxing and GPIO control under Linux

7.5 Porting

These pages document how to port Zephyr to new hardware.

7.5.1 Architecture Porting Guide

An architecture port is needed to enable Zephyr to run on an ISA (instruction set architecture) or an ABI (Application Binary Interface) that is not currently supported.

The following are examples of ISAs and ABIs that Zephyr supports:

- x86_32 ISA with System V ABI
- ARMv7-M ISA with Thumb2 instruction set and ARM Embedded ABI (aeabi)
- ARCv2 ISA

For information on Kconfig configuration, see Setting Kconfig configuration values. Architectures use a Kconfig configuration scheme similar to boards.

An architecture port can be divided in several parts; most are required and some are optional:

- **The early boot sequence**: each architecture has different steps it must take when the CPU comes out of reset (required).
- **Interrupt and exception handling**: each architecture handles asynchronous and unrequested events in a specific manner (required).
- **Thread context switching**: the Zephyr context switch is dependent on the ABI and each ISA has a different set of registers to save (required).
- **Thread creation and termination**: a thread's initial stack frame is ABI and architecture-dependent, and thread abortion possibly as well (required).
- **Device drivers**: most often, the system clock timer and the interrupt controller are tied to the architecture (some required, some optional).
- **Utility libraries**: some common kernel APIs rely on an architecture-specific implementation for performance reasons (required).
- **CPU idling/power management**: most architectures implement instructions for putting the CPU to sleep (partly optional, most likely very desired).
- **Fault management**: for implementing architecture-specific debug help and handling of fatal error in threads (partly optional).
- **Linker scripts and toolchains**: architecture-specific details will most likely be needed in the build system and when linking the image (required).

**Early Boot Sequence**

The goal of the early boot sequence is to take the system from the state it is after reset to a state where it can run C code and thus the common kernel initialization sequence. Most of the time, very few steps are needed, while some architectures require a bit more work to be performed.

Common steps for all architectures:

- Setup an initial stack.
• If running an XIP (eXecute-In-Place) kernel, copy initialized data from ROM to RAM.
• If not using an ELF loader, zero the BSS section.
• Jump to _Cstart(), the early kernel initialization
  – _Cstart() is responsible for context switching out of the fake context running at startup into the main thread.

Some examples of architecture-specific steps that have to be taken:
• If given control in real mode on x86_32, switch to 32-bit protected mode.
• Setup the segment registers on x86_32 to handle boot loaders that leave them in an unknown or broken state.
• Initialize a board-specific watchdog on Cortex-M3/4.
• Switch stacks from MSP to PSP on Cortex-M.
• Use a different approach than calling into _Swap() on Cortex-M to prevent race conditions.
• Setup FIRQ and regular IRQ handling on ARCv2.

Interrupt and Exception Handling

Each architecture defines interrupt and exception handling differently. When a device wants to signal the processor that there is some work to be done on its behalf, it raises an interrupt. When a thread does an operation that is not handled by the serial flow of the software itself, it raises an exception. Both, interrupts and exceptions, pass control to a handler. The handler is known as an ISR (Interrupt Service Routine) in the case of interrupts. The handler performs the work required by the exception or the interrupt. For interrupts, that work is device-specific. For exceptions, it depends on the exception, but most often the core kernel itself is responsible for providing the handler.

The kernel has to perform some work in addition to the work the handler itself performs. For example:

• Prior to handing control to the handler:
  – Save the currently executing context.
  – Possibly getting out of power saving mode, which includes waking up devices.
  – Updating the kernel uptime if getting out of tickless idle mode.
• After getting control back from the handler:
  – Decide whether to perform a context switch.
  – When performing a context switch, restore the context being context switched in.

This work is conceptually the same across architectures, but the details are completely different:
• The registers to save and restore.
• The processor instructions to perform the work.
• The numbering of the exceptions.
• etc.

It thus needs an architecture-specific implementation, called the interrupt/exception stub.

Another issue is that the kernel defines the signature of ISRs as:

```c
void (*isr)(void *parameter)
```

Architectures do not have a consistent or native way of handling parameters to an ISR. As such there are two commonly used methods for handling the parameter.
• Using some architecture defined mechanism, the parameter value is forced in the stub. This is commonly found in X86-based architectures.

• The parameters to the ISR are inserted and tracked via a separate table requiring the architecture to discover at runtime which interrupt is executing. A common interrupt handler demuxer is installed for all entries of the real interrupt vector table, which then fetches the device's ISR and parameter from the separate table. This approach is commonly used in the ARC and ARM architectures via the `CONFIG_GEN_ISR_TABLES` implementation. You can find examples of the stubs by looking at `_interrupt_enter()` in x86, `_IntExit()` in ARM, `_isr_wrapper()` in ARM, or the full implementation description for ARC in `arch/arc/core/isr_wrapper.S`.

Each architecture also has to implement primitives for interrupt control:

- locking interrupts: `irq_lock()`, `irq_unlock()`.
- registering interrupts: `IRQ_CONNECT()`.
- programming the priority if possible `irq_priority_set()`.
- enabling/disabling interrupts: `irq_enable()`, `irq_disable()`.

**Note:** `IRQ_CONNECT` is a macro that uses assembler and/or linker script tricks to connect interrupts at build time, saving boot time and text size.

The vector table should contain a handler for each interrupt and exception that can possibly occur. The handler can be as simple as a spinning loop. However, we strongly suggest that handlers at least print some debug information. The information helps figuring out what went wrong when hitting an exception that is a fault, like divide-by-zero or invalid memory access, or an interrupt that is not expected (spurious interrupt). See the ARM implementation in `arch/arm/core/aarch32/cortex_m/fault.c` for an example.

**Thread Context Switching**

Multi-threading is the basic purpose to have a kernel at all. Zephyr supports two types of threads: preemptible and cooperative.

Two crucial concepts when writing an architecture port are the following:

- Cooperative threads run at a higher priority than preemptible ones, and always preempt them.
- After handling an interrupt, if a cooperative thread was interrupted, the kernel always goes back to running that thread, since it is not preemptible.

A context switch can happen in several circumstances:

- When a thread executes a blocking operation, such as taking a semaphore that is currently unavailable.
- When a preemptible thread unblocks a thread of higher priority by releasing the object on which it was blocked.
- When an interrupt unblocks a thread of higher priority than the one currently executing, if the currently executing thread is preemptible.
- When a thread runs to completion.
- When a thread causes a fatal exception and is removed from the running threads. For example, referencing invalid memory,

Therefore, the context switching must thus be able to handle all these cases.

The kernel keeps the next thread to run in a “cache”, and thus the context switching code only has to fetch from that cache to select which thread to run.

There are two types of context switches: **cooperative** and **preemptive**.
• A **cooperative** context switch happens when a thread willfully gives the control to another thread. There are two cases where this happens
  - When a thread explicitly yields.
  - When a thread tries to take an object that is currently unavailable and is willing to wait until the object becomes available.

• A **preemptive** context switch happens either because an ISR or a thread causes an operation that schedules a thread of higher priority than the one currently running, if the currently running thread is preemptible. An example of such an operation is releasing an object on which the thread of higher priority was waiting.

**Note:** Control is never taken from cooperative thread when one of them is the running thread.

A cooperative context switch is always done by having a thread call the \_Swap() kernel internal symbol. When \_Swap is called, the kernel logic knows that a context switch has to happen: \_Swap does not check to see if a context switch must happen. Rather, \_Swap decides what thread to context switch in. \_Swap is called by the kernel logic when an object being operated on is unavailable, and some thread yielding/sleeping primitives.

**Note:** On x86 and Nios2, \_Swap is generic enough and the architecture flexible enough that \_Swap can be called when exiting an interrupt to provoke the context switch. This should not be taken as a rule, since neither the ARM Cortex-M or ARCv2 port do this.

Since \_Swap is cooperative, the caller-saved registers from the ABI are already on the stack. There is no need to save them in the k_thread structure.

A context switch can also be performed preemptively. This happens upon exiting an ISR, in the kernel interrupt exit stub:

- \_interrupt\_enter on x86 after the handler is called.
- \_IntExit on ARM.
- \_firq\_exit and \_rirq\_exit on ARCv2.

In this case, the context switch must only be invoked when the interrupted thread was preemptible, not when it was a cooperative one, and only when the current interrupt is not nested.

The kernel also has the concept of “locking the scheduler”. This is a concept similar to locking the interrupts, but lighter-weight since interrupts can still occur. If a thread has locked the scheduler, is it temporarily non-preemptible.

So, the decision logic to invoke the context switch when exiting an interrupt is simple:

- If the interrupted thread is not preemptible, do not invoke it.
- Else, fetch the cached thread from the ready queue, and:
  - If the cached thread is not the current thread, invoke the context switch.
  - Else, do not invoke it.

This is simple, but crucial: if this is not implemented correctly, the kernel will not function as intended and will experience bizarre crashes, mostly due to stack corruption.

**Note:** If running a coop-only system, i.e. if CONFIG\_NUM\_PREEMPT\_PRIORITIES is 0, no preemptive context switch ever happens. The interrupt code can be optimized to not take any scheduling decision when this is the case.
Thread Creation and Termination

To start a new thread, a stack frame must be constructed so that the context switch can pop it the same way it would pop one from a thread that had been context switched out. This is to be implemented in an architecture-specific new_thread internal routine.

The thread entry point is also not to be called directly, i.e. it should not be set as the PC (program counter) for the new thread. Rather it must be wrapped in thread_entry. This means that the PC in the stack frame shall be set to thread_entry, and the thread entry point shall be passed as the first parameter to thread_entry. The specifics of this depend on the ABI.

The need for an architecture-specific thread termination implementation depends on the architecture. There is a generic implementation, but it might not work for a given architecture.

One reason that has been encountered for having an architecture-specific implementation of thread termination is that aborting a thread might be different if aborting because of a graceful exit or because of an exception. This is the case for ARM Cortex-M, where the CPU has to be taken out of handler mode if the thread triggered a fatal exception, but not if the thread gracefully exits its entry point function.

This means implementing an architecture-specific version of k_thread_abort(), and setting the Kconfig option CONFIG_ARCH_HAS_THREAD_ABORT as needed for the architecture (e.g. see arch/arm/core/aarch32/cortex_m/Kconfig).

Thread Local Storage

To enable thread local storage on a new architecture:

1. Implement arch_tls_stack_setup() to setup the TLS storage area in stack. Refer to the toolchain documentation on how the storage area needs to be structured. Some helper functions can be used:
   - Function z_tls_data_size() returns the size needed for thread local variables (excluding any extra data required by toolchain and architecture).
   - Function z_tls_copy() prepares the TLS storage area for thread local variables. This only copies the variable themselves and does not do architecture and/or toolchain specific data.

2. In the context switching, grab the tls field inside the new thread’s struct k_thread and put it into an appropriate register (or some other variable) for access to the TLS storage area. Refer to toolchain and architecture documentation on which registers to use.

3. In kconfig, add select CONFIG_ARCH_HAS_THREAD_LOCAL_STORAGE to kconfig related to the new architecture.

4. Run the tests/kernel/threads/tls to make sure the new code works.

Device Drivers

The kernel requires very few hardware devices to function. In theory, the only required device is the interrupt controller, since the kernel can run without a system clock. In practice, to get access to most, if not all, of the sanity check test suite, a system clock is needed as well. Since these two are usually tied to the architecture, they are part of the architecture port.

Interrupt Controllers  There can be significant differences between the interrupt controllers and the interrupt concepts across architectures.

For example, x86 has the concept of an IDT and different interrupt controllers. The position of an interrupt in the IDT determines its priority.

On the other hand, the ARM Cortex-M has the NVIC (Nested Vectored Interrupt Controller) as part of the architecture definition. There is no need for an IDT-like table that is separate from the NVIC vector
table. The position in the table has nothing to do with priority of an IRQ: priorities are programmable per-entry.

The ARChitectural Vector (ARCv2) has its interrupt unit as part of the architecture definition, which is somewhat similar to the NVIC. However, where ARC defines interrupts as having a one-to-one mapping between exception and interrupt numbers (i.e. exception 1 is IRQ1, and device IRQs start at 16), ARM has IRQ0 being equivalent to exception 16 (and weirdly enough, exception 1 can be seen as IRQ-15).

All these differences mean that very little, if anything, can be shared between architectures with regards to interrupt controllers.

System Clock  

x86 has APIC timers and the HPET as part of its architecture definition. ARM Cortex-M has the SYSTICK exception. Finally, ARCv2 has the timer0/1 device.

Kernel timeouts are handled in the context of the system clock timer driver's interrupt handler.

Console Over Serial Line  

There is one other device that is almost a requirement for an architecture port, since it is so useful for debugging. It is a simple polling, output-only, serial port driver on which to send the console (printf, printk) output.

It is not required, and a RAM console (CONFIG_RAM_CONSOLE) can be used to send all output to a circular buffer that can be read by a debugger instead.

Utility Libraries

The kernel depends on a few functions that can be implemented with very few instructions or in a lockless manner in modern processors. Those are thus expected to be implemented as part of an architecture port.

- Atomic operators.
  - If instructions do exist for a given architecture, the implementation is configured using the CONFIG_ATOMIC_OPERATIONS_ARCH Kconfig option.
  - If instructions do not exist for a given architecture, a generic version that wraps irq_lock() or irq_unlock() around non-atomic operations exists. It is configured using the CONFIG_ATOMIC_OPERATIONS_C Kconfig option.

- Find-least-significant-bit-set and find-most-significant-bit-set.
  - If instructions do not exist for a given architecture, it is always possible to implement these functions as generic C functions.

It is possible to use compiler built-ins to implement these, but be careful they use the required compiler barriers.

CPU Idling/Power Management

The kernel provides support for CPU power management with two functions: arch_cpu_idle() and arch_cpu_atomic_idle().

arch_cpu_idle() can be as simple as calling the power saving instruction for the architecture with interrupts unlocked, for example hlt on x86, wfi or wfe on ARM, sleep on ARC. This function can be called in a loop within a context that does not care if it get interrupted or not by an interrupt before going to sleep. There are basically two scenarios when it is correct to use this function:

- In a single-threaded system, in the only thread when the thread is not used for doing real work after initialization, i.e. it is sitting in a loop doing nothing for the duration of the application.
- In the idle thread.
arch_cpu_atomic_idle(), on the other hand, must be able to atomically re-enable interrupts and invoke the power saving instruction. It can thus be used in real application code, again in single-threaded systems.

Normally, idling the CPU should be left to the idle thread, but in some very special scenarios, these APIs can be used by applications.

Both functions must exist for a given architecture. However, the implementation can be simply the following steps, if desired:

1. unlock interrupts
2. NOP

However, a real implementation is strongly recommended.

Fault Management

In the event of an unhandled CPU exception, the architecture code must call into z_fatal_error(). This function dumps out architecture-agnostic information and makes a policy decision on what to do next by invoking k_sys_fatal_error(). This function can be overridden to implement application-specific policies that could include locking interrupts and spinning forever (the default implementation) or even powering off the system (if supported).

Toolchain and Linking

Toolchain support has to be added to the build system.

Some architecture-specific definitions are needed in include/zephyr/toolchain/gcc.h. See what exists in that file for currently supported architectures.

Each architecture also needs its own linker script, even if most sections can be derived from the linker scripts of other architectures. Some sections might be specific to the new architecture, for example the SCB section on ARM and the IDT section on x86.

Memory Management

If the target platform enables paging and requires drivers to memory-map their I/O regions, CONFIG_MMU needs to be enabled and the following API implemented:

- arch_mem_map()
- arch_mem_unmap()
- arch_page_phys_get()

Stack Objects

The presence of memory protection hardware affects how stack objects are created. All architecture ports must specify the required alignment of the stack pointer, which is some combination of CPU and ABI requirements. This is defined in architecture headers with ARCH_STACK_PTR_ALIGN and is typically something small like 4, 8, or 16 bytes.

Two types of thread stacks exist:

- “kernel” stacks defined with K_KERNEL_STACK_DEFINE() and related APIs, which can host kernel threads running in supervisor mode or used as the stack for interrupt/exception handling. These have significantly relaxed alignment requirements and use less reserved data. No memory is reserved for privilege elevation stacks.
“thread” stacks which typically use more memory, but are capable of hosting thread running in user mode, as well as any use-cases for kernel stacks.

If CONFIG_USERSPACE is not enabled, “thread” and “kernel” stacks are equivalent.

Additional macros may be defined in the architecture layer to specify the alignment of the base of stack objects, any reserved data inside the stack object not used for the thread's stack buffer, and how to round up stack sizes to support user mode threads. In the absence of definitions some defaults are assumed:

- ARCH_KERNEL_STACK_RESERVED: default no reserved space
- ARCH_THREAD_STACK_RESERVED: default no reserved space
- ARCH_KERNEL_STACK_OBJ_ALIGN: default align to ARCH_STACK_PTR_ALIGN
- ARCH_THREAD_STACK_OBJ_ALIGN: default align to ARCH_STACK_PTR_ALIGN
- ARCH_THREAD_STACK_SIZE_ALIGN: default round up to ARCH_STACK_PTR_ALIGN

All stack creation macros are defined in terms of these.

Stack objects all have the following layout, with some regions potentially zero-sized depending on configuration. There are always two main parts: reserved memory at the beginning, and then the stack buffer itself. The bounds of some areas can only be determined at runtime in the context of its associated thread object. Other areas are entirely computable at build time.

Some architectures may need to carve-out reserved memory at runtime from the stack buffer, instead of unconditionally reserving it at build time, or to supplement an existing reserved area (as is the case with the ARM FPU). Such carve-outs will always be tracked in thread.stack_info.start. The region specified by thread.stack_info.start and thread.stack_info.size is always fully accessible by a user mode thread. thread.stack_info.delta denotes an offset which can be used to compute the initial stack pointer from the very end of the stack object, taking into account storage for TLS and ASLR random offsets.

At present, Zephyr does not support stacks that grow upward.

No Memory Protection If no memory protection is in use, then the defaults are sufficient.

HW-based stack overflow detection This option uses hardware features to generate a fatal error if a thread in supervisor mode overflows its stack. This is useful for debugging, although for a couple reasons, you can’t reliably make any assertions about the state of the system after this happens:

- The kernel could have been inside a critical section when the overflow occurs, leaving important global data structures in a corrupted state.
For systems that implement stack protection using a guard memory region, it’s possible to overshoot the guard and corrupt adjacent data structures before the hardware detects this situation.

To enable the CONFIG_HW_STACK_PROTECTION feature, the system must provide some kind of hardware-based stack overflow protection, and enable the CONFIG_ARCH_HAS_STACK_PROTECTION option.

Two forms of HW-based stack overflow detection are supported: dedicated CPU features for this purpose, or special read-only guard regions immediately preceding stack buffers.

CONFIG_HW_STACK_PROTECTION only catches stack overflows for supervisor threads. This is not required to catch stack overflow from user threads; CONFIG_USERSPACE is orthogonal.

This feature only detects supervisor mode stack overflows, including stack overflows when handling system calls. It doesn’t guarantee that the kernel has not been corrupted. Any stack overflow in supervisor mode should be treated as a fatal error, with no assertions about the integrity of the overall system possible.

Stack overflows in user mode are recoverable (from the kernel’s perspective) and require no special configuration; CONFIG_HW_STACK_PROTECTION only applies to catching overflows when the CPU is in supervisor mode.

**CPU-based stack overflow detection** If we are detecting stack overflows in supervisor mode via special CPU registers (like ARM’s SPLIM), then the defaults are sufficient.

**Guard-based stack overflow detection** We are detecting supervisor mode stack overflows via special memory protection region located immediately before the stack buffer that generates an exception on write. Reserved memory will be used for the guard region.

ARCH_KERNEL_STACK_RESERVED should be defined to the minimum size of a memory protection region. On most ARM CPUs this is 32 bytes. ARCH_KERNEL_STACK_OBJ_ALIGN should also be set to the required alignment for this region.

MMU-based systems should not reserve RAM for the guard region and instead simply leave an non-present virtual page below every stack when it is mapped into the address space. The stack object will still need to be properly aligned and sized to page granularity.

Guard carve-outs for kernel stacks are uncommon and should be avoided if possible. They tend to be needed for two situations:

- The same stack may be re-purposed to host a user thread, in which case the guard is unnecessary and shouldn’t be unconditionally reserved. This is the case when privilege elevation stacks are not inside the stack object.
- The required guard size is variable and depends on context. For example, some ARM CPUs have lazy floating point stacking during exceptions and may decrement the stack pointer by a large value without writing anything, completely overshooting a minimally-sized guard and corrupting adjacent memory. Rather than unconditionally reserving a larger guard, the extra memory is carved out if the thread uses floating point.

**User mode enabled** Enabling user mode activates two new requirements:

- A separate fixed-sized privilege mode stack, specified by CONFIG_PRIVILEGED_STACK_SIZE, must be allocated that the user thread cannot access. It is used as the stack by the kernel when handling...
system calls. If stack guards are implemented, a stack guard region must be able to be placed before it, with support for carve-outs if necessary.

- The memory protection hardware must be able to program a region that exactly covers the thread's stack buffer, tracked in thread.stack_info. This implies that ARCH_THREAD_STACK_SIZE_ADJUST() will need to round up the requested stack size so that a region may cover it, and that ARCH_THREAD_STACK_OBJ_ALIGN() is also specified per the granularity of the memory protection hardware.

This becomes more complicated if the memory protection hardware requires that all memory regions be sized to a power of two, and aligned to their own size. This is common on older MPUs and is known with CONFIG_MPUQUIRES_POWER_OF_TWO_ALIGNMENT.

thread.stack_info always tracks the user-accessible part of the stack object, it must always be correct to program a memory protection region with user access using the range stored within.

Non power-of-two memory region requirements On systems without power-of-two region requirements, the reserved memory area for threads stacks defined by K_THREAD_STACK_RESERVED may be used to contain the privilege mode stack. The layout could be something like:

```
+-------------------------------+ <- thread.stack_obj
| Other platform data |
+-------------------------------+
| Guard region (if enabled) |
+-------------------------------+
| Guard carve-out (if needed) |
|..............................|
| Privilege elevation stack |
+-------------------------------+ <- thread.stack_obj |
K_THREAD_STACK_RESERVED = thread.stack_info.start
```

The guard region, and any carve-out (if needed) would be configured as a read-only region when the thread is created.

- If the thread is a supervisor thread, the privilege elevation region is just extra stack memory. An overflow will eventually crash into the guard region.
- If the thread is running in user mode, a memory protection region will be configured to allow user threads access to the stack buffer, but nothing before or after it. An overflow in user mode will crash into the privilege elevation stack, which the user thread has no access to. An overflow when handling a system call will crash into the guard region.

On an MMU system there should be no physical guards; the privilege mode stack will be mapped into kernel memory, and the stack buffer in the user part of memory, each with non-present virtual guard pages below them to catch runtime stack overflows.

Other platform data may be stored before the guard region, but this is highly discouraged if such data could be stored in thread.arch somewhere.

ARCH_THREAD_STACK_RESERVED will need to be defined to capture the size of the reserved region containing platform data, privilege elevation stacks, and guards. It must be appropriately sized such that an MPU region to grant user mode access to the stack buffer can be placed immediately after it.

Power-of-two memory region requirements Thread stack objects must be sized and aligned to the same power of two, without any reserved memory to allow efficient packing in memory. Thus, any guards in the thread stack must be completely carved out, and the privilege elevation stack must be allocated elsewhere.

ARCH_THREAD_STACK_SIZE_ADJUST() and ARCH_THREAD_STACK_OBJ_ALIGN() should both be defined to Z_POW2_CEIL(). K_THREAD_STACK_RESERVED must be 0.
For the privilege stacks, the `CONFIG_GEN_PRIV_STACKS` must be enabled. For every thread stack found in the system, a corresponding fixed-size kernel stack used for handling system calls is generated. The address of the privilege stacks can be looked up quickly at runtime based on the thread stack address using `z_priv_stack_find()`. These stacks are laid out the same way as other kernel-only stacks.

```
+-----------------------------+ <- z_priv_stack_find(thread.stack_obj)
 | Reserved memory            |
+-----------------------------+ \} K_KERNEL_STACK_RESERVED
+-----------------------------+ <- z_priv_stack_find(thread.stack_obj) +
   | Guard carve-out (if needed)|
   | Privilege elevation stack |
+-----------------------------+ <- thread.stack_obj
+-----------------------------+ <- thread.stack_info.start
   | MPU guard carve-out        |
   | (supervisor mode only)     |
   |.............................|
   | Stack buffer              |
```

The guard carve-out in the thread stack object is only used if the thread is running in supervisor mode. If the thread drops to user mode, there is no guard and the entire object is used as the stack buffer, with full access to the associated user mode thread and `thread.stack_info` updated appropriately.

**User Mode Threads**

To support user mode threads, several kernel-to-arch APIs need to be implemented, and the system must enable the `CONFIG_ARCH_HAS USERSPACE` option. Please see the documentation for each of these functions for more details:

- `arch_buffer_validate()` to test whether the current thread has access permissions to a particular memory region
- `arch_user_mode_enter()` which will irreversibly drop a supervisor thread to user mode privileges. The stack must be wiped.
- `arch_syscall_oops()` which generates a kernel oops when system call parameters can’t be validated, in such a way that the oops appears to be generated from where the system call was invoked in the user thread
- `arch_syscall_invoke0()` through `arch_syscall_invoke6()` invoke a system call with the appropriate number of arguments which must all be passed in during the privilege elevation via registers.
- `arch_is_user_context()` return nonzero if the CPU is currently running in user mode
- `arch_mem_domain_max_partitions_get()` which indicates the max number of regions for a memory domain. MMU systems have an unlimited amount, MPU systems have constraints on this.

Some architectures may need to update software memory management structures or modify hardware registers on another CPU when memory domain APIs are invoked. If so, `CONFIG_ARCH_MEM_DOMAIN_SYNCHRONOUS_API` must be selected by the architecture and some additional APIs must be implemented. This is common on MMU systems and uncommon on MPU systems:

- `arch_mem_domain_thread_add()`
- `arch_mem_domain_thread_remove()`
- `arch_mem_domain_partition_add()`
arch_mem_domain_partition_remove()

Please see the doxygen documentation of these APIs for details.

In addition to implementing these APIs, there are some other tasks as well:

- `_new_thread()` needs to spawn threads with `K_USER` in user mode.
- On context switch, the outgoing thread’s stack memory should be marked inaccessible to user mode by making the appropriate configuration changes in the memory management hardware. The incoming thread’s stack memory should likewise be marked as accessible. This ensures that threads can’t mess with other thread stacks.
- On context switch, the system needs to switch between memory domains for the incoming and outgoing threads.
- Thread stack areas must include a kernel stack region. This should be inaccessible to user threads at all times. This stack will be used when system calls are made. This should be fixed size for all threads, and must be large enough to handle any system call.
- A software interrupt or some kind of privilege elevation mechanism needs to be established. This is closely tied to how the `_arch_syscall_invoke` macros are implemented. On system call, the appropriate handler function needs to be looked up in `_k_syscall_table`. Bad system call IDs should jump to the `K_SYSCALL_BAD` handler. Upon completion of the system call, care must be taken not to leak any register state back to user mode.

GDB Stub

To enable GDB stub for remote debugging on a new architecture:

1. Create a new `gdbstub.h` header file under appropriate architecture include directory (`include/arch/<arch>/gdbstub.h`).
   - Create a new struct `struct gdb_ctx` as the GDB context.
     - Must define a member named `exception` of type `unsigned int` to store the GDB exception reason. This value needs to be set before entering `z_gdb_main_loop()`.
     - Architecture can define as many members as needed for GDB stub to function.
     - Pointer to this struct needs to be passed to `z_gdb_main_loop()`, where this pointer will be passed to other GDB stub functions.

2. Functions for entering and exiting GDB stub main loop.
   - If the architecture relies on interrupts to service breakpoints, interrupt service routines (ISR) need to be implemented, which will serve as the entry point to GDB stub main loop.
   - These functions need to save and restore context so code execution can continue as if no breakpoints have been encountered.
   - These functions need to call `z_gdb_main_loop()` after saving execution context to go into the GDB stub main loop to receive commands from GDB.
   - Before calling `z_gdb_main_loop()`, `gdb_ctx.exception` must be set to specify the exception reason.

3. Implement necessary functions to support GDB stub functionality:
   - `arch_gdb_init()`
     - This needs to initialize necessary bits to support GDB stub functionality, for example, setting up the GDB context and connecting debug interrupts.
     - This must stop code execution via architecture specific method (e.g. raising debug interrupts). This allows GDB to connect during boot.
   - `arch_gdb_continue()`
This function is called when GDB sends a `c` or `continue` command to continue code execution.

- **arch_gdb_step()**
  - This function is called when GDB sends a `si` or `stepi` command to execute one machine instruction, before returning to GDB prompt.

**Hardware register read/write functions:**

- Since the GDB stub is running on the target, manipulation of hardware registers need to be cached to avoid affecting the execution of GDB stub. Think of it as context switching, where the execution context is changed to the GDB stub. So that the register values of the running thread before context switch need to be stored. Manipulation of register values must only be done to this cached copy. The updated values will then be written to hardware registers before switching back to the previous running thread.

  - **arch_gdb_reg_readall()**
    - This collects all hardware register values that would appear in a g/G packets which will be sent back to GDB. The format of the G-packet is architecture specific. Consult GDB on what is expected.
    - Note that, for most architectures, a valid G-packet must be returned and sent to GDB. If a packet without incorrect length is sent to GDB, GDB will abort the debugging session.

  - **arch_gdb_reg_writeall()**
    - This takes a G-packet sent by GDB and populates the hardware registers with values from the G-packet.

  - **arch_gdb_reg_readone()**
    - This reads the value of one hardware register and sends the result to GDB.

  - **arch_gdb_reg_writeone()**
    - This writes the value of one hardware register received from GDB.

**Breakpoints:**

- **arch_gdb_add_breakpoint()** and **arch_gdb_remove_breakpoint()**

  - GDB may decide to use software breakpoints which modifies the memory at the breakpoint locations to replace the instruction with software breakpoint or trap instructions. GDB will then restore the memory content once execution reaches the breakpoints. GDB supports this by default and there is usually no need to handle software breakpoints in the architecture code (where breakpoint type is 0).

  - Hardware breakpoints (type 1) are required if the code is in ROM or flash that cannot be modified at runtime. Consult the architecture datasheet on how to enable hardware breakpoints.

  - If hardware breakpoints are not supported by the architecture, there is no need to implement these in architecture code. GDB will then rely on software breakpoints.

4. For architecture where certain memory regions are not accessible, an array named `gdb_mem_region_array` of type `gdb_mem_region` needs to be defined to specify regions that are accessible. For each array item:

  - `gdb_mem_region.start` specifies the start of a memory region.
  - `gdb_mem_region.end` specifies the end of a memory region.
  - `gdb_mem_region.attributes` specifies the permission of a memory region.
    - `GDB_MEM_REGION_RO`: region is read-only.
    - `GDB_MEM_REGION_RW`: region is read-write.
• *gdb_mem_region.alignment* specifies read/write alignment of a memory region. Use 0 if there is no alignment requirement and read/write can be done byte-by-byte.

**API Reference**

**Timing**

group arch-timing

**Unnamed Group**

```c
void arch_timing_init(void)
    Initialize the timing subsystem.
    Perform the necessary steps to initialize the timing subsystem.

    See also:
    timing_init()
```

```c
void arch_timing_start(void)
    Signal the start of the timing information gathering.
    Signal to the timing subsystem that timing information will be gathered from this point forward.

    See also:
    timing_start()
```

**Note:** Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

```c
void arch_timing_stop(void)
    Signal the end of the timing information gathering.
    Signal to the timing subsystem that timing information is no longer being gathered from this point forward.

    See also:
    timing_stop()
```

**Note:** Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

```c
timing_t arch_timing_counter_get(void)
    Return timing counter.

    See also:
    timing_counter_get()
```
Note: Any call to `arch_timing_counter_get()` must be done between calls to `arch_timing_start()` and `arch_timing_stop()`, and on the same CPU core.

Note: Not all platforms have a timing counter with 64 bit precision. It is possible to see this value “go backwards” due to internal rollover. Timing code must be prepared to address the rollover (with platform-dependent code, e.g. by casting to a `uint32_t` before subtraction) or by using `arch_timing_cycles_get()` which is required to understand the distinction.

Returns
Timing counter.

```c
uint64_t arch_timing_cycles_get(volatile timing_t *const start, volatile timing_t *const end)
```

Get number of cycles between `start` and `end`.

For some architectures or SoCs, the raw numbers from counter need to be scaled to obtain actual number of cycles, or may roll over internally. This function computes a positive-definite interval between two returned cycle values.

See also:
`timing_cycles_get()`

Parameters
- `start` – Pointer to counter at start of a measured execution.
- `end` – Pointer to counter at stop of a measured execution.

Returns
Number of cycles between start and end.

```c
uint64_t arch_timing_freq_get(void)
```

Get frequency of counter used (in Hz).

See also:
`timing_freq_get()`

Returns
Frequency of counter used for timing in Hz.

```c
uint64_t arch_timing_cycles_to_ns(uint64_t cycles)
```

Convert number of cycles into nanoseconds.

See also:
`timing_cycles_to_ns()`

Parameters
- `cycles` – Number of cycles

Returns
Converted time value
uint64_t arch_timing_cycles_to_ns_avg(uint64_t cycles, uint32_t count)

Convert number of cycles into nanoseconds with averaging.

See also:

timing_cycles_to_ns_avg()

Parameters

• cycles – Number of cycles
• count – Times of accumulated cycles to average over

Returns

Converted time value

uint32_t arch_timing_freq_get_mhz(void)

Get frequency of counter used (in MHz).

See also:

timing_freq_get_mhz()

Returns

Frequency of counter used for timing in MHz.

Functions

void arch_busy_wait(uint32_t usec_to_wait)

Architecture-specific implementation of busy-waiting

Parameters

• usec_to_wait – Wait period, in microseconds

static inline uint32_t arch_k_cycle_get_32(void)

Obtain the current cycle count, in units that are hardware-specific

See also:

k_cycle_get_32()

static inline uint64_t arch_k_cycle_get_64(void)

Obtain the current cycle count, in units that are hardware-specific

See also:

k_cycle_get_64()

Threads

group arch-threads
Functions

```c
void arch_new_thread(struct k_thread *thread, k_thread_stack_t *stack, char *stack_ptr,
                     k_thread_entry_t *entry, void *p1, void *p2, void *p3)
```

Handle arch-specific logic for setting up new threads

The stack and arch-specific thread state variables must be set up such that a later attempt to
switch to this thread will succeed and we will enter `z_thread_entry` with the requested thread
and arguments as its parameters.

At some point in this function’s implementation, `z_setup_new_thread()` must be called with
the true bounds of the available stack buffer within the thread’s stack object.

The provided stack pointer is guaranteed to be properly aligned with respect to the CPU and
ABI requirements. There may be space reserved between the stack pointer and the bounds of
the stack buffer for initial stack pointer randomization and thread-local storage.

Fields in `thread->base` will be initialized when this is called.

**Parameters**

- **thread** – Pointer to uninitialized `struct k_thread`
- **stack** – Pointer to the stack object
- **stack_ptr** – Aligned initial stack pointer
- **entry** – Thread entry function
- **p1** – 1st entry point parameter
- **p2** – 2nd entry point parameter
- **p3** – 3rd entry point parameter

```c
static inline void arch_switch(void *switch_to, void **switched_from)
```

Cooperative context switch primitive

The action of `arch_switch()` should be to switch to a new context passed in the first argument,
and save a pointer to the current context into the address passed in the second argument.

The actual type and interpretation of the switch handle is specified by the architecture. It is the same data structure stored in the “switch_handle” field of a newly-created thread in `arch_new_thread()`, and passed to the kernel as the “interrupted” argument to `z_get_next_switch_handle()`.

Note that on SMP systems, the kernel uses the store through the second pointer as a synchro-
nization point to detect when a thread context is completely saved (so another CPU can know
when it is safe to switch). This store must be done AFTER all relevant state is saved, and must
include whatever memory barriers or cache management code is required to be sure another
CPU will see the result correctly.

The simplest implementation of `arch_switch()` is generally to push state onto the thread stack
and use the resulting stack pointer as the switch handle. Some architectures may instead
decide to use a pointer into the thread struct as the “switch handle” type. These can legally
assume that the second argument to `arch_switch()` is the address of the switch_handle field of
struct thread_base and can use an offset on this value to find other parts of the thread struct.

For example a (C pseudocode) implementation of `arch_switch()` might look like:

```c
void arch_switch(void *switch_to, void **switched_from) {
    struct k_thread *new = switch_to;
    struct k_thread *old = CONTAINER_OF(switched_from, struct k_thread,switch_handle);
    // save old context... *switched_from = old; // restore new context... }
```

Note that the kernel manages the switch_handle field for synchronization as described above.
So it is not legal for architecture code to assume that it has any particular value at any other
time. In particular it is not legal to read the field from the address passed in the second argument.
Parameters

- `switch_to` – Incoming thread's switch handle
- `switched_from` – Pointer to outgoing thread's switch handle storage location, which must be updated.

```c
void arch_switch_to_main_thread(struct k_thread *main_thread, char *stack_ptr,
                                k_thread_entry_t _main)
```

Custom logic for entering main thread context at early boot

Used by architectures where the typical trick of setting up a dummy thread in early boot context to “switch out” of isn't workable.

Parameters

- `main_thread` – main thread object
- `stack_ptr` – Initial stack pointer
- `_main` – Entry point for application main function.

```c
int arch_float_disable(struct k_thread *thread)
```

Disable floating point context preservation.

The function is used to disable the preservation of floating point context information for a particular thread.

**Note:** For ARM architecture, disabling floating point preservation may only be requested for the current thread and cannot be requested in ISRs.

```c
int arch_float_enable(struct k_thread *thread, unsigned int options)
```

Enable floating point context preservation.

The function is used to enable the preservation of floating point context information for a particular thread. This API depends on each architecture implementation. If the architecture does not support enabling, this API will always be failed.

The `options` parameter indicates which floating point register sets will be used by the specified thread. Currently it is used by x86 only.

Parameters

- `thread` – ID of thread.
- `options` – architecture dependent options

Return values

- 0 – On success.
- -EINVAL – If the floating point enabling could not be performed.
- -ENOTSUP – If the operation is not supported
Functions

size_t arch_tls_stack_setup(struct k_thread *new_thread, char *stack_ptr)

Setup Architecture-specific TLS area in stack.

This sets up the stack area for thread local storage. The structure inside in area is architecture specific.

Parameters

• new_thread – New thread object
• stack_ptr – Stack pointer

Returns

Number of bytes taken by the TLS area

Power Management

group arch-pm

Functions

FUNC_NORETURN void arch_system_halt(unsigned int reason)

Halt the system, optionally propagating a reason code

void arch_cpu_idle(void)

Power save idle routine.

This function will be called by the kernel idle loop or possibly within an implementation of z_pm_save_idle in the kernel when the ‘_pm_save_flag’ variable is non-zero.

Architectures that do not implement power management instructions may immediately return, otherwise a power-saving instruction should be issued to wait for an interrupt.

See also:

k_cpu_idle()

Note: The function is expected to return after the interrupt that has caused the CPU to exit power-saving mode has been serviced, although this is not a firm requirement.

void arch_cpu_atomic_idle(unsigned int key)

Atomically re-enable interrupts and enter low power mode.

The requirements for arch_cpu_atomic_idle() are as follows:

a. Enabling interrupts and entering a low-power mode needs to be atomic, i.e. there should be no period of time where interrupts are enabled before the processor enters a low-power mode. See the comments in k_lifo_get(), for example, of the race condition that occurs if this requirement is not met.

b. After waking up from the low-power mode, the interrupt lockout state must be restored as indicated in the ‘key’ input parameter.

See also:

k_cpu_atomic_idle()
Parameters

- **key** – Lockout key returned by previous invocation of `arch_irq_lock()`

Symmetric Multi-Processing

group arch-smp

Typedefs

typedef FUNC_NORETURN void (*arch_cpustart_t)(void *data)

Per-cpu entry function

**Param data**
context parameter, implementation specific

Functions

void arch_start_cpu(int cpu_num, k_thread_stack_t *stack, int sz, arch_cpustart_t fn, void *arg)

Start a numbered CPU on a MP-capable system.

This starts and initializes a specific CPU. The main thread on startup is running on CPU zero, other processors are numbered sequentially. On return from this function, the CPU is known to have begun operating and will enter the provided function. Its interrupts will be initialized but disabled such that `irq_unlock()` with the provided key will work to enable them.

Normally, in SMP mode this function will be called by the kernel initialization and should not be used as a user API. But it is defined here for special-purpose apps which want Zephyr running on one core and to use others for design-specific processing.

**Parameters**

- **cpu_num** – Integer number of the CPU
- **stack** – Stack memory for the CPU
- **sz** – Stack buffer size, in bytes
- **fn** – Function to begin running on the CPU.
- **arg** – Untyped argument to be passed to “fn”

bool arch_cpu_active(int cpu_num)

Return CPU power status.

**Parameters**

- **cpu_num** – Integer number of the CPU

static inline struct _cpu *arch_curr_cpu(void)

Return the CPU struct for the currently executing CPU

static inline uint32_t arch_proc_id(void)

Processor hardware ID.

Most multiprocessor architectures have a low-level unique ID value associated with the current CPU that can be retrieved rapidly and efficiently in kernel context. Note that while the numbering of the CPUs is guaranteed to be unique, the values are platform-defined. In particular, they are not guaranteed to match Zephyr's own sequential CPU IDs (even though on some platforms they do).
Note: There is an inherent race with this API: the system may preempt the current thread and migrate it to another CPU before the value is used. Safe usage requires knowing the migration is impossible (e.g. because the code is in interrupt context, holds a spinlock, or cannot migrate due to k_cpu_mask state).

**Returns**
Unique ID for currently-executing CPU

void arch_sched_ipi(void)
Broadcast an interrupt to all CPUs
This will invoke z_sched_ipi() on other CPUs in the system.

static inline unsigned int arch_num_cpus(void)
Returns the number of CPUs.
For most systems this will be the same as CONFIG_MP_MAX_NUM_CPUS, however some systems may determine this at runtime instead.

**Returns**
the number of CPUs

**Interrupts**
group arch-irq

**Functions**

static inline bool arch_is_in_isr(void)
Test if the current context is in interrupt context
XXX: This is inconsistently handled among arches wrt exception context See: #17656

**Returns**
true if we are in interrupt context

static inline unsigned int arch_irq_lock(void)
Lock interrupts on the current CPU

**See also:**
*irq_lock()*

static inline void arch_irq_unlock(unsigned int key)
Unlock interrupts on the current CPU

**See also:**
*irq_unlock()*

static inline bool arch_irq_unlocked(unsigned int key)
Test if calling *arch_irq_unlock()* with this key would unlock irqs

**Parameters**
- key – value returned by *arch_irq_lock()*
Returns
true if interrupts were unlocked prior to the `arch_irq_lock()` call that produced the key argument.

```c
void arch_irq_disable(unsigned int irq)
Disables the specified interrupt line.
```

See also:
`irq_disable()`

Note: The behavior of interrupts that arrive after this call returns and before the corresponding call to `arch_irq_enable()` is undefined. The hardware is not required to latch and deliver such an interrupt, though on some architectures that may work. Other architectures will simply lose such an interrupt and never deliver it. Many drivers and subsystems are not tolerant of such dropped interrupts and it is the job of the application layer to ensure that behavior remains correct.

```c
void arch_irq_enable(unsigned int irq)
Enables the specified interrupt line.
```

See also:
`irq_enable()`

```c
int arch_irq_is_enabled(unsigned int irq)
Tests if an interrupt line is enabled.
```

See also:
`irq_is_enabled()`

```c
int arch_irq_connect_dynamic(unsigned int irq, unsigned int priority, void (*routine)(const void *parameter), const void *parameter, uint32_t flags)
Arch-specific hook to install a dynamic interrupt.
```

Parameters
- `irq` – IRQ line number
- `priority` – Interrupt priority
- `routine` – Interrupt service routine
- `parameter` – ISR parameter
- `flags` – Arch-specific IRQ configuration flag

Returns
The vector assigned to this interrupt

```c
unsigned int arch_irq_allocate(void)
Arch-specific hook for allocating IRQs.
```

Note: disable/enable IRQ relevantly inside the implementation of such function to avoid concurrency issues. Also, an allocated IRQ is assumed to be used thus a following

See also:
`arch_irq_is_used()` should return true.
Returns
The newly allocated IRQ or UINT_MAX on error.

void arch_irq_set_used(unsigned int irq)
Arch-specific hook for declaring an IRQ being used.
Note: disable/enable IRQ relevantly inside the implementation of such function to avoid concurrency issues.

Parameters
• irq – the IRQ to declare being used

bool arch_irq_is_used(unsigned int irq)
Arch-specific hook for checking if an IRQ is being used already.

Parameters
• irq – the IRQ to check

Returns
true if being, false otherwise

Userspace

Functions

static inline uintptr_t arch_syscall_invoke0(uintptr_t call_id)
Invoke a system call with 0 arguments.

No general-purpose register state other than return value may be preserved when transitioning from supervisor mode back down to user mode for security reasons.

It is required that all arguments be stored in registers when elevating privileges from user to supervisor mode.

Processing of the syscall takes place on a separate kernel stack. Interrupts should be enabled when invoking the system call marshallers from the dispatch table. Thread preemption may occur when handling system calls.

Call ids are untrusted and must be bounds-checked, as the value is used to index the system call dispatch table, containing function pointers to the specific system call code.

Parameters
• call_id – System call ID

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke1(uintptr_t arg1, uintptr_t call_id)
Invoke a system call with 1 argument.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke2(uintptr_t arg1, uintptr_t arg2, uintptr_t call_id)
Invoke a system call with 2 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• arg2 – Second argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke3(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t call_id)
Invoke a system call with 3 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• arg2 – Second argument to the system call.
• arg3 – Third argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

Returns
Return value of the system call. Void system calls return 0 here.

static inline uintptr_t arch_syscall_invoke4(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t call_id)
Invoke a system call with 4 arguments.

See also:
arch_syscall_invoke0()

Parameters
• arg1 – First argument to the system call.
• arg2 – Second argument to the system call.
• arg3 – Third argument to the system call.
• arg4 – Fourth argument to the system call.
• call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

**Returns**
Return value of the system call. Void system calls return 0 here.

```c
static inline uintptr_t arch_syscall_invoke5(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t arg5, uintptr_t call_id)
```

Invoke a system call with 5 arguments.

**See also:**
`arch_syscall_invoke0()`

**Parameters**
- arg1 – First argument to the system call.
- arg2 – Second argument to the system call.
- arg3 – Third argument to the system call.
- arg4 – Fourth argument to the system call.
- arg5 – Fifth argument to the system call.
- call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

**Returns**
Return value of the system call. Void system calls return 0 here.

```c
static inline uintptr_t arch_syscall_invoke6(uintptr_t arg1, uintptr_t arg2, uintptr_t arg3, uintptr_t arg4, uintptr_t arg5, uintptr_t arg6, uintptr_t call_id)
```

Invoke a system call with 6 arguments.

**See also:**
`arch_syscallInvoke0()`

**Parameters**
- arg1 – First argument to the system call.
- arg2 – Second argument to the system call.
- arg3 – Third argument to the system call.
- arg4 – Fourth argument to the system call.
- arg5 – Fifth argument to the system call.
- arg6 – Sixth argument to the system call.
- call_id – System call ID, will be bounds-checked and used to reference kernel-side dispatch table

**Returns**
Return value of the system call. Void system calls return 0 here.
static inline bool arch_is_user_context(void)
    Indicate whether we are currently running in user mode

Returns
    true if the CPU is currently running with user permissions

int arch_mem_domain_max_partitions_get(void)
    Get the maximum number of partitions for a memory domain.

Returns
    Max number of partitions, or -1 if there is no limit

int arch_buffer_validate(void *addr, size_t size, int write)
    Check memory region permissions.
    Given a memory region, return whether the current memory management hardware configuration would allow a user thread to read/write that region. Used by system calls to validate buffers coming in from userspace.
    Notes: The function is guaranteed to never return validation success, if the entire buffer area is not user accessible.
    The function is guaranteed to correctly validate the permissions of the supplied buffer, if the user access permissions of the entire buffer are enforced by a single, enabled memory management region.
    In some architectures the validation will always return failure if the supplied memory buffer spans multiple enabled memory management regions (even if all such regions permit user access).

Warning: 0 size buffer has undefined behavior.

Parameters
    • addr – start address of the buffer
    • size – the size of the buffer
    • write – If nonzero, additionally check if the area is writable. Otherwise, just check if the memory can be read.

Returns
    nonzero if the permissions don’t match.

size_t arch_virt_region_align(uintptr_t phys, size_t size)
    Get the optimal virtual region alignment to optimize the MMU table layout
    Some MMU HW requires some region to be aligned to some of the intermediate block alignment in order to reduce table usage. This call returns the optimal virtual address alignment in order to permit such optimization in the following MMU mapping call.

Parameters
    • phys – [in] Physical address of region to be mapped, aligned to MMU_PAGE_SIZE
    • size – [in] Size of region to be mapped, aligned to MMU_PAGE_SIZE

Return values
    alignment – to apply on the virtual address of this region

FUNC_NORETURN void arch_user_mode_enter(k_thread_entry_t user_entry, void *p1, void *p2, void *p3)
Perform a one-way transition from supervisor to kernel mode.

Implementations of this function must do the following:

- Reset the thread’s stack pointer to a suitable initial value. We do not need any prior context since this is a one-way operation.
- Set up any kernel stack region for the CPU to use during privilege elevation
- Put the CPU in whatever its equivalent of user mode is
- Transfer execution to `arch_new_thread()` passing along all the supplied arguments, in user mode.

**Parameters**

- `user_entry` – Entry point to start executing as a user thread
- `p1` – 1st parameter to user thread
- `p2` – 2nd parameter to user thread
- `p3` – 3rd parameter to user thread

```c
FUNC_NORETURN void arch_syscall_oops(void *ssf)
```

Induce a kernel oops that appears to come from a specific location.

Normally, `k_oops()` generates an exception that appears to come from the call site of the `k_oops()` itself.

However, when validating arguments to a system call, if there are problems we want the oops to appear to come from where the system call was invoked and not inside the validation function.

**Parameters**

- `ssf` – System call stack frame pointer. This gets passed as an argument to `_k_syscall_handler_t` functions and its contents are completely architecture specific.

```c
size_t arch_user_string_nlen(const char *s, size_t maxsize, int *err)
```

Safely take the length of a potentially bad string.

This must not fault, instead the `err` parameter must have -1 written to it. This function otherwise should work exactly like `libc strnlen()`. On success `*err` should be set to 0.

**Parameters**

- `s` – String to measure
- `maxsize` – Max length of the string
- `err` – Error value to write

**Returns**

Length of the string, not counting NULL byte, up to `maxsize`

```c
static inline bool arch_mem_coherent(void *ptr)
```

Detect memory coherence type.

Required when `ARCH_HAS_COHERENCE` is true. This function returns true if the byte pointed to lies within an architecture-defined “coherence region” (typically implemented with uncached memory) and can safely be used in multiprocessor code without explicit flush or invalidate operations.
static inline void arch_cohere_stacks(struct k_thread *old_thread, void *old_switch_handle, struct k_thread *new_thread)

Ensure cache coherence prior to context switch.

Required when ARCH_HAS_COHERENCE is true. On cache-incoherent multiprocessor architectures, thread stacks are cached by default for performance reasons. They must therefore be flushed appropriately on context switch. The rules are:

a. The region containing live data in the old stack (generally the bytes between the current stack pointer and the top of the stack memory) must be flushed to underlying storage so a new CPU that runs the same thread sees the correct data. This must happen before the assignment of the switch_handle field in the thread struct which signals the completion of context switch.

b. Any data areas to be read from the new stack (generally the same as the live region when it was saved) should be invalidated (and NOT flushed!) in the data cache. This is because another CPU may have run or re-initialized the thread since this CPU suspended it, and any data present in cache will be stale.

• old_thread The old thread to be flushed before being allowed to run on other CPUs.
• old_switch_handle The switch handle to be stored into old_thread (it will not be valid until the cache is flushed so is not present yet). This will be NULL if inside z_swap() (because the arch_switch() has not saved it yet).
• new_thread The new thread to be invalidated before it runs locally.

Note: The kernel will call this function during interrupt exit when a new thread has been chosen to run, and also immediately before entering arch_switch() to effect a code-driven context switch. In the latter case, it is very likely that more data will be written to the old_thread stack region after this function returns but before the completion of the switch. Simply flushing naively here is not sufficient on many architectures and coordination with the arch_switch() implementation is likely required.

Memory Management

group arch-mmu

Defines

ARCH_DATA_PAGE_ACCESSED
Bit indicating the data page was accessed since the value was last cleared.
Used by marking eviction algorithms. Safe to set this if uncertain.
This bit is undefined if ARCH_DATA_PAGE_LOADED is not set.
ARCH_DATA_PAGE_DIRTY

Bit indicating the data page, if evicted, will need to be paged out.
Set if the data page was modified since it was last paged out, or if it has never been paged out before. Safe to set this if uncertain.
This bit is undefined if ARCH_DATA_PAGE_LOADED is not set.

ARCH_DATA_PAGE_LOADED

Bit indicating that the data page is loaded into a physical page frame.
If un-set, the data page is paged out or not mapped.

ARCH_DATA_PAGE_NOT_MAPPED

If ARCH_DATA_PAGE_LOADED is un-set, this will indicate that the page is not mapped at all.
This bit is undefined if ARCH_DATA_PAGE_LOADED is set.

Enums

define arch_page_location

Values:

enumerator ARCH_PAGE_LOCATION_PAGED_OUT
enumerator ARCH_PAGE_LOCATION_PAGED_IN
enumerator ARCH_PAGE_LOCATION_BAD

Functions

void arch_mem_map(void *virt, uintptr_t phys, size_t size, uint32_t flags)

Map physical memory into the virtual address space
This is a low-level interface to mapping pages into the address space. Behavior when providing unaligned addresses/sizes is undefined, these are assumed to be aligned to CONFIG_MMU_PAGE_SIZE.
The core kernel handles all management of the virtual address space; by the time we invoke this function, we know exactly where this mapping will be established. If the page tables already had mappings installed for the virtual memory region, these will be overwritten.
If the target architecture supports multiple page sizes, currently only the smallest page size will be used.
The memory range itself is never accessed by this operation.
This API must be safe to call in ISRs or exception handlers. Calls to this API are assumed to be serialized, and indeed all usage will originate from kernel/mm.c which handles virtual memory management.
Architectures are expected to pre-allocate page tables for the entire address space, as defined by CONFIG_KERNEL_VM_BASE and CONFIG_KERNEL_VM_SIZE. This operation should never require any kind of allocation for paging structures.
Validation of arguments should be done via assertions.
This API is part of infrastructure still under development and may change.
Parameters

- virt – Page-aligned Destination virtual address to map
- phys – Page-aligned Source physical address to map
- size – Page-aligned size of the mapped memory region in bytes
- flags – Caching, access and control flags, see K_MAP_* macros

void arch_mem_unmap(void *addr, size_t size)

Remove mappings for a provided virtual address range

This is a low-level interface for un-mapping pages from the address space. When this completes, the relevant page table entries will be updated as if no mapping was ever made for that memory range. No previous context needs to be preserved. This function must update mappings in all active page tables.

Behavior when providing unaligned addresses/sizes is undefined, these are assumed to be aligned to CONFIG_MMU_PAGE_SIZE.

Behavior when providing an address range that is not already mapped is undefined.

This function should never require memory allocations for paging structures, and it is not necessary to free any paging structures. Empty page tables due to all contained entries being un-mapped may remain in place.

Implementations must invalidate TLBs as necessary.

This API is part of infrastructure still under development and may change.

Parameters

- addr – Page-aligned base virtual address to un-map
- size – Page-aligned region size

int arch_page_phys_get(void *virt, uintptr_t *phys)

Get the mapped physical memory address from virtual address.

The function only needs to query the current set of page tables as the information it reports must be common to all of them if multiple page tables are in use. If multiple page tables are active it is unnecessary to iterate over all of them.

Unless otherwise specified, virtual pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior. Just check the currently installed page tables and return the information in that.

Parameters

- virt – Page-aligned virtual address
- phys – [out] Mapped physical address (can be NULL if only checking if virtual address is mapped)

Return values

- 0 – if mapping is found and valid
- -EFAULT – if virtual address is not mapped

void arch_reserved_pages_update(void)

Update page frame database with reserved pages

Some page frames within system RAM may not be available for use. A good example of this is reserved regions in the first megabyte on PC-like systems.

Implementations of this function should mark all relevant entries in z_page_frames with K_PAGE_FRAME_RESERVED. This function is called at early system initialization with mm_lock held.
void arch_mem_page_out(void *addr, uintptr_t location)

Update all page tables for a paged-out data page

This function:

- Sets the data page virtual address to trigger a fault if accessed that can be distinguished from access violations or un-mapped pages.
- Saves the provided location value so that it can retrieved for that data page in the page fault handler.
- The location value semantics are undefined here but the value will be always be page-aligned. It could be 0.

If multiple page tables are in use, this must update all page tables. This function is called with interrupts locked.

Calling this function on data pages which are already paged out is undefined behavior.

This API is part of infrastructure still under development and may change.

void arch_mem_page_in(void *addr, uintptr_t phys)

Update all page tables for a paged-in data page

This function:

- Maps the specified virtual data page address to the provided physical page frame address, such that future memory accesses will function as expected. Access and caching attributes are undisturbed.
- Clears any accounting for “accessed” and “dirty” states.

If multiple page tables are in use, this must update all page tables. This function is called with interrupts locked.

Calling this function on data pages which are already paged in is undefined behavior.

This API is part of infrastructure still under development and may change.

void arch_mem_scratch(uintptr_t phys)

Update current page tables for a temporary mapping

Map a physical page frame address to a special virtual address Z_SCRATCH_PAGE, with read/write access to supervisor mode, such that when this function returns, the calling context can read/write the page frame’s contents from the Z_SCRATCH_PAGE address.

This mapping only needs to be done on the current set of page tables, as it is only used for a short period of time exclusively by the caller. This function is called with interrupts locked.

This API is part of infrastructure still under development and may change.

enum arch_page_location arch_page_location_get(void *addr, uintptr_t *location)

Fetch location information about a page at a particular address

The function only needs to query the current set of page tables as the information it reports must be common to all of them if multiple page tables are in use. If multiple page tables are active it is unnecessary to iterate over all of them. This may allow certain types of optimizations (such as reverse page table mapping on x86).

This function is called with interrupts locked, so that the reported information can’t become stale while decisions are being made based on it.

Unless otherwise specified, virtual data pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior. Just check the currently installed page tables and return the information in that.

Parameters
• *addr* – Virtual data page address that took the page fault

• *location* – [out] In the case of ARCH_PAGE_FAULT_PAGED_OUT, the backing store location value used to retrieve the data page. In the case of ARCH_PAGE_FAULT_PAGED_IN, the physical address the page is mapped to.

**Return values**

• ARCH_PAGE_FAULT_PAGED_OUT – The page was evicted to the backing store.

• ARCH_PAGE_FAULT_PAGED_IN – The data page is resident in memory.

• ARCH_PAGE_FAULT_BAD – The page is un-mapped or otherwise has had invalid access

```c
uintptr_t arch_page_info_get(void *addr, uintptr_t *location, bool clear_accessed)
```

Retrieve page characteristics from the page table(s)

The architecture is responsible for maintaining “accessed” and “dirty” states of data pages to support marking eviction algorithms. This can either be directly supported by hardware or emulated by modifying protection policy to generate faults on reads or writes. In all cases the architecture must maintain this information in some way.

For the provided virtual address, report the logical OR of the accessed and dirty states for the relevant entries in all active page tables in the system if the page is mapped and not paged out.

If clear_accessed is true, the ARCH_DATA_PAGE_ACCESSED flag will be reset. This function will report its prior state. If multiple page tables are in use, this function clears accessed state in all of them.

This function is called with interrupts locked, so that the reported information can’t become stale while decisions are being made based on it.

The return value may have other bits set which the caller must ignore.

Clearing accessed state for data pages that are not ARCH_DATA_PAGE_LOADED is undefined behavior.

ARCH_DATA_PAGE_DIRTY and ARCH_DATA_PAGE_ACCESSED bits in the return value are only significant if ARCH_DATA_PAGE_LOADED is set, otherwise ignore them.

ARCH_DATA_PAGE_NOT_mapped bit in the return value is only significant if ARCH_DATA_PAGE_LOADED is un-set, otherwise ignore it.

Unless otherwise specified, virtual data pages have the same mappings across all page tables. Calling this function on data pages that are exceptions to this rule (such as the scratch page) is undefined behavior.

This API is part of infrastructure still under development and may change.

**Parameters**

• *addr* – Virtual address to look up in page tables

• *location* – [out] If non-NULL, updated with either physical page frame address or backing store location depending on ARCH_DATA_PAGE_LOADED state. This is not touched if ARCH_DATA_PAGE_NOT_MAPPED.

• clear_accessed – Whether to clear ARCH_DATA_PAGE_ACCESSED state

**Return values**

Value – with ARCH_DATA_PAGE_ * bits set reflecting the data page configuration
Functions

int arch_printk_char_out(int c)
   Early boot console output hook
   Definition of this function is optional. If implemented, any invocation of printk() (or logging
calls with CONFIG_LOG_MODE_MINIMAL which are backed by printk) will default to sending
characters to this function. It is useful for early boot debugging before main serial or console
drivers come up.
   This can be overridden at runtime with __printk_hook_install().
   The default __weak implementation of this does nothing.

   Parameters
   • c – Character to print

   Returns
   The character printed

static inline void arch_kernel_init(void)
   Architecture-specific kernel initialization hook
   This function is invoked near the top of _Cstart, for additional architecture-specific setup
before the rest of the kernel is brought up.
   TODO: Deprecate, most arches are using a prep_c() function to do the same thing in a simpler
way

static inline void arch_nop(void)
   Do nothing and return. Yawn.

GDB Stub APIs

   group arch-gdbstub

Functions

void arch_gdb_init(void)
   Architecture layer debug start.
   This function is called by gdb_init()

void arch_gdb_continue(void)
   Continue running program.
   Continue software execution.

void arch_gdb_step(void)
   Continue with one step.
   Continue software execution until reaches the next statement.

size_t arch_gdb_reg_readall(struct gdb_ctx *ctx, uint8_t *buf, size_t buflen)
   Read all registers, and outputs as hexadecimal string.
   This reads all CPU registers and outputs as hexadecimal string. The output string must be
parsable by GDB.

   Parameters
   • ctx – GDB context
   • buf – Buffer to output hexadecimal string.
buflen – Length of buffer.

Returns
Length of hexadecimal string written. Return 0 if error or not supported.

size_t arch_gdb_reg_writeall(struct gdb_ctx *ctx, uint8_t *hex, size_t hexlen)
Take a hexadecimal string and update all registers.
This takes in a hexadecimal string as presented from GDB, and updates all CPU registers with new values.

Parameters
• ctx – GDB context
• hex – Input hexadecimal string.
• hexlen – Length of hexadecimal string.

Returns
Length of hexadecimal string parsed. Return 0 if error or not supported.

size_t arch_gdb_reg_readone(struct gdb_ctx *ctx, uint8_t *buf, size_t buflen, uint32_t regno)
Read one register, and outputs as hexadecimal string.
This reads one CPU register and outputs as hexadecimal string. The output string must be parsable by GDB.

Parameters
• ctx – GDB context
• buf – Buffer to output hexadecimal string.
• buflen – Length of buffer.
• regno – Register number

Returns
Length of hexadecimal string written. Return 0 if error or not supported.

size_t arch_gdb_reg_writeone(struct gdb_ctx *ctx, uint8_t *hex, size_t hexlen, uint32_t regno)
Take a hexadecimal string and update one register.
This takes in a hexadecimal string as presented from GDB, and updates one CPU registers with new value.

Parameters
• ctx – GDB context
• hex – Input hexadecimal string.
• hexlen – Length of hexadecimal string.
• regno – Register number

Returns
Length of hexadecimal string parsed. Return 0 if error or not supported.

int arch_gdb_add_breakpoint(struct gdb_ctx *ctx, uint8_t type, uintptr_t addr, uint32_t kind)
Add breakpoint or watchpoint.

Parameters
• ctx – GDB context
• type – Breakpoint or watchpoint type
• addr – Address of breakpoint or watchpoint
• kind – Size of breakpoint/watchpoint in bytes
Return values

- 0 – Operation successful
- -1 – Error encountered
- -2 – Not supported

```c
int arch_gdb_remove_breakpoint(struct gdb_ctx *ctx, uint8_t type, uintptr_t addr, uint32_t kind)
```

Remove breakpoint or watchpoint.

**Parameters**

- ctx – GDB context
- type – Breakpoint or watchpoint type
- addr – Address of breakpoint or watchpoint
- kind – Size of breakpoint/watchpoint in bytes

**Return values**

- 0 – Operation successful
- -1 – Error encountered
- -2 – Not supported

### 7.5.2 Board Porting Guide

To add Zephyr support for a new board, you at least need a *board directory* with various files in it. Files in the board directory inherit support for at least one SoC and all of its features. Therefore, Zephyr must support your SoC as well.

**Boards, SoCs, etc.**

Zephyr’s hardware support hierarchy has these layers, from most to least specific:

- Board: a particular CPU instance and its peripherals in a concrete hardware specification
- SoC: the exact system on a chip the board’s CPU is part of
- SoC series: a smaller group of tightly related SoCs
- SoC family: a wider group of SoCs with similar characteristics
- CPU core: a particular CPU in an architecture
- Architecture: an instruction set architecture

You can visualize the hierarchy like this:

<table>
<thead>
<tr>
<th>Board</th>
<th>SoC</th>
<th>SoC series</th>
<th>SoC family</th>
<th>CPU core</th>
<th>Architecture</th>
</tr>
</thead>
<tbody>
<tr>
<td>nrf52dk_nrf52832</td>
<td>nRF52832</td>
<td>nRF52</td>
<td>Nordic nRF5</td>
<td>Arm M4</td>
<td>Arm</td>
</tr>
<tr>
<td>frdm_k64f</td>
<td>MK64F12</td>
<td>K6x</td>
<td>NXP Kinetis</td>
<td>Arm M4</td>
<td>Arm</td>
</tr>
<tr>
<td>stm32h747i_disco</td>
<td>STM32H747XI</td>
<td>STM32H7</td>
<td>STMicro STM32</td>
<td>Arm M7</td>
<td>Arm</td>
</tr>
<tr>
<td>rv32m1_vega_r15cy</td>
<td>RV32M1</td>
<td>(Not used)</td>
<td>(Not used)</td>
<td>RISCY</td>
<td>RISC-V</td>
</tr>
</tbody>
</table>

7.5. Porting
Make sure your SoC is supported

Start by making sure your SoC is supported by Zephyr. If it is, it's time to Create your board directory. If you don't know, try:

- checking boards for names that look relevant, and reading individual board documentation to find out for sure.
- asking your SoC vendor

If you need to add SoC, CPU core, or even architecture support, this is the wrong page, but here is some general advice.

Architecture  See Architecture Porting Guide.

CPU Core  CPU core support files go in core subdirectories under arch, e.g. arch/x86/core.

See Install a Toolchain for information about toolchains (compiler, linker, etc.) supported by Zephyr. If you need to support a new toolchain, Build and Configuration Systems is a good place to start learning about the build system. Please reach out to the community if you are looking for advice or want to collaborate on toolchain support.

SoC  Zephyr SoC support files are in architecture-specific subdirectories of soc. They are generally grouped by SoC family.

When adding a new SoC family or series for a vendor that already has SoC support within Zephyr, please try to extract common functionality into shared files to avoid duplication. If there is no support for your vendor yet, you can add it in a new directory zephyr/soc/<YOUR-ARCH>/<YOUR-SOC>; please use self-explanatory directory names.
Create your board directory

Once you’ve found an existing board that uses your SoC, you can usually start by copy/pasting its board directory and changing its contents for your hardware.

You need to give your board a unique name. Run `west boards` for a list of names that are already taken, and pick something new. Let’s say your board is called `plank` (please don’t actually use that name).

Start by creating the board directory `zephyr/boards/<ARCH>/plank`, where `<ARCH>` is your SoC’s architecture subdirectory. (You don’t have to put your board directory in the zephyr repository, but it’s the easiest way to get started. See Custom Board, Devicetree and SOC Definitions for documentation on moving your board directory to a separate repository once it’s working.)

Your board directory should look like this:

```
boards/<ARCH>/plank
    board.cmake
    CMakeLists.txt
    doc
        plank.png
        index.rst
    Kconfig.board
    Kconfig.defconfig
    plank_defconfig
    plank.dts
    plank.yaml
```

Replace `plank` with your board’s name, of course.

The mandatory files are:

1. `plank.dts`: a hardware description in devicetree format. This declares your SoC, connectors, and any other hardware components such as LEDs, buttons, sensors, or communication peripherals (USB, BLE controller, etc).

2. `Kconfig.board`, `Kconfig.defconfig`, `plank_defconfig`: software configuration in Configuration System (Kconfig) formats. This provides default settings for software features and peripheral drivers.

The optional files are:

- `board.cmake`: used for Flash and debug support
- `CMakeLists.txt`: if you need to add additional source files to your build.
- `doc/index.rst`, `doc/plank.png`: documentation for and a picture of your board. You only need this if you’re Contributing your board to Zephyr.
- `plank.yaml`: a YAML file with miscellaneous metadata used by the Test Runner (Twister).

Write your devicetree

The devicetree file `boards/<ARCH>/plank/plank.dts` describes your board hardware in the Devicetree Source (DTS) format (as usual, change `plank` to your board’s name). If you’re new to devicetree, see Introduction to devicetree.

In general, `plank.dts` should look like this:

```
/dts-v1/;
#include <your_soc_vendor/your_soc.dtsi>
/
    model = "A human readable name";
```
compatible = "yourcompany,plank";

chosen {
    zephyr,console = &your_uart_console;
    zephyr,sram = &your_memory_node;
    /* other chosen settings for your hardware */
};

/* Your board-specific hardware: buttons, LEDs, sensors, etc. */

leds {
    compatible = "gpio-leds";
    led0: led_0 {
        gpios = "gpio your LED is hooked up to ";
        label = "LED 0";
   );
    /* ... other LEDs ... */
};

buttons {
    compatible = "gpio-keys";
    /* ... your button definitions ... */
};

/* These aliases are provided for compatibility with samples */
aliases {
    led0 = &led0; /* now you support the blinky sample! */
    /* other aliases go here */
};

&some_peripheral_you_want_to_enable {
    /* like a GPIO or SPI controller */
    status = "okay";
};

&another_peripheral_you_want {
    status = "okay";
};

If you're in a hurry, simple hardware can usually be supported by copy/paste followed by trial and error. If you want to understand details, you will need to read the rest of the devicetree documentation and the devicetree specification.

Example: FRDM-K64F and Hexiwear K64 This section contains concrete examples related to writing your board's devicetree.

The FRDM-K64F and Hexiwear K64 board devicetrees are defined in frdm_k64fs.dts and hexiwear_k64.dts respectively. Both boards have NXP SoCs from the same Kinetis SoC family, the K6X.

Common devicetree definitions for K6X are stored in nxp_k6x.dtsi, which is included by both board .dts files. nxp_k6x.dtsi in turn includes armv7-m.dtsi, which has common definitions for Arm v7-M cores.

Since nxp_k6x.dtsi is meant to be generic across K6X-based boards, it leaves many devices disabled by default using status properties. For example, there is a CAN controller defined as follows (with unimportant parts skipped):

```dts
compatible = "nxp,can";
... other settings...
```
It is up to the board .dts or application overlay files to enable these devices as desired, by setting `status = "okay"`. The board .dts files are also responsible for any board-specific configuration of the device, such as adding nodes for on-board sensors, LEDs, buttons, etc.

For example, FRDM-K64 (but not Hexiwear K64) .dts enables the CAN controller and sets the bus speed:

```c
can0 {  
    status = "okay";
    bus-speed = <125000>;
};
```

The `&can0 { ... }` syntax adds/overrides properties on the node with label can0, i.e. the `can@40024000` node defined in the .dtsi file.

Other examples of board-specific customization is pointing properties in aliases and chosen to the right nodes (see Aliases and chosen nodes), and making GPIO/pinmux assignments.

### Write Kconfig files

Zephyr uses the Kconfig language to configure software features. Your board needs to provide some Kconfig settings before you can compile a Zephyr application for it.

Setting Kconfig configuration values is documented in detail in Setting Kconfig configuration values.

There are three mandatory Kconfig files in the board directory for a board named plank:

```
boards/<ARCH>/plank
    |__ Kconfig.board
    |__ Kconfig.defconfig
    |__ plank_defconfig
```

**Kconfig.board**

Included by `boards/Kconfig` to include your board in the list of options.

This should at least contain a definition for a `BOARD_PLANK` option, which looks something like this:

```c
config BOARD_PLANK
    bool "Plank board"
    depends on SOC_SERIES_YOUR_SOC_SERIES_HERE
    select SOC_PART_NUMBER_ABCDEFGH
```

**Kconfig.defconfig**

Board-specific default values for Kconfig options.

The entire file should be inside an `if BOARD_PLANK / endif` pair of lines, like this:

```c
if BOARD_PLANK
    # Always set CONFIG_BOARD here. This isn't meant to be customized,
    # but is set as a "default" due to Kconfig language restrictions.
    config BOARD
        default "plank"
    # Other options you want enabled by default go next. Examples:
```

(continues on next page)
plank_defconfig
A Kconfig fragment that is merged as-is into the final build directory .config whenever an application is compiled for your board.

You should at least select your board's SOC and do any mandatory settings for your system clock, console, etc. The results are architecture-specific, but typically look something like this:

```plaintext
CONFIG_SOC_${VENDOR_XYZ3000}=y /* select your SoC */
CONFIG_SYS_CLOCK_HW_CYCLES_PER_SEC=120000000 /* set up your clock, etc */
CONFIG_SERIAL=y
```

plank_x_y_z.conf
A Kconfig fragment that is merged as-is into the final build directory .config whenever an application is compiled for your board revision x.y.z.

Build, test, and fix

Now it's time to build and test the application(s) you want to run on your board until you're satisfied.

For example:

```plaintext
west build -b plank samples/hello_world
west flash
```

For west flash to work, see Flash and debug support below. You can also just flash build/zephyr/zephyr.elf, zephyr.hex, or zephyr.bin with any other tools you prefer.

General recommendations

For consistency and to make it easier for users to build generic applications that are not board specific for your board, please follow these guidelines while porting.

- Unless explicitly recommended otherwise by this section, leave peripherals and their drivers disabled by default.
- Configure and enable a system clock, along with a tick source.
- Provide pin and driver configuration that matches the board's valuable components such as sensors, buttons or LEDs, and communication interfaces such as USB, Ethernet connector, or Bluetooth/Wi-Fi chip.
- If your board uses a well-known connector standard (like Arduino, Mikrobus, Grove, or 96Boards connectors), add connector nodes to your DTS and configure pin muxes accordingly.
- Configure components that enable the use of these pins, such as configuring an SPI instance to use the usual Arduino SPI pins.
- If available, configure and enable a serial output for the console using the zephyr,console chosen node in the devicetree.
• If your board supports networking, configure a default interface.
• Enable all GPIO ports connected to peripherals or expansion connectors.
• If available, enable pinmux and interrupt controller drivers.
• It is recommended to enable the MPU by default, if there is support for it in hardware. For boards with limited memory resources it is acceptable to disable it. When the MPU is enabled, it is recommended to also enable hardware stack protection (CONFIG_HW_STACK_PROTECTION=y) and, thus, allow the kernel to detect stack overflows when the system is running in privileged mode.

Flash and debug support

Zephyr supports Building, Flashing and Debugging via west extension commands.

To add west flash and west debug support for your board, you need to create a board.cmake file in your board directory. This file's job is to configure a “runner” for your board. (There's nothing special you need to do to get west build support for your board.)

“Runners” are Zephyr-specific Python classes that wrap flash and debug host tools and integrate with west and the zephyr build system to support west flash and related commands. Each runner supports flashing, debugging, or both. You need to configure the arguments to these Python scripts in your board.cmake to support those commands like this example board.cmake:

```c
board_runner_args(jlink "--device=nrf52" "--speed=4000")
board_runner_args(pyocd "--target=nrf52" "--frequency=4000000")
```

```c
include(${ZEPHYR_BASE}/boards/common/nrfjprog.board.cmake)
include(${ZEPHYR_BASE}/boards/common/jlink.board.cmake)
include(${ZEPHYR_BASE}/boards/common/pyocd.board.cmake)
```

This example configures the nrfjprog, jlink, and pyocd runners.

**Warning:** Runners usually have names which match the tools they wrap, so the jlink runner wraps Segger’s J-Link tools, and so on. But the runner command line options like --speed etc. are specific to the Python scripts.

For more details:

• Run west flash --context to see a list of available runners which support flashing, and west flash --context -r <RUNNER> to view the specific options available for an individual runner.
• Run west debug --context and west debug --context <RUNNER> to get the same output for runners which support debugging.
• Run west flash --help and west debug --help for top-level options for flashing and debugging.
• See Flash and debug runners for Python APIs.
• Look for board.cmake files for other boards similar to your own for more examples.

To see what a west flash or west debug command is doing exactly, run it in verbose mode:

```c
west --verbose flash
west --verbose debug
```

Verbose mode prints any host tool commands the runner uses.

The order of the include() calls in your board.cmake matters. The first include sets the default runner if it’s not already set. For example, including nrfjprog.board.cmake first means that nrfjprog is the default flash runner for this board. Since nrfjprog does not support debugging, jlink is the default debug runner.
Multiple board revisions

See Building for a board revision for basics on this feature from the user perspective.

To create a new board revision for the plank board, create these additional files in the board folder:

```
boards/<ARCH>/plank
   - plank_<revision>.conf   # optional
   - plank_<revision>.overlay # optional
   - revision.cmake
```

When the user builds for board plank@<revision>:

- The optional Kconfig settings specified in the file plank_<revision>.conf will be merged into the board’s default Kconfig configuration.
- The optional devicetree overlay plank_<revision>.overlay will be added to the common plank.dts devicetree file.
- The revision.cmake file controls how the Zephyr build system matches the <board>@<revision> string specified by the user when building an application for the board.

Currently, <revision> can be either a numeric MAJOR.MINOR.PATCH style revision like 1.5.0, an integer number like 1, or single letter like A, B, etc. Zephyr provides a CMake board extension function, board_check_revision(), to make it easy to match either style from revision.cmake.

Valid board revisions may be specified as arguments to the board_check_revision() function, like:

```
board_check_revision(FORMAT MAJOR.MINOR.PATCH
   VALID_REVISIONS 0.1.0 0.3.0 ...)
```

Note: VALID_REVISIONS can be omitted if all valid revisions have specific Kconfig fragments, such as <board>_0_1_0.conf, <board>_0_3_0.conf. This allows you to just place Kconfig revision fragments in the board folder and not have to keep the corresponding VALID_REVISIONS in sync.

The following sections describe how to support these styles of revision numbers.

**MAJOR.MINOR.PATCH revisions** Let’s say you want to add support for revisions 0.5.0, 1.0.0, and 1.5.0 of the plank board with both Kconfig fragments and devicetree overlays. Create revision.cmake with board_check_revision(FORMAT MAJOR.MINOR.PATCH), and create the following additional files in the board directory:

```
boards/<ARCH>/plank
   - plank_0_5_0.conf
   - plank_0_5_0.overlay
   - plank_1_0_0.conf
   - plank_1_0_0.overlay
   - plank_1_5_0.conf
   - plank_1_5_0.overlay
   - revision.cmake
```

Notice how the board files have changed periods (".") in the revision number to underscores ("_”).

**Fuzzy revision matching** To support “fuzzy” MAJOR.MINOR.PATCH revision matching for the plank board, use the following code in revision.cmake:

```
board_check_revision(FORMAT MAJOR.MINOR.PATCH)
```
If the user selects a revision between those available, the closest revision number that is not larger than the user's choice is used. For example, if the user builds for `plank@0.7.0`, the build system will target revision 0.5.0.

The build system will print this at CMake configuration time:

```
-- Board: plank, Revision: 0.7.0 (Active: 0.5.0)
```

This allows you to only create revision configuration files for board revision numbers that introduce incompatible changes.

Any revision less than the minimum defined will be treated as an error.

You may use `0.0.0` as a minimum revision to build for by creating the file `plank_0_0_0.conf` in the board directory. This will be used for any revision lower than 0.5.0, for example if the user builds for `plank@0.1.0`.

**Exact revision matching**  Alternatively, the `EXACT` keyword can be given to `board_check_revision()` in `revision.cmake` to allow exact matches only, like this:

```
board_check_revision(FORMAT MAJOR.MINOR.PATCH EXACT)
```

With this `revision.cmake`, building for `plank@0.7.0` in the above example will result in the following error message:

```
Board revision `0.7.0` not found. Please specify a valid board revision.
```

**Letter revision matching**  Let's say instead that you need to support revisions A, B, and C of the `plank` board. Create the following additional files in the board directory:

```
boards/<ARCH>/plank
   ─ planks_A.conf
   ─ planks_A.overlay
   ─ planks_B.conf
   ─ planks_B.overlay
   ─ planks_C.conf
   ─ planks_C.overlay
   ─ revision.cmake
```

And add the following to `revision.cmake`:

```
board_check_revision(FORMAT LETTER)
```

**Number revision matching**  Let's say instead that you need to support revisions 1, 2, and 3 of the `plank` board. Create the following additional files in the board directory:

```
boards/<ARCH>/plank
   ─ planks_1.conf
   ─ planks_1.overlay
   ─ planks_2.conf
   ─ planks_2.overlay
   ─ planks_3.conf
   ─ planks_3.overlay
   ─ revision.cmake
```

And add the following to `revision.cmake`: 7.5. Porting
board_check_revision(FORMAT NUMBER)

board_check_revision() details

board_check_revision(FORMAT <LETTER | NUMBER | MAJOR.MINOR.PATCH>
[EXACT]
[DEFAULT_REVISION <revision>]
[HIGHEST_REVISION <revision>]
[VALID_REVISIONS <revision> [<revision> ...]]
)

This function supports the following arguments:

- **FORMAT LETTER**: matches single letter revisions from A to Z only
- **FORMAT NUMBER**: matches integer revisions
- **FORMAT MAJOR.MINOR.PATCH**: matches exactly three digits. The command line allows for loose typing, that is -DBOARD=<board>@1 and -DBOARD=<board>@1.0 will be handled as -DBOARD=<board>@1.0.0. Kconfig fragment and devicetree overlay files must use full numbering to avoid ambiguity, so only <board>_1_0_0.conf and <board>_1_0_0.overlay are allowed.
- **EXACT**: if given, the revision is required to be an exact match. Otherwise, the closest matching revision not greater than the user’s choice will be selected.
- **DEFAULT_REVISION <revision>**: if given, <revision> is the default revision to use when user has not selected a revision number. If not given, the build system prints an error when the user does not specify a board revision.
- **HIGHEST_REVISION**: if given, specifies the highest valid revision for a board. This can be used to ensure that a newer board cannot be used with an older Zephyr. For example, if the current board directory supports revisions 0.x.0-0.99.99 and 1.0.0-1.99.99, and it is expected that the implementation will not work with board revision 2.0.0, then giving HIGHEST_REVISION 1.99.99 causes an error if the user builds using <board>@2.0.0.
- **VALID_REVISIONS**: if given, specifies a list of revisions that are valid for this board. If this argument is not given, then each Kconfig fragment of the form <board>_<revision>.conf in the board folder will be used as a valid revision for the board.

Custom revision.cmake files

Some boards may not use board revisions supported by board_check_revision(). To support revisions of any type, the file revision.cmake can implement custom revision matching without calling board_check_revision().

To signal to the build system that it should use a different revision than the one specified by the user, revision.cmake can set the variable ACTIVE_BOARD_REVISION to the revision to use instead. The corresponding Kconfig files and devicetree overlays must be named <board>_<ACTIVE_BOARD_REVISION>.conf and <board>_<ACTIVE_BOARD_REVISION>.overlay.

For example, if the user builds for plank@zero, revision.cmake can set ACTIVE_BOARD_REVISION to one to use the files plank_one.conf and plank_one.overlay.

Contributing your board

If you want to contribute your board to Zephyr, first – thanks!

There are some extra things you’ll need to do:

1. Make sure you’ve followed all the *General recommendations*. They are requirements for boards included with Zephyr.
2. Add documentation for your board using the template file `doc/templates/board.tmpl`. See *Documentation Generation* for information on how to build your documentation before submitting your pull request.

3. Prepare a pull request adding your board which follows the *Contribution Guidelines*.

### 7.5.3 Shields

Shields, also known as “add-on” or “daughter boards”, attach to a board to extend its features and services for easier and modularized prototyping. In Zephyr, the shield feature provides Zephyr-formatted shield descriptions for easier compatibility with applications.

#### Shield porting and configuration

Shield configuration files are available in the board directory under `/boards/shields`:

```
boards/shields/<shield>
  └── <shield>.overlay
  └── Kconfig.shield
  └── Kconfig.defconfig
```

These files provide shield configuration as follows:

- `<shield>.overlay`: This file provides a shield description in devicetree format that is merged with the board’s `devicetree` before compilation.

- `Kconfig.shield`: This file defines shield Kconfig symbols that will be used for default shield configuration. To ease use with applications, the default shield configuration here should be consistent with those in the *Write your devicetree*.

- `Kconfig.defconfig`: This file defines the default shield configuration. It is made to be consistent with the *Write your devicetree*. Hence, shield configuration should be done by keeping in mind that features activation is application responsibility.

Besides, in order to avoid name conflicts with devices that may be defined at board level, it is advised, specifically for shields devicetree descriptions, to provide a device nodelabel in the form `<device>_<shield>`, for instance:

```
sdhc_myshield: sdhc01 {
  reg = <1>;
  ...
}
```

#### Board compatibility

Hardware shield-to-board compatibility depends on the use of well-known connectors used on popular boards (such as Arduino and 96boards). For software compatibility, boards must also provide a configuration matching their supported connectors.

This should be done at two different level:

- Pinmux: Connector pins should be correctly configured to match shield pins

- Devicetree: A board `devicetree` file, `BOARD.dts` should define an alternate nodelabel for each connector interface. For example, for Arduino I2C:

```
arduino_i2c: &i2c1 {
}
```
Board specific shield configuration  If modifications are needed to fit a shield to a particular board or board revision, you can override a shield description for a specific board by adding board or board revision overriding files to a shield, as follows:

```
boards/shields/<shield>
  boards
    <board>_<revision>.overlay
    <board>.overlay
    <board>.defconfig
    <board>_<revision>.conf
    <board>.conf
```

### Shield activation

Activate support for one or more shields by adding the matching `-DSHIELD` arg to CMake command.

```
# From the root of the zephyr repository
west build -b None your_app -- -DSHIELD="x_nucleo_idb05a1 x_nucleo_iks01a1"
```

Alternatively, it could be set by default in a project's `CMakeLists.txt`:

```
set(SHIELD x_nucleo_iks01a1)
```

### Shield variants

Some shields may support several variants or revisions. In that case, it is possible to provide multiple version of the shields description:

```
boards/shields/<shield>
  <shield_v1>.overlay
  <shield_v1>.defconfig
  <shield_v2>.overlay
  <shield_v2>.defconfig
```

In this case, a shield-particular revision name can be used:

```
# From the root of the zephyr repository
west build -b None your_app -- -DSHIELD=shield_v2
```

You can also provide a board-specific configuration to a specific shield revision:

```
boards/shields/<shield>
  <shield_v1>.overlay
  <shield_v1>.defconfig
  <shield_v2>.overlay
  <shield_v2>.defconfig
  boards
    <shield_v2>
      <board>.overlay
      <board>.defconfig
```

### GPIO nexus nodes

GPIOs accessed by the shield peripherals must be identified using the shield GPIO abstraction, for example from the `arduino-header-r3` compatible. Boards that provide the header must map the header pins
to SOC-specific pins. This is accomplished by including a nexus node that looks like the following into the board devicetree file:

```c
arduino_header: connector {
    compatible = "arduino-header-r3";
    #gpio-cells = <2>;
    gpio-map-mask = <0xffffffff 0xffffffffc0>;
    gpio-map-pass-thru = <0 0x3f>;
    gpio-map = <0 0 &gpioa 0 0>, /* A0 */
               <1 0 &gpioa 1 0>, /* A1 */
               <2 0 &gpioa 4 0>, /* A2 */
               <3 0 &gpiob 0 0>, /* A3 */
               <4 0 &gpioc 1 0>, /* A4 */
               <5 0 &gpioc 0 0>, /* A5 */
               <6 0 &gpioa 3 0>, /* D0 */
               <7 0 &gpiob 2 0>, /* D1 */
               <8 0 &gpiob 10 0>, /* D2 */
               <9 0 &gpiob 3 0>, /* D3 */
               <10 0 &gpiob 5 0>, /* D4 */
               <11 0 &gpiob 4 0>, /* D5 */
               <12 0 &gpiob 10 0>, /* D6 */
               <13 0 &gpiob 8 0>, /* D7 */
               <14 0 &gpiob 9 0>, /* D8 */
               <15 0 &gpioc 7 0>, /* D9 */
               <16 0 &gpiob 6 0>, /* D10 */
               <17 0 &gpiob 7 0>, /* D11 */
               <18 0 &gpiob 6 0>, /* D12 */
               <19 0 &gpiob 5 0>, /* D13 */
               <20 0 &gpiob 9 0>, /* D14 */
               <21 0 &gpiob 8 0>; /* D15 */
};
```

This specifies how Arduino pin references like `<&arduino_header 11 0>` are converted to SOC gpio pin references like `<&gpiob 4 0>`.

In Zephyr GPIO specifiers generally have two parameters (indicated by `#gpio-cells = <2>`): the pin number and a set of flags. The low 6 bits of the flags correspond to features that can be configured in devicetree. In some cases it's necessary to use a non-zero flag value to tell the driver how a particular pin behaves, as with:

```
drdy-gpios = <&arduino_header 11 GPIO_ACTIVE_LOW>;
```

After preprocessing this becomes `<&arduino_header 11 1>`. Normally the presence of such a flag would cause the map lookup to fail, because there is no map entry with a non-zero flags value. The `gpio-map-mask` property specifies that, for lookup, all bits of the pin and all but the low 6 bits of the flags are used to identify the specifier. Then the `gpio-map-pass-thru` specifies that the low 6 bits of the flags are copied over, so the SOC GPIO reference becomes `<&gpiob 4 1>` as intended.

See nexus node for more information about this capability.
Chapter 8

Contributing to Zephyr

8.1 Contribution Guidelines

As an open-source project, we welcome and encourage the community to submit patches directly to the project. In our collaborative open source environment, standards and methods for submitting changes help reduce the chaos that can result from an active development community.

This document explains how to participate in project conversations, log bugs and enhancement requests, and submit patches to the project so your patch will be accepted quickly in the codebase.

8.1.1 Licensing

Licensing is very important to open source projects. It helps ensure the software continues to be available under the terms that the author desired.

Zephyr uses the Apache 2.0 license (as found in the LICENSE file in the project's GitHub repo) to strike a balance between open contribution and allowing you to use the software however you would like to. The Apache 2.0 license is a permissive open source license that allows you to freely use, modify, distribute and sell your own products that include Apache 2.0 licensed software. (For more information about this, check out articles such as Why choose Apache 2.0 licensing and Top 10 Apache License Questions Answered).

A license tells you what rights you have as a developer, as provided by the copyright holder. It is important that the contributor fully understands the licensing rights and agrees to them. Sometimes the copyright holder isn't the contributor, such as when the contributor is doing work on behalf of a company.

Components using other Licenses

There are some imported or reused components of the Zephyr project that use other licensing, as described in Licensing of Zephyr Project components.

Importing code into the Zephyr OS from other projects that use a license other than the Apache 2.0 license needs to be fully understood in context and approved by the Zephyr governing board.

By carefully reviewing potential contributions and also enforcing a Developer Certification of Origin (DCO) for contributed code, we can ensure that the Zephyr community can develop products with the Zephyr Project without concerns over patent or copyright issues.

See Contributing External Components for more information about this contributing and review process for imported components.
Licensing of Zephyr Project components The Zephyr kernel tree imports or reuses packages, scripts and other files that are not covered by the Apache 2.0 License. In some places there is no LICENSE file or way to put a LICENSE file there, so we describe the licensing in this document.

scripts/{checkpatch.pl,checkstack.pl,get_maintainers.pl,spelling.txt}
  Origin: Linux Kernel
  Licensing: GPLv2 License

8.1.2 Copyrights Notices

Please follow this Community Best Practice for Copyright Notices from the Linux Foundation.

8.1.3 Developer Certification of Origin (DCO)

To make a good faith effort to ensure licensing criteria are met, the Zephyr project requires the Developer Certificate of Origin (DCO) process to be followed.

The DCO is an attestation attached to every contribution made by every developer. In the commit message of the contribution, (described more fully later in this document), the developer simply adds a Signed-off-by statement and thereby agrees to the DCO.

When a developer submits a patch, it is a commitment that the contributor has the right to submit the patch per the license. The DCO agreement is shown below and at http://developercertificate.org/.

---

**Developer's Certificate of Origin 1.1**

By making a contribution to this project, I certify that:

(a) The contribution was created in whole or in part by me and I have the right to submit it under the open source license indicated in the file; or

(b) The contribution is based upon previous work that, to the best of my knowledge, is covered under an appropriate open source license and I have the right under that license to submit that work with modifications, whether created in whole or in part by me, under the same open source license (unless I am permitted to submit under a different license), as indicated in the file; or

(c) The contribution was provided directly to me by some other person who certified (a), (b) or (c) and I have not modified it.

(d) I understand and agree that this project and the contribution are public and that a record of the contribution (including all personal information I submit with it, including my sign-off) is maintained indefinitely and may be redistributed consistent with this project or the open source license(s) involved.

---

DCO Sign-Off

The “sign-off” in the DCO is a “Signed-off-by:” line in each commit's log message. The Signed-off-by: line must be in the following format:
Signed-off-by: Your Name <your.email@example.com>

For your commits, replace:

- Your Name with your legal name (pseudonyms, hacker handles, and the names of groups are not allowed)
- your.email@example.com with the same email address you are using to author the commit (CI will fail if there is no match)

You can automatically add the Signed-off-by: line to your commit body using `git commit -s`. Use other commits in the zephyr git history as examples.

Additional requirements:

- If you are altering an existing commit created by someone else, you must add your Signed-off-by: line without removing the existing one.
- If you forget to add the Signed-off-by: line, you can add it to your previous commit by running `git commit --amend -s`.
- If you've pushed your changes to GitHub already you'll need to force push your branch after this with `git push -f`.

Notes

Any contributions made as part of submitted pull requests are considered free for the Project to use. Developers are permitted to cherry-pick patches that are included in pull requests submitted by other contributors. It is expected that

- the content of the patches will not be substantially modified,
- the cherry-picked commits or portions of a commit shall preserve the original sign-off messages and the author identity.

*Modifying Contributions made by other developers* describes additional recommended policies around working with contributions submitted by other developers.

### 8.1.4 Prerequisites

As a contributor, you'll want to be familiar with the Zephyr project, how to configure, install, and use it as explained in the Zephyr Project website and how to set up your development environment as introduced in the Zephyr Getting Started Guide.

You should be familiar with common developer tools such as Git and CMake, and platforms such as GitHub.

If you haven't already done so, you'll need to create a (free) GitHub account on `https://github.com` and have Git tools available on your development system.

**Note:** The Zephyr development workflow supports all 3 major operating systems (Linux, macOS, and Windows) but some of the tools used in the sections below are only available on Linux and macOS. On Windows, instead of running these tools yourself, you will need to rely on the Continuous Integration (CI) service using Github Actions, which runs automatically on GitHub when you submit your Pull Request (PR). You can see any failure results in the workflow details link near the end of the PR conversation list. See *Continuous Integration* for more information.
8.1.5 Source Tree Structure

To clone the main Zephyr Project repository use the instructions in Get Zephyr and install Python dependencies.

This section describes the main repository’s source tree. In addition to the Zephyr kernel itself, you’ll also find the sources for technical documentation, sample code, supported board configurations, and a collection of subsystem tests. All of these are available for developers to contribute to and enhance.

Understanding the Zephyr source tree can help locate the code associated with a particular Zephyr feature.

At the top of the tree, several files are of importance:

- `CMakeLists.txt` The top-level file for the CMake build system, containing a lot of the logic required to build Zephyr.
- `Kconfig` The top-level Kconfig file, which refers to the file `Kconfig.zephyr` also found in the top-level directory.
  See the Kconfig section of the manual for detailed Kconfig documentation.
- `west.yml` The West (Zephyr’s meta-tool) manifest, listing the external repositories managed by the west command-line tool.

The Zephyr source tree also contains the following top-level directories, each of which may have one or more additional levels of subdirectories not described here.

- `arch` Architecture-specific kernel and system-on-chip (SoC) code. Each supported architecture (for example, x86 and ARM) has its own subdirectory, which contains additional subdirectories for the following areas:
  - architecture-specific kernel source files
  - architecture-specific kernel include files for private APIs
- `soc` SoC related code and configuration files.
- `boards` Board related code and configuration files.
- `doc` Zephyr technical documentation source files and tools used to generate the https://docs.zephyrproject.org web content.
- `drivers` Device driver code.
- `dts` devicetree source files used to describe non-discoverable board-specific hardware details.
- `include` Include files for all public APIs, except those defined under lib.
- `kernel` Architecture-independent kernel code.
- `lib` Library code, including the minimal standard C library.
- `misc` Miscellaneous code that doesn’t belong to any of the other top-level directories.
samples
  Sample applications that demonstrate the use of Zephyr features.

scripts
  Various programs and other files used to build and test Zephyr applications.

cmake
  Additional build scripts needed to build Zephyr.

subsys
  Subsystems of Zephyr, including:
  • USB device stack code
  • Networking code, including the Bluetooth stack and networking stacks
  • File system code
  • Bluetooth host and controller

tests
  Test code and benchmarks for Zephyr features.

share
  Additional architecture independent data. It currently contains Zephyr’s CMake package.

8.1.6 Pull Requests and Issues

Before starting on a patch, first check in our issues Zephyr Project Issues system to see what’s been reported on the issue you’d like to address. Have a conversation on the Zephyr devel mailing list (or the Zephyr Discord Server) to see what others think of your issue (and proposed solution). You may find others that have encountered the issue you’re finding, or that have similar ideas for changes or additions. Send a message to the Zephyr devel mailing list to introduce and discuss your idea with the development community.

It’s always a good practice to search for existing or related issues before submitting your own. When you submit an issue (bug or feature request), the triage team will review and comment on the submission, typically within a few business days.

You can find all open pull requests on GitHub and open Zephyr Project Issues in Github issues.

8.1.7 Tools and Git Setup

Signed-off-by

The name in the commit message Signed-off-by: line and your email must match the change authorship information. Make sure your .gitconfig is set up correctly:

```
git config --global user.name "David Developer"
git config --global user.email "david.developer@company.com"
```

gitlint

When you submit a pull request to the project, a series of checks are performed to verify your commit messages meet the requirements. The same step done during the CI process can be performed locally using the the gitlint command.

Run gitlint locally in your tree and branch where your patches have been committed:
gitlint

Note, gitlint only checks HEAD (the most recent commit), so you should run it after each commit, or use the --commits option to specify a commit range covering all the development patches to be submitted.

twister

**Note:** twister does not currently run on Windows.

To verify that your changes did not break any tests or samples, please run the twister script locally before submitting your pull request to GitHub. To run the same tests the CI system runs, follow these steps from within your local Zephyr source working directory:

```
source zephyr-env.sh
./scripts/twister
```

The above will execute the basic twister script, which will run various kernel tests using the QEMU emulator. It will also do some build tests on various samples with advanced features that can’t run in QEMU.

We highly recommend you run these tests locally to avoid any CI failures.

clang-format

The clang-format tool can be helpful to quickly reformat large amounts of new source code to our Coding Style standards together with the .clang-format configuration file provided in the repository. clang-format is well integrated into most editors, but you can also run it manually like this:

```
clang-format -i my_source_file.c
```

clang-format is part of LLVM, which can be downloaded from the project releases page <https://github.com/llvm/llvm-project/releases>. Note that if you are a Linux user, clang-format will likely be available as a package in your distribution repositories.

### 8.1.8 Coding Style

Use these coding guidelines to ensure that your development complies with the project’s style and naming conventions.

In general, follow the Linux kernel coding style, with the following exceptions:

- Add braces to every if, else, do, while, for and switch body, even for single-line code blocks. Use the --ignore BRACES flag to make checkpatch stop complaining.
- Use spaces instead of tabs to align comments after declarations, as needed.
- Use C89-style single line comments, /* */. The C99-style single line comment, //, is not allowed.
- Use /* */ for doxygen comments that need to appear in the documentation.

The Linux kernel GPL-licensed tool checkpatch is used to check coding style conformity.

**Note:** checkpatch does not currently run on Windows.

Checkpatch is available in the scripts directory. To invoke it when committing code, make the file $ZEPHYR_BASE/.git/hooks/pre-commit executable and edit it to contain:
Instead of running checkpatch at each commit, you may prefer to run it only before pushing on zephyr repo. To do this, make the file $ZEPHYR_BASE/.git/hooks/pre-push executable and edit it to contain:

```
#!/bin/sh
remote="$1"
url="$2"
z40=00000000000000000000000000000000

echo "Run push hook"

while read local_ref local_sha remote_ref remote_sha
do
    args="$remote $url $local_ref $local_sha $remote_ref $remote_sha"
    exec $(ZEPHYR_BASE)/scripts/series-push-hook.sh $args
done

exit 0
```

If you want to override checkpatch verdict and push you branch despite reported issues, you can add option --no-verify to the git push command.

A more complete alternative to this is using check_compliance.py script from ci-tools repo.

### 8.1.9 Contribution Workflow

One general practice we encourage, is to make small, controlled changes. This practice simplifies review, makes merging and rebasing easier, and keeps the change history clear and clean.

When contributing to the Zephyr Project, it is also important you provide as much information as you can about your change, update appropriate documentation, and test your changes thoroughly before submitting.

The general GitHub workflow used by Zephyr developers uses a combination of command line Git commands and browser interaction with GitHub. As it is with Git, there are multiple ways of getting a task done. We’ll describe a typical workflow here:

1. **Create a Fork of Zephyr** to your personal account on GitHub. (Click on the fork button in the top right corner of the Zephyr project repo page in GitHub.)
2. **On your development computer,** change into the zephyr folder that was created when you obtained the code:
   ```
   cd zephyrproject/zephyr
   ```
   Rename the default remote pointing to the **upstream repository** from origin to upstream:
   ```
   git remote rename origin upstream
   ```
   Let Git know about the fork you just created, naming it origin:
   ```
   git remote add origin https://github.com/<your github id>/zephyr
   ```
   and verify the remote repos:
The output should look similar to:

```
origin  https://github.com/<your github id>/zephyr (fetch)
origin  https://github.com/<your github id>/zephyr (push)
upstream https://github.com/zephyrproject-rtos/zephyr (fetch)
upstream https://github.com/zephyrproject-rtos/zephyr (push)
```

3. Create a topic branch (off of main) for your work (if you're addressing an issue, we suggest including the issue number in the branch name):

```
git checkout main
git checkout -b fix_comment_typo
```

Some Zephyr subsystems do development work on a separate branch from main so you may need to indicate this in your checkout:

```
git checkout -b fix_out_of_date_patch origin/net
```

4. Make changes, test locally, change, test, test again, ... (Check out the prior chapter on `twister` as well).

5. When things look good, start the pull request process by adding your changed files:

```
git add [file(s) that changed, add -p if you want to be more specific]
```

You can see files that are not yet staged using:

```
git status
```

6. Verify changes to be committed look as you expected:

```
git diff --cached
```

7. Commit your changes to your local repo:

```
git commit -s
```

The `-s` option automatically adds your `Signed-off-by:` to your commit message. Your commit will be rejected without this line that indicates your agreement with the DCO. See the Commit Guidelines section for specific guidelines for writing your commit messages.

8. Push your topic branch with your changes to your fork in your personal GitHub account:

```
git push origin fix_comment_typo
```

9. In your web browser, go to your forked repo and click on the Compare & pull request button for the branch you just worked on and you want to open a pull request with.

10. Review the pull request changes, and verify that you are opening a pull request for the appropriate branch. The title and message from your commit message should appear as well.

11. If you're working on a subsystem branch that's not `main`, you may need to change the intended branch for the pull request here, for example, by changing the base branch from `main` to `net`.

12. GitHub will assign one or more suggested reviewers (based on the CODEOWNERS file in the repo). If you are a project member, you can select additional reviewers now too.

13. Click on the submit button and your pull request is sent and awaits review. Email will be sent as review comments are made, or you can check on your pull request at https://github.com/zephyrproject-rtos/zephyr/pulls.
14. While you’re waiting for your pull request to be accepted and merged, you can create another branch to work on another issue. (Be sure to make your new branch off of main and not the previous branch):

```bash
git checkout main
git checkout -b fix_another_issue
```

and use the same process described above to work on this new topic branch.

15. If reviewers do request changes to your patch, you can interactively rebase commit(s) to fix review issues. In your development repo:

```bash
git fetch --all
git rebase --ignore-whitespace upstream/main
```

The `--ignore-whitespace` option stops `git apply` (called by rebase) from changing any whitespace. Continuing:

```bash
git rebase -i <offending-commit-id>^  
```

In the interactive rebase editor, replace `pick` with `edit` to select a specific commit (if there’s more than one in your pull request), or remove the line to delete a commit entirely. Then edit files to fix the issues in the review.

As before, inspect and test your changes. When ready, continue the patch submission:

```bash
git add [file(s)]
git rebase --continue
```

Update commit comment if needed, and continue:

```bash
git push --force origin fix_comment typo
```

By force pushing your update, your original pull request will be updated with your changes so you won’t need to resubmit the pull request.

**Note:** While amending commits and force pushing is a common review model outside GitHub, and the one recommended by Zephyr, it’s not the main model supported by GitHub. Forced pushes can cause unexpected behavior, such as not being able to use “View Changes” buttons except for the last one - GitHub complains it can’t find older commits. You’re also not always able to compare the latest reviewed version with the latest submitted version. When rewriting history GitHub only guarantees access to the latest version.

16. If the CI run fails, you will need to make changes to your code in order to fix the issues and amend your commits by rebasing as described above. Additional information about the CI system can be found in *Continuous Integration*.

### 8.1.10 Commit Guidelines

Changes are submitted as Git commits. Each commit message must contain:

- A short and descriptive subject line that is less than 72 characters, followed by a blank line. The subject line must include a prefix that identifies the subsystem being changed, followed by a colon, and a short title, for example: `doc: update wiki references to new site`. (If you’re updating an existing file, you can use `git log <filename>` to see what developers used as the prefix for previous patches of this file.)
- A change description with your logic or reasoning for the changes, followed by a blank line. (Every single line has to be less than 75 characters.)
• A Signed-off-by line, Signed-off-by: <name> <email> typically added automatically by using
  git commit -s
• If the change addresses an issue, include a line of the form:
  Fixes #<issue number>.

All changes and topics sent to GitHub must be well-formed, as described above.

Commit Message Body

When editing the commit message, please briefly explain what your change does and why it’s needed. A change summary of "Fixes stuff" will be rejected.

Warning: An empty change summary body is not permitted. Even for trivial changes, please include a summary body in the commit message.

The description body of the commit message must include:

• what the change does,
• why you chose that approach,
• what assumptions were made, and
• how you know it works – for example, which tests you ran.

For examples of accepted commit messages, you can refer to the Zephyr GitHub changelog.

Other Commit Expectations

• Commits must build cleanly when applied on top of each other, thus avoiding breaking bisectability.
• Commits must pass all CI checks (see Continuous Integration for more information)
• Each commit must address a single identifiable issue and must be logically self-contained. Unrelated changes should be submitted as separate commits.
• You may submit pull request RFCs (requests for comments) to send work proposals, progress snapshots of your work, or to get early feedback on features or changes that will affect multiple areas in the code base.
• When major new functionality is added, tests for the new functionality MUST be added to the automated test suite. All new APIs MUST be documented and tested and tests MUST cover at least 80% of the added functionality using the code coverage tool and reporting provided by the project.

Submitting Proposals

You can request a new feature or submit a proposal by submitting an issue to our GitHub Repository. If you would like to implement a new feature, please submit an issue with a proposal (RFC) for your work first, to be sure that we can use it. Please consider what kind of change it is:

• For a Major Feature, first open an issue and outline your proposal so that it can be discussed. This will also allow us to better coordinate our efforts, prevent duplication of work, and help you to craft the change so that it is successfully accepted into the project. Providing the following information will increase the chances of your issue being dealt with quickly:
  – Overview of the Proposal
  – Motivation for or Use Case
— Design Details
— Alternatives
— Test Strategy

• Small Features can be crafted and directly submitted as a Pull Request.

Identifying Contribution Origin

When adding a new file to the tree, it is important to detail the source of origin on the file, provide attributions, and detail the intended usage. In cases where the file is an original to Zephyr, the commit message should include the following (“Original” is the assumption if no Origin tag is present):

Origin: Original

In cases where the file is imported from an external project, the commit message shall contain details regarding the original project, the location of the project, the SHA-id of the origin commit for the file and the intended purpose.

For example, a copy of a locally maintained import:

Origin: Contiki OS
License: BSD 3-Clause
URL: http://www.contiki-os.org/
commit: 853207acfd49b10eb3e44504b1a75ae1ad63a
Purpose: Introduction of networking stack.

For example, a copy of an externally maintained import in a module repository:

Origin: Tiny Crypt
License: BSD 3-Clause
URL: https://github.com/01org/tinycrypt
commit: 08ded7f21529c39e5133688ffeb93a9d0c94e5c6e
Purpose: Introduction of TinyCrypt

8.1.11 Continuous Integration (CI)

The Zephyr Project operates a Continuous Integration (CI) system that runs on every Pull Request (PR) in order to verify several aspects of the PR:

• Git commit formatting
• Coding Style
• Twister builds for multiple architectures and boards
• Documentation build to verify any doc changes

CI is run on Github Actions and it uses the same tools described in the Contribution Tools section. The CI results must be green indicating “All checks have passed” before the Pull Request can be merged. CI is run when the PR is created, and again every time the PR is modified with a commit.

The current status of the CI run can always be found at the bottom of the GitHub PR page, below the review status. Depending on the success or failure of the run you will see:

• “All checks have passed”
• “All checks have failed”

In case of failure you can click on the “Details” link presented below the failure message in order to navigate to Github Actions and inspect the results. Once you click on the link you will be taken to the
Github actions summary results page where a table with all the different builds will be shown. To see what build or test failed click on the row that contains the failed (i.e. non-green) build.
The builds@lists.zephyrproject.org mailing list archives any nightly build results produced by CI.

8.1.12 Contributions to External Modules

Follow the guidelines in the Modules (External projects) section for contributing new modules and submitting changes to existing modules.

8.1.13 Treewide Changes

This section describes contributions that are treewide changes and some additional associated requirements that apply to them. These requirements exist to try to give such changes increased review and user visibility due to their large impact.

Definition and Decision Making

A treewide change is defined as any change to Zephyr APIs, coding practices, or other development requirements that either implies required changes throughout the zephyr source code repository or can reasonably be expected to do so for a wide class of external Zephyr-based source code.

This definition is informal by necessity. This is because the decision on whether any particular change is treewide can be subjective and may depend on additional context.

Project maintainers should use good judgement and prioritize the Zephyr developer experience when deciding when a proposed change is treewide. Protracted disagreements can be resolved by the Zephyr Project’s Technical Steering Committee (TSC), but please avoid premature escalation to the TSC.

Requirements for Treewide Changes

- The zephyr repository must apply the ‘treewide’ GitHub label to any issues or pull requests that are treewide changes
- The person proposing a treewide change must create an RFC issue describing the change, its rationale and impact, etc. before any pull requests related to the change can be merged
- The project’s Architecture Working Group (WG) must include the issue on the agenda and discuss whether the project will accept or reject the change before any pull requests related to the change can be merged (with escalation to the TSC if consensus is not reached at the WG)
- The Architecture WG must specify the procedure for merging any PRs associated with each individual treewide change, including any required approvals for pull requests affecting specific sub-systems or extra review time requirements
- The person proposing a treewide change must email devel@lists.zephyrproject.org about the RFC if it is accepted by the Architecture WG before any pull requests related to the change can be merged

Examples

Some example past treewide changes are:
- the deprecation of version 1 of the Logging API in favor of version 2 (see commit 262cc55609)
- the removal of support for a legacy Devicetree bindings syntax (6bf761fc0a)

Note that adding a new version of a widely used API while maintaining support for the old one is not a treewide change. Deprecation and removal of such APIs, however, are treewide changes.
8.2 Coding Guidelines

The project TSC and the Safety Committee of the project agreed to implement a staged and incremental approach for complying with a set of coding rules (AKA Coding Guidelines) to improve quality and consistency of the code base. Below are the agreed upon stages and the approximate timelines:

Stage I
Coding guideline rules are available to be followed and referenced, but not enforced. Rules are not yet enforced in CI and pull-requests cannot be blocked by reviewers/approvers due to violations.

Stage II
Begin enforcement on a limited scope of the code base. Initially, this would be the safety certification scope. For rules easily applied across codebase, we should not limit compliance to initial scope. This step requires tooling and CI setup and will start sometime after LTS2.

Stage III
Revisit the coding guideline rules and based on experience from previous stages, refine/iterate on selected rules.

Stage IV
Expand enforcement to the wider codebase. Exceptions may be granted on some areas of the codebase with a proper justification. Exception would require TSC approval.

**Note:** Coding guideline rules may be removed/changed at any time by filing a GH issue/RFC.

8.2.1 Main rules

The coding guideline rules are based on MISRA-C 2012 and are a subset of MISRA-C. The subset is listed in the table below with a summary of the rules, its severity and the equivalent rules from other standards for reference.

**Note:** For existing Zephyr maintainers and collaborators, if you are unable to obtain a copy through your employer, a limited number of copies will be made available through the project. If you need a copy of MISRA-C 2012, please send email to safety@lists.zephyrproject.org and provide details on reason why you can't obtain one through other options and expected contributions once you have one. The safety committee will review all requests.

<table>
<thead>
<tr>
<th>MISRA C 2012</th>
<th>Severity</th>
<th>Description</th>
<th>CERT C</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Dir 1.1</td>
<td>Required</td>
<td>Any implementation-defined behaviour on which the output of the program depends shall be documented and understood</td>
<td>MSC09-C</td>
<td>Dir 1.1</td>
</tr>
<tr>
<td>Dir 2.1</td>
<td>Required</td>
<td>All source files shall compile without any compilation errors</td>
<td>N/A</td>
<td>Dir 2.1</td>
</tr>
<tr>
<td>Dir 3.1</td>
<td>Required</td>
<td>All code shall be traceable to documented requirements</td>
<td>N/A</td>
<td>Dir 3.1</td>
</tr>
<tr>
<td>Dir 4.1</td>
<td>Required</td>
<td>Run-time failures shall be minimized</td>
<td>N/A</td>
<td>Dir 4.1</td>
</tr>
<tr>
<td>Dir 4.2</td>
<td>Advisory</td>
<td>All usage of assembly language should be documented</td>
<td>N/A</td>
<td>Dir 4.2</td>
</tr>
<tr>
<td>Dir 4.4</td>
<td>Advisory</td>
<td>Sections of code should not be “commented out”</td>
<td>MSC04-C</td>
<td>Dir 4.4</td>
</tr>
</tbody>
</table>

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<table>
<thead>
<tr>
<th>MISRA C 2012</th>
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<th>Description</th>
<th>CERT C</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Dir 4.5</td>
<td>Advisory</td>
<td>Identifiers in the same name space with overlapping visibility should be typographically unambiguous</td>
<td>DCL02-C</td>
<td>Dir 4.5</td>
</tr>
<tr>
<td>Dir 4.6</td>
<td>Advisory</td>
<td>typedefs that indicate size and signedness should be used in place of the basic numerical types</td>
<td>N/A</td>
<td>Dir 4.6</td>
</tr>
<tr>
<td>Dir 4.7</td>
<td>Required</td>
<td>If a function returns error information, then that error information shall be tested</td>
<td>N/A</td>
<td>Dir 4.7</td>
</tr>
<tr>
<td>Dir 4.8</td>
<td>Advisory</td>
<td>If a pointer to a structure or union is never dereferenced within a translation unit, then the implementation of the object should be hidden</td>
<td>DCL12-C</td>
<td>Dir 4.8 example 1 Dir 4.8 example 2</td>
</tr>
<tr>
<td>Dir 4.9</td>
<td>Advisory</td>
<td>A function should be used in preference to a function-like macro where they are interchangeable</td>
<td>PRE00-C</td>
<td>Dir 4.9</td>
</tr>
<tr>
<td>Dir 4.10</td>
<td>Required</td>
<td>Precautions shall be taken in order to prevent the contents of a header file being included more than once</td>
<td>PRE06-C</td>
<td>Dir 4.10</td>
</tr>
<tr>
<td>Dir 4.11</td>
<td>Required</td>
<td>The validity of values passed to library functions shall be checked</td>
<td>N/A</td>
<td>Dir 4.11</td>
</tr>
<tr>
<td>Dir 4.12</td>
<td>Required</td>
<td>Dynamic memory allocation shall not be used</td>
<td>STR01-C</td>
<td>Dir 4.12</td>
</tr>
<tr>
<td>Dir 4.13</td>
<td>Advisory</td>
<td>Functions which are designed to provide operations on a resource should be called in an appropriate sequence</td>
<td>N/A</td>
<td>Dir 4.13</td>
</tr>
<tr>
<td>Dir 4.14</td>
<td>Required</td>
<td>The validity of values received from external sources shall be checked</td>
<td>N/A</td>
<td>Dir 4.14</td>
</tr>
<tr>
<td>Rule 1.2</td>
<td>Advisory</td>
<td>Language extensions should not be used</td>
<td>MSC04-C</td>
<td>Rule 1.2</td>
</tr>
<tr>
<td>Rule 1.3</td>
<td>Required</td>
<td>There shall be no occurrence of undefined or critical unspecified behaviour</td>
<td>N/A</td>
<td>Rule 1.3</td>
</tr>
<tr>
<td>Rule 2.1</td>
<td>Required</td>
<td>A project shall not contain unreachable code</td>
<td>MSC07-C</td>
<td>Rule 2.1 example 1 Rule 2.1 example 2</td>
</tr>
<tr>
<td>Rule 2.2</td>
<td>Required</td>
<td>There shall be no dead code</td>
<td>MSC12-C</td>
<td>Rule 2.2</td>
</tr>
<tr>
<td>Rule 2.3</td>
<td>Advisory</td>
<td>A project should not contain unused type declarations</td>
<td>N/A</td>
<td>Rule 2.3</td>
</tr>
<tr>
<td>Rule 2.6</td>
<td>Advisory</td>
<td>A function should not contain unused label declarations</td>
<td>N/A</td>
<td>Rule 2.6</td>
</tr>
<tr>
<td>Rule 2.7</td>
<td>Advisory</td>
<td>There should be no unused parameters in functions</td>
<td>N/A</td>
<td>Rule 2.7</td>
</tr>
<tr>
<td>Rule 3.1</td>
<td>Required</td>
<td>The character sequences /* and // shall not be used within a comment</td>
<td>MSC04-C</td>
<td>Rule 3.1</td>
</tr>
<tr>
<td>Rule 3.2</td>
<td>Required</td>
<td>Line-splicing shall not be used in // comments</td>
<td>N/A</td>
<td>Rule 3.2</td>
</tr>
<tr>
<td>Rule 4.1</td>
<td>Required</td>
<td>Octal and hexadecimal escape sequences shall be terminated</td>
<td>MSC09-C</td>
<td>Rule 4.1</td>
</tr>
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</table>

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<thead>
<tr>
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<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rule 4.2</td>
<td>Advisory</td>
<td>Trigraphs should not be used</td>
<td>PRE07-C</td>
<td>Rule 4.2</td>
</tr>
<tr>
<td>Rule 5.1</td>
<td>Required</td>
<td>External identifiers shall be distinct</td>
<td>DCL23-C</td>
<td>Rule 5.1 example 1 Rule 5.1 example 2</td>
</tr>
<tr>
<td>Rule 5.2</td>
<td>Required</td>
<td>Identifiers declared in the same scope and name space shall be distinct</td>
<td>DCL23-C</td>
<td>Rule 5.2</td>
</tr>
<tr>
<td>Rule 5.3</td>
<td>Required</td>
<td>An identifier declared in an inner scope shall not hide an identifier declared in an outer scope</td>
<td>DCL23-C</td>
<td>Rule 5.3</td>
</tr>
<tr>
<td>Rule 5.4</td>
<td>Required</td>
<td>Macro identifiers shall be distinct</td>
<td>DCL23-C</td>
<td>Rule 5.4</td>
</tr>
<tr>
<td>Rule 5.5</td>
<td>Required</td>
<td>Identifiers shall be distinct from macro names</td>
<td>DCL23-C</td>
<td>Rule 5.5</td>
</tr>
<tr>
<td>Rule 5.6</td>
<td>Required</td>
<td>A typedef name shall be a unique identifier</td>
<td>N/A</td>
<td>Rule 5.6</td>
</tr>
<tr>
<td>Rule 5.7</td>
<td>Required</td>
<td>A tag name shall be a unique identifier</td>
<td>N/A</td>
<td>Rule 5.7</td>
</tr>
<tr>
<td>Rule 5.8</td>
<td>Required</td>
<td>Identifiers that define objects or functions with external linkage shall be unique</td>
<td>N/A</td>
<td>Rule 5.8 example 1 Rule 5.8 example 2</td>
</tr>
<tr>
<td>Rule 5.9</td>
<td>Advisory</td>
<td>Identifiers that define objects or functions with internal linkage should be unique</td>
<td>N/A</td>
<td>Rule 5.9 example 1 Rule 5.9 example 2</td>
</tr>
<tr>
<td>Rule 6.1</td>
<td>Required</td>
<td>Bit-fields shall only be declared with an appropriate type</td>
<td>INT14-C</td>
<td>Rule 6.1</td>
</tr>
<tr>
<td>Rule 6.2</td>
<td>Required</td>
<td>Single-bit named bit fields shall not be of a signed type</td>
<td>INT14-C</td>
<td>Rule 6.2</td>
</tr>
<tr>
<td>Rule 7.1</td>
<td>Required</td>
<td>Octal constants shall not be used</td>
<td>DCL18-C</td>
<td>Rule 7.1</td>
</tr>
<tr>
<td>Rule 7.2</td>
<td>Required</td>
<td>A u or U suffix shall be applied to all integer constants that are represented in an unsigned type</td>
<td>N/A</td>
<td>Rule 7.2</td>
</tr>
<tr>
<td>Rule 7.3</td>
<td>Required</td>
<td>The lowercase character l shall not be used in a literal suffix</td>
<td>DCL16-C</td>
<td>Rule 7.3</td>
</tr>
<tr>
<td>Rule 7.4</td>
<td>Required</td>
<td>A string literal shall not be assigned to an object unless the objects type is pointer to const-qualified char</td>
<td>N/A</td>
<td>Rule 7.4</td>
</tr>
<tr>
<td>Rule 8.1</td>
<td>Required</td>
<td>Types shall be explicitly specified</td>
<td>N/A</td>
<td>Rule 8.1</td>
</tr>
<tr>
<td>Rule 8.2</td>
<td>Required</td>
<td>Function types shall be in prototype form with named parameters</td>
<td>DCL20-C</td>
<td>Rule 8.2</td>
</tr>
</tbody>
</table>

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<table>
<thead>
<tr>
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<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>Rule 8.3</td>
<td>Required</td>
<td>All declarations of an object or function shall use the same names and type qualifiers</td>
<td>N/A</td>
<td>Rule 8.3</td>
</tr>
<tr>
<td>Rule 8.4</td>
<td>Required</td>
<td>A compatible declaration shall be visible when an object or function with external linkage is defined</td>
<td>N/A</td>
<td>Rule 8.4</td>
</tr>
<tr>
<td>Rule 8.5</td>
<td>Required</td>
<td>An external object or function shall be declared once in one and only one file</td>
<td>N/A</td>
<td>Rule 8.5 example 1, Rule 8.5 example 2</td>
</tr>
<tr>
<td>Rule 8.6</td>
<td>Required</td>
<td>An identifier with external linkage shall have exactly one external definition</td>
<td>N/A</td>
<td>Rule 8.6 example 1, Rule 8.6 example 2</td>
</tr>
<tr>
<td>Rule 8.8</td>
<td>Required</td>
<td>The static storage class specifier shall be used in all declarations of objects and functions that have internal linkage</td>
<td>DCL15-C</td>
<td>Rule 8.8</td>
</tr>
<tr>
<td>Rule 8.9</td>
<td>Advisory</td>
<td>An object should be defined at block scope if its identifier only appears in a single function</td>
<td>DCL19-C</td>
<td>Rule 8.9</td>
</tr>
<tr>
<td>Rule 8.10</td>
<td>Required</td>
<td>An inline function shall be declared with the static storage class</td>
<td>N/A</td>
<td>Rule 8.10</td>
</tr>
<tr>
<td>Rule 8.12</td>
<td>Required</td>
<td>Within an enumerator list, the value of an implicitly-specified enumeration constant shall be unique</td>
<td>INT09-C</td>
<td>Rule 8.12</td>
</tr>
<tr>
<td>Rule 8.14</td>
<td>Required</td>
<td>The restrict type qualifier shall not be used</td>
<td>N/A</td>
<td>Rule 8.14</td>
</tr>
<tr>
<td>Rule 9.1</td>
<td>Mandatory</td>
<td>The value of an object with automatic storage duration shall not be read before it has been set</td>
<td>N/A</td>
<td>Rule 9.1</td>
</tr>
<tr>
<td>Rule 9.2</td>
<td>Required</td>
<td>The initializer for an aggregate or union shall be enclosed in braces</td>
<td>N/A</td>
<td>Rule 9.2</td>
</tr>
<tr>
<td>Rule 9.3</td>
<td>Required</td>
<td>Arrays shall not be partially initialized</td>
<td>N/A</td>
<td>Rule 9.3</td>
</tr>
<tr>
<td>Rule 9.4</td>
<td>Required</td>
<td>An element of an object shall not be initialized more than once</td>
<td>N/A</td>
<td>Rule 9.4</td>
</tr>
<tr>
<td>Rule 9.5</td>
<td>Required</td>
<td>Where designated initializers are used to initialize an array object the size of the array shall be specified explicitly</td>
<td>N/A</td>
<td>Rule 9.5</td>
</tr>
<tr>
<td>Rule 10.1</td>
<td>Required</td>
<td>Operands shall not be of an inappropriate essential type</td>
<td>STR04-C</td>
<td>Rule 10.1</td>
</tr>
<tr>
<td>Rule 10.2</td>
<td>Required</td>
<td>Expressions of essentially character type shall not be used inappropriately in addition and subtraction operations</td>
<td>STR04-C</td>
<td>Rule 10.2</td>
</tr>
<tr>
<td>Rule 10.3</td>
<td>Required</td>
<td>The value of an expression shall not be assigned to an object with a narrower essential type or of a different essential type category</td>
<td>STR04-C</td>
<td>Rule 10.3</td>
</tr>
</tbody>
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<tbody>
<tr>
<td>Rule 10.4</td>
<td>Required</td>
<td>Both operands of an operator in which the usual arithmetic conversions are performed shall have the same essential type category</td>
<td>STR04-C</td>
<td>Rule 10.4</td>
</tr>
<tr>
<td>Rule 10.5</td>
<td>Advisory</td>
<td>The value of an expression should not be cast to an inappropriate essential type</td>
<td>N/A</td>
<td>Rule 10.5</td>
</tr>
<tr>
<td>Rule 10.6</td>
<td>Required</td>
<td>The value of a composite expression shall not be assigned to an object with wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.6</td>
</tr>
<tr>
<td>Rule 10.7</td>
<td>Required</td>
<td>If a composite expression is used as one operand of an operator in which the usual arithmetic conversions are performed then the other operand shall not have wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.7</td>
</tr>
<tr>
<td>Rule 10.8</td>
<td>Required</td>
<td>The value of a composite expression shall not be cast to a different essential type category or a wider essential type</td>
<td>INT02-C</td>
<td>Rule 10.8</td>
</tr>
<tr>
<td>Rule 11.2</td>
<td>Required</td>
<td>Conversions shall not be performed between a pointer to an incomplete type and any other type</td>
<td>N/A</td>
<td>Rule 11.2</td>
</tr>
<tr>
<td>Rule 11.6</td>
<td>Required</td>
<td>A cast shall not be performed between pointer to void and an arithmetic type</td>
<td>N/A</td>
<td>Rule 11.6</td>
</tr>
<tr>
<td>Rule 11.7</td>
<td>Required</td>
<td>A cast shall not be performed between pointer to object and a noninteger arithmetic type</td>
<td>N/A</td>
<td>Rule 11.7</td>
</tr>
<tr>
<td>Rule 11.8</td>
<td>Required</td>
<td>A cast shall not remove any const or volatile qualification from the type pointed to by a pointer</td>
<td>EXP05-C</td>
<td>Rule 11.8</td>
</tr>
<tr>
<td>Rule 11.9</td>
<td>Required</td>
<td>The macro NULL shall be the only permitted form of integer null pointer constant</td>
<td>N/A</td>
<td>Rule 11.9</td>
</tr>
<tr>
<td>Rule 12.1</td>
<td>Advisory</td>
<td>The precedence of operators within expressions should be made explicit</td>
<td>EXP00-C</td>
<td>Rule 12.1</td>
</tr>
<tr>
<td>Rule 12.2</td>
<td>Required</td>
<td>The right hand operand of a shift operator shall lie in the range zero to one less than the width in bits of the essential type of the left hand operand</td>
<td>N/A</td>
<td>Rule 12.2</td>
</tr>
<tr>
<td>Rule 12.4</td>
<td>Advisory</td>
<td>Evaluation of constant expressions should not lead to unsigned integer wrap-around</td>
<td>N/A</td>
<td>Rule 12.4</td>
</tr>
<tr>
<td>Rule 12.5</td>
<td>Mandatory</td>
<td>The sizeof operator shall not have an operand which is a function parameter declared as “array of type”</td>
<td>N/A</td>
<td>Rule 12.5</td>
</tr>
<tr>
<td>Rule 13.1</td>
<td>Required</td>
<td>Initializer lists shall not contain persistent side effects</td>
<td>N/A</td>
<td>Rule 13.1 example 1 Rule 13.1 example 2</td>
</tr>
<tr>
<td>Rule 13.2</td>
<td>Required</td>
<td>The value of an expression and its persistent side effects shall be the same under all permitted evaluation orders</td>
<td>N/A</td>
<td>Rule 13.2</td>
</tr>
</tbody>
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<tbody>
<tr>
<td>Rule 13.3</td>
<td>Advisory</td>
<td>A full expression containing an increment (+ +) or decrement (–) operator should have no other potential side effects other than that caused by the increment or decrement operator</td>
<td>N/A</td>
<td>Rule 13.3</td>
</tr>
<tr>
<td>Rule 13.4</td>
<td>Advisory</td>
<td>The result of an assignment operator should not be used</td>
<td>N/A</td>
<td>Rule 13.4</td>
</tr>
<tr>
<td>Rule 13.5</td>
<td>Required</td>
<td>The right hand operand of a logical &amp;&amp; or</td>
<td></td>
<td>operator shall not contain persistent side effects</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td></td>
<td>Rule 13.5 example 2</td>
</tr>
<tr>
<td>Rule 13.6</td>
<td>Mandatory</td>
<td>The operand of the sizeof operator shall not contain any expression which has potential side effects</td>
<td>N/A</td>
<td>Rule 13.6</td>
</tr>
<tr>
<td>Rule 14.1</td>
<td>Required</td>
<td>A loop counter shall not have essentially floating type</td>
<td>N/A</td>
<td>Rule 14.1</td>
</tr>
<tr>
<td>Rule 14.2</td>
<td>Required</td>
<td>A for loop shall be well-formed</td>
<td>N/A</td>
<td>Rule 14.2</td>
</tr>
<tr>
<td>Rule 14.3</td>
<td>Required</td>
<td>Controlling expressions shall not be invariant</td>
<td>N/A</td>
<td>Rule 14.3</td>
</tr>
<tr>
<td>Rule 14.4</td>
<td>Required</td>
<td>The controlling expression of an if statement and the controlling expression of an iteration-statement shall have essentially Boolean type</td>
<td>N/A</td>
<td>Rule 14.4</td>
</tr>
<tr>
<td>Rule 15.2</td>
<td>Required</td>
<td>The goto statement shall jump to a label declared later in the same function</td>
<td>N/A</td>
<td>Rule 15.2</td>
</tr>
<tr>
<td>Rule 15.3</td>
<td>Required</td>
<td>Any label referenced by a goto statement shall be declared in the same block, or in any block enclosing the goto statement</td>
<td>N/A</td>
<td>Rule 15.3</td>
</tr>
<tr>
<td>Rule 15.6</td>
<td>Required</td>
<td>The body of an iteration-statement or a selection-statement shall be a compound-statement</td>
<td>EXP19-C</td>
<td>Rule 15.6</td>
</tr>
<tr>
<td>Rule 15.7</td>
<td>Required</td>
<td>All if else if constructs shall be terminated with an else statement</td>
<td>N/A</td>
<td>Rule 15.7</td>
</tr>
<tr>
<td>Rule 16.1</td>
<td>Required</td>
<td>All switch statements shall be well-formed</td>
<td>N/A</td>
<td>Rule 16.1</td>
</tr>
<tr>
<td>Rule 16.2</td>
<td>Required</td>
<td>A switch label shall only be used when the most closely-enclosing compound statement is the body of a switch statement</td>
<td>MSC20-C</td>
<td>Rule 16.2</td>
</tr>
<tr>
<td>Rule 16.3</td>
<td>Required</td>
<td>An unconditional break statement shall terminate every switch-clause</td>
<td>N/A</td>
<td>Rule 16.3</td>
</tr>
<tr>
<td>Rule 16.4</td>
<td>Required</td>
<td>Every switch statement shall have a default label</td>
<td>N/A</td>
<td>Rule 16.4</td>
</tr>
<tr>
<td>Rule 16.5</td>
<td>Required</td>
<td>A default label shall appear as either the first or the last switch label of a switch statement</td>
<td>N/A</td>
<td>Rule 16.5</td>
</tr>
<tr>
<td>Rule 16.6</td>
<td>Required</td>
<td>Every switch statement shall have at least two switch-clauses</td>
<td>N/A</td>
<td>Rule 16.6</td>
</tr>
<tr>
<td>Rule 16.7</td>
<td>Required</td>
<td>A switch-expression shall not have essentially Boolean type</td>
<td>N/A</td>
<td>Rule 16.7</td>
</tr>
</tbody>
</table>

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<tbody>
<tr>
<td>Rule 17.1</td>
<td>Required</td>
<td>The features of <code>&lt;stdarg.h&gt;</code> shall not be used</td>
<td>ERR00-C</td>
<td>Rule 17.1</td>
</tr>
<tr>
<td>Rule 17.2</td>
<td>Required</td>
<td>Functions shall not call themselves, either directly or indirectly</td>
<td>MEM05-C</td>
<td>Rule 17.2</td>
</tr>
<tr>
<td>Rule 17.3</td>
<td>Mandatory</td>
<td>A function shall not be declared implicitly</td>
<td>N/A</td>
<td>Rule 17.3</td>
</tr>
<tr>
<td>Rule 17.4</td>
<td>Mandatory</td>
<td>All exit paths from a function with non-void return type shall have an explicit return statement with an expression</td>
<td>N/A</td>
<td>Rule 17.4</td>
</tr>
<tr>
<td>Rule 17.5</td>
<td>Advisory</td>
<td>The function argument corresponding to a parameter declared to have an array type shall have an appropriate number of elements</td>
<td>N/A</td>
<td>Rule 17.5</td>
</tr>
<tr>
<td>Rule 17.6</td>
<td>Mandatory</td>
<td>The declaration of an array parameter shall not contain the static keyword between the [ ]</td>
<td>N/A</td>
<td>Rule 17.6</td>
</tr>
<tr>
<td>Rule 17.7</td>
<td>Required</td>
<td>The value returned by a function having non-void return type shall be used</td>
<td>N/A</td>
<td>Rule 17.7</td>
</tr>
<tr>
<td>Rule 18.1</td>
<td>Required</td>
<td>A pointer resulting from arithmetic on a pointer operand shall address an element of the same array as that pointer operand</td>
<td>EXP08-C</td>
<td>Rule 18.1</td>
</tr>
<tr>
<td>Rule 18.2</td>
<td>Required</td>
<td>Subtraction between pointers shall only be applied to pointers that address elements of the same array</td>
<td>EXP08-C</td>
<td>Rule 18.2</td>
</tr>
<tr>
<td>Rule 18.3</td>
<td>Required</td>
<td>The relational operators &gt;, &gt;=, &lt; and &lt;= shall not be applied to objects of pointer type except where they point into the same object</td>
<td>EXP08-C</td>
<td>Rule 18.3</td>
</tr>
<tr>
<td>Rule 18.5</td>
<td>Advisory</td>
<td>Declarations should contain no more than two levels of pointer nesting</td>
<td>N/A</td>
<td>Rule 18.5</td>
</tr>
</tbody>
</table>
| Rule 18.6    | Required | The address of an object with automatic storage shall not be copied to another object that persists after the first object has ceased to exist | N/A | Rule 18.6 example 1 
Rule 18.6 example 2 |
| Rule 18.8    | Required | Variable-length array types shall not be used | N/A | Rule 18.8 |
| Rule 19.1    | Mandatory | An object shall not be assigned or copied to an overlapping object | N/A | Rule 19.1 |
| Rule 20.2    | Required | The ", " or characters and the "/" or // character sequences shall not occur in a header file name" | N/A | Rule 20.2 |
| Rule 20.3    | Required | The #include directive shall be followed by either a `<filename>` or “filename” sequence | N/A | Rule 20.3 |
| Rule 20.4    | Required | A macro shall not be defined with the same name as a keyword | N/A | Rule 20.4 |
| Rule 20.7    | Required | Expressions resulting from the expansion of macro parameters shall be enclosed in parentheses | PRE01-C | Rule 20.7 |

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<tbody>
<tr>
<td>Rule 20.8</td>
<td>Required</td>
<td>The controlling expression of a #if or #elif preprocessing directive shall evaluate to 0 or 1</td>
<td>N/A</td>
<td>Rule 20.8</td>
</tr>
<tr>
<td>Rule 20.9</td>
<td>Required</td>
<td>All identifiers used in the controlling expression of #if or #elif preprocessing directives shall be #defined before evaluation</td>
<td>N/A</td>
<td>Rule 20.9</td>
</tr>
<tr>
<td>Rule 20.11</td>
<td>Required</td>
<td>A macro parameter immediately following a # operator shall not immediately be followed by a ## operator</td>
<td>N/A</td>
<td>Rule 20.11</td>
</tr>
<tr>
<td>Rule 20.12</td>
<td>Required</td>
<td>A macro parameter used as an operand to the # or ## operators, which is itself subject to further macro replacement, shall only be used as an operand to these operators</td>
<td>N/A</td>
<td>Rule 20.12</td>
</tr>
<tr>
<td>Rule 20.13</td>
<td>Required</td>
<td>A line whose first token is # shall be a valid preprocessing directive</td>
<td>N/A</td>
<td>Rule 20.13</td>
</tr>
<tr>
<td>Rule 20.14</td>
<td>Required</td>
<td>All #else, #elif and #endif preprocessing directives shall reside in the same file as the #if, #ifdef or #ifndef directive to which they are related</td>
<td>N/A</td>
<td>Rule 20.14</td>
</tr>
<tr>
<td>Rule 21.1</td>
<td>Required</td>
<td>#define and #undef shall not be used on a reserved identifier or reserved macro name</td>
<td>N/A</td>
<td>Rule 21.1</td>
</tr>
<tr>
<td>Rule 21.2</td>
<td>Required</td>
<td>A reserved identifier or macro name shall not be declared</td>
<td>N/A</td>
<td>Rule 21.2</td>
</tr>
<tr>
<td>Rule 21.3</td>
<td>Required</td>
<td>The memory allocation and deallocation functions of &lt;stdlib.h&gt; shall not be used</td>
<td>MSC24-C</td>
<td>Rule 21.3</td>
</tr>
<tr>
<td>Rule 21.4</td>
<td>Required</td>
<td>The standard header file &lt;setjmp.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.4</td>
</tr>
<tr>
<td>Rule 21.6</td>
<td>Required</td>
<td>The Standard Library input/output functions shall not be used</td>
<td>N/A</td>
<td>Rule 21.6</td>
</tr>
<tr>
<td>Rule 21.7</td>
<td>Required</td>
<td>The atof, atoi, atol and atoll functions of &lt;stdlib.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.7</td>
</tr>
<tr>
<td>Rule 21.9</td>
<td>Required</td>
<td>The library functions bsearch and qsort of &lt;stdlib.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.9</td>
</tr>
<tr>
<td>Rule 21.11</td>
<td>Required</td>
<td>The standard header file &lt;tgmath.h&gt; shall not be used</td>
<td>N/A</td>
<td>Rule 21.11</td>
</tr>
<tr>
<td>Rule 21.12</td>
<td>Advisory</td>
<td>The exception handling features of &lt;fenv.h&gt; should not be used</td>
<td>N/A</td>
<td>Rule 21.12</td>
</tr>
<tr>
<td>Rule 21.13</td>
<td>Mandatory</td>
<td>Any value passed to a function in &lt;ctypes.h&gt; shall be representable as an unsigned char or be the value EO</td>
<td>N/A</td>
<td>Rule 21.13</td>
</tr>
<tr>
<td>Rule 21.14</td>
<td>Required</td>
<td>The Standard Library function memcmp shall not be used to compare null terminated strings</td>
<td>N/A</td>
<td>Rule 21.14</td>
</tr>
<tr>
<td>Rule 21.15</td>
<td>Required</td>
<td>The pointer arguments to the Standard Library functions memcpy, memmove and memcmp shall be pointers to qualified or unqualified versions of compatible types</td>
<td>N/A</td>
<td>Rule 21.15</td>
</tr>
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<tr>
<td>Rule 21.16</td>
<td>Required</td>
<td>The pointer arguments to the Standard Library function memcmp shall point to either a pointer type, an essentially signed type, an essentially unsigned type, an essentially Boolean type or an essentially enum type</td>
<td>N/A</td>
<td>Rule 21.16</td>
</tr>
<tr>
<td>Rule 21.17</td>
<td>Mandatory</td>
<td>Use of the string handling functions from <code>&lt;string.h&gt;</code> shall not result in accesses beyond the bounds of the objects referenced by their pointer parameters</td>
<td>N/A</td>
<td>Rule 21.17</td>
</tr>
<tr>
<td>Rule 21.18</td>
<td>Mandatory</td>
<td>The size_t argument passed to any function in <code>&lt;string.h&gt;</code> shall have an appropriate value</td>
<td>N/A</td>
<td>Rule 21.18</td>
</tr>
<tr>
<td>Rule 21.19</td>
<td>Mandatory</td>
<td>The pointers returned by the Standard Library functions localeconv, getenv, setlocale or, strerror shall only be used as if they have pointer to const-qualified type</td>
<td>N/A</td>
<td>Rule 21.19</td>
</tr>
<tr>
<td>Rule 21.20</td>
<td>Mandatory</td>
<td>The pointer returned by the Standard Library functions asctime, ctime, gmtime, localtime, localeconv, getenv, setlocale or strerror shall not be used following a subsequent call to the same function</td>
<td>N/A</td>
<td>Rule 21.20</td>
</tr>
<tr>
<td>Rule 22.1</td>
<td>Required</td>
<td>All resources obtained dynamically by means of Standard Library functions shall be explicitly released</td>
<td>N/A</td>
<td>Rule 22.1</td>
</tr>
<tr>
<td>Rule 22.2</td>
<td>Mandatory</td>
<td>A block of memory shall only be freed if it was allocated by means of a Standard Library function</td>
<td>N/A</td>
<td>Rule 22.2</td>
</tr>
<tr>
<td>Rule 22.3</td>
<td>Required</td>
<td>The same file shall not be open for read and write access at the same time on different streams</td>
<td>N/A</td>
<td>Rule 22.3</td>
</tr>
<tr>
<td>Rule 22.4</td>
<td>Mandatory</td>
<td>There shall be no attempt to write to a stream which has been opened as read-only</td>
<td>N/A</td>
<td>Rule 22.4</td>
</tr>
<tr>
<td>Rule 22.5</td>
<td>Mandatory</td>
<td>A pointer to a FILE object shall not be dereferenced</td>
<td>N/A</td>
<td>Rule 22.5</td>
</tr>
<tr>
<td>Rule 22.6</td>
<td>Mandatory</td>
<td>The value of a pointer to a FILE shall not be used after the associated stream has been closed</td>
<td>N/A</td>
<td>Rule 22.6</td>
</tr>
<tr>
<td>Rule 22.7</td>
<td>Required</td>
<td>The macro EOF shall only be compared with the unmodified return value from any Standard Library function capable of returning EOF</td>
<td>N/A</td>
<td>Rule 22.7</td>
</tr>
<tr>
<td>Rule 22.8</td>
<td>Required</td>
<td>The value of errno shall be set to zero prior to a call to an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.8</td>
</tr>
<tr>
<td>Rule 22.9</td>
<td>Required</td>
<td>The value of errno shall be tested against zero after calling an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.9</td>
</tr>
<tr>
<td>Rule 22.10</td>
<td>Required</td>
<td>The value of errno shall only be tested when the last function to be called was an errno-setting-function</td>
<td>N/A</td>
<td>Rule 22.10</td>
</tr>
</tbody>
</table>

#### 8.2.2 Additional rules
Rule A.1: Conditional Compilation

Severity  Required

Description  Do not conditionally compile function declarations in header files. Do not conditionally compile structure declarations in header files. You may conditionally exclude fields within structure definitions to avoid wasting memory when the feature they support is not enabled.

Rationale  Excluding declarations from the header based on compile-time options may prevent their documentation from being generated. Their absence also prevents use of `if (IS_ENABLED(CONFIG_FOO)) {}` as an alternative to preprocessor conditionals when the code path should change based on the selected options.

Rule A.2: Inclusive Language

Severity  Required

Description  Do not introduce new usage of offensive terms listed below. This rule applies but is not limited to source code, comments, documentation, and branch names. Replacement terms may vary by area or subsystem, but should aim to follow updated industry standards when possible. Exceptions are allowed for maintaining existing implementations or adding new implementations of industry standard specifications governed externally to the Zephyr Project. Existing usage is recommended to change as soon as updated industry standard specifications become available or new terms are publicly announced by the governing body, or immediately if no specifications apply.

<table>
<thead>
<tr>
<th>Offensive Terms</th>
<th>Recommended Replacements</th>
</tr>
</thead>
<tbody>
<tr>
<td>{master,leader} / slave</td>
<td>• {primary,main} / {secondary, replica}</td>
</tr>
<tr>
<td></td>
<td>• {initiator,requester} / {target, responder}</td>
</tr>
<tr>
<td></td>
<td>• {controller,host} / {device,worker, proxy,target}</td>
</tr>
<tr>
<td></td>
<td>• director / performer</td>
</tr>
<tr>
<td></td>
<td>• central / peripheral</td>
</tr>
<tr>
<td>blacklist / whitelist</td>
<td>• denylist / allowlist</td>
</tr>
<tr>
<td></td>
<td>• blocklist / allowlist</td>
</tr>
<tr>
<td></td>
<td>• rejectlist / acceptlist</td>
</tr>
<tr>
<td>grandfather policy</td>
<td>• legacy</td>
</tr>
<tr>
<td>sanity</td>
<td>• coherence</td>
</tr>
<tr>
<td></td>
<td>• confidence</td>
</tr>
</tbody>
</table>

Rationale  Offensive terms do not create an inclusive community environment and therefore violate the Zephyr Project Code of Conduct. This coding rule was inspired by a similar rule in Linux.
Status  Related GitHub Issues and Pull Requests are tagged with the Inclusive Language Label.

<table>
<thead>
<tr>
<th>Area</th>
<th>Selected Replacements</th>
<th>Status</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bluetooth APIs</td>
<td>See Bluetooth Appropriate Language Mapping Tables</td>
<td></td>
</tr>
<tr>
<td>CAN</td>
<td>This CAN in Automation Inclusive Language news post has a list of general recommendations. See CAN in Automation Inclusive Language for terms to be used in specification document updates.</td>
<td></td>
</tr>
<tr>
<td>eSPI</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>gPTP</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>I2C</td>
<td>• master / slave =&gt; TBD</td>
<td>NXP publishes the I2C Specification and has selected controller / target as replacement terms, but the timing to publish an announcement or new specification is TBD. Zephyr will update I2C when replacement terminology is confirmed by a public announcement or updated specification. See Zephyr issue 27033.</td>
</tr>
<tr>
<td>I2S</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>SMP/AMP</td>
<td>• master / slave =&gt; TBD</td>
<td></td>
</tr>
<tr>
<td>SPI</td>
<td>• master / slave =&gt; TBD</td>
<td>The Open Source Hardware Association has selected these replacement terms. See OSHWA Resolution to Redefine SPI Signal Names</td>
</tr>
<tr>
<td>Test Runner (Twister)</td>
<td>• platform_whitelist =&gt; platform_allow • sanitycheck =&gt; twister</td>
<td></td>
</tr>
</tbody>
</table>

8.2.3 Parasoft Codescan Tool

Parasoft Codescan is an official static code analysis tool used by the Zephyr project. It is used to automate compliance with a range of coding and security standards. The tool is currently set to the MISRA-C:2012 Coding Standard because the Zephyr Coding Guidelines are based on that standard. It is used together with the Coverity Scan tool to achieve the best code health and precision in bug findings.
Violations fixing process

Step 1
Any Zephyr Project member, company or a developer can request access to the Parasoft reporting centre if they wish to get involved in fixing violations by submitting issues.

Step 2
A developer starts to review violations.

Step 3
A developer submits a Github PR with the fix. Commit messages should follow the same guidelines as other PRs in the Zephyr project. Please add a comment that your fix was found by a static coding scanning tool. Developers should follow and refer to the Zephyr Coding Guidelines as basic rules for coding. These rules are based on the MISRA-C standard.

Below you can find an example of a recommended commit message:

```
lib: os: add braces to 'if' statements

An 'if' (expression) construct shall be followed by a compound statement. Add braces to improve readability and maintainability.

Found as a coding guideline violation (Rule 15.6) by static coding scanning tool.

Signed-off-by: Johnny Developer <johnny.developer@company.com>
```

Step 4
If a violation is a false positive, the developer should mark it for the Codescan tool just like they would do for the Coverity tool. The developer should also add a comment to the code explaining that the violation raised by the static code analysis tool should be considered a false positive.

Step 5
If the developer has found a real violation that the community decided to ignore, the developer must submit a PR with a suppression tag and a comment explaining why the violation has been deviated. The template structure of the comment and tag in the code should be:

```
/* Explain why that part of the code doesn't follow the standard,
 * explain why it is a deliberate deviation from the standard.
 * Don't refer to the Parasoft tool here, just mention that static code
 * analysis tool raised a violation in the line below.
 */

code_line_with_a_violation /* parasoft-suppress Rule ID */
```

Below you can find an example of a recommended commit message:

```
testsuite: suppress usage of setjmp in a testcode (rule 21.4)

According to the Rule 21.4 the standard header file <setjmp.h> shall not be used. We will suppress this violation because it is in test code. Tag suppresses reporting of the violation for the line where the violation is located. This is a deliberate deviation.

Found as a coding guideline violation (Rule 21.4) by static coding scanning tool.

Signed-off-by: Johnny Developer <johnny.developer@company.com>
```

The example below demonstrates how deviations can be suppressed in the code:
/* Static code analysis tool can raise a violation that the standard
* header <setjmp.h> shall not be used.
* Since this violation is in test code, we will suppress it.
* Deliberate deviation.
*/
#include <setjmp.h> /* parasoft-suppress MISRAC2012-RULE_21_4-a MISRAC2012-RULE_21_4-b */

This variant above suppresses item MISRAC2012-RULE_21_4-a and MISRAC2012-RULE_21_4-b on the line with “setjmp” header include. You can add as many rules to suppress you want - just make sure to keep the Parasoft tag on one line and separate rules with a space. To read more about suppressing findings in the Parasoft tool, refer to the official Parasoft documentation.

Step 6
After a PR is submitted, the developer should add the Coding guidelines and MISRA-C Github labels so their PR can be easily tracked by maintainers. If you have any concerns about what your PR should look like, you can search on Github using those tags and refer to similar PRs that have already been merged.

8.3 Documentation
8.3.1 Documentation Guidelines

Note: For instructions on building the documentation, see Documentation Generation.

Zephyr Project content is written using the reStructuredText markup language (.rst file extension) with Sphinx extensions, and processed using Sphinx to create a formatted standalone website. Developers can view this content either in its raw form as .rst markup files, or (with Sphinx installed) they can build the documentation using the Makefile on Linux systems, or make.bat on Windows, to generate the HTML content. The HTML content can then be viewed using a web browser. This same .rst content is also fed into the Zephyr documentation website (with a different theme applied).

You can read details about reStructuredText and about Sphinx extensions from their respective websites. This document provides a quick reference for commonly used reST and Sphinx-defined directives and roles used to create the documentation you're reading.

Headings

While reST allows use of both and overline and matching underline to indicate a heading, we only use an underline indicator for headings.

- Document title (h1) use “#” for the underline character
- First section heading level (h2) use “*”
- Second section heading level (h3) use “=”
- Third section heading level (h4) use “-”

The heading underline must be at least as long as the title it’s under.

For example:

This is a title heading

# # # # # # # # # #

(continues on next page)
some content goes here

First section heading
********************

Content Highlighting

Some common reST inline markup samples:

- one asterisk: *text* for emphasis (italics),
- two asterisks: **text** for strong emphasis (boldface), and
- two backquotes: `text` for inline code samples.

If asterisks or backquotes appear in running text and could be confused with inline markup delimiters, you can eliminate the confusion by adding a backslash (\) before it.

Lists

For bullet lists, place an asterisk (*) or hyphen (-) at the start of a paragraph and indent continuation lines with two spaces.

The first item in a list (or sublist) must have a blank line before it and should be indented at the same level as the preceding paragraph (and not indented itself).

For numbered lists start with a 1. or a. for example, and continue with autonumbering by using a # sign. Indent continuation lines with three spaces:

* This is a bulleted list.
* It has two items, the second item and has more than one line of reST text. Additional lines are indented to the first character of the text of the bullet list.

1. This is a new numbered list. If the wasn't a blank line before it, it would be a continuation of the previous list (or paragraph).
   #. It has two items too.

   a. This is a numbered list using alphabetic list headings
   #. It has three items (and uses autonumbering for the rest of the list)
   #. Here's the third item

   #. This is an autonumbered list (default is to use numbers starting with 1).
      #. This is a second-level list under the first item (also autonumbered). Notice the indenting.
      #. And a second item in the nested list.
      #. And a second item back in the containing list. No blank line needed, but it wouldn't hurt for readability.

Definition lists (with a term and its definition) are a convenient way to document a word or phrase with an explanation. For example this reST content:

The Makefile has targets that include:
html
   Build the HTML output for the project

clean
   Remove all generated output, restoring the folders to a clean state.

Would be rendered as:

The Makefile has targets that include:

html
   Build the HTML output for the project

clean
   Remove all generated output, restoring the folders to a clean state.

**Multi-column lists**

If you have a long bullet list of items, where each item is short, you can indicate the list items should be rendered in multiple columns with a special `.. rst-class:: rst-columns` directive. The directive will apply to the next non-comment element (e.g., paragraph), or to content indented under the directive. For example, this unordered list:

```
.. rst-class:: rst-columns

* A list of
  * short items
  * that should be
  * displayed
  * horizontally
  * so it doesn't
  * use up so much
  * space on
  * the page
```

would be rendered as:

- A list of
- short items
- that should be
- displayed
- horizontally
- so it doesn't
- use up so much
- space on
- the page

A maximum of three columns will be displayed, and change based on the available width of the display window; reducing to one column on narrow (phone) screens if necessary. We've deprecated use of the `hlist` directive because it misbehaves on smaller screens.
Tables

There are a few ways to create tables, each with their limitations or quirks. Grid tables offer the most capability for defining merged rows and columns, but are hard to maintain:

```
+------------------------+------------+----------+----------+
| Header row, column 1  | Header 2  | Header 3 | Header 4 |
| (header rows optional)| | | |
+========================+============+==========+==========+
| body row 1, column 1  | column 2  | column 3 | column 4 |
+------------------------+------------+----------+----------+
| body row 2            | ...        | ...      | you can |
+------------------------+------------+----------+----------+
| body row 3 with a two column span | ... | span     | rows     |
+------------------------+------------+----------+----------+
| body row 4            | ...        | ...      | too       |
+------------------------+------------+----------+----------+
```

This example would render as:

<table>
<thead>
<tr>
<th>Header row, column 1 (header rows optional)</th>
<th>Header 2</th>
<th>Header 3</th>
<th>Header 4</th>
</tr>
</thead>
<tbody>
<tr>
<td>body row 1, column 1</td>
<td>column 2</td>
<td>column 3</td>
<td>column 4</td>
</tr>
<tr>
<td>body row 2</td>
<td>...</td>
<td>...</td>
<td>you can</td>
</tr>
<tr>
<td>body row 3 with a two column span</td>
<td>...</td>
<td>span</td>
<td>rows</td>
</tr>
<tr>
<td>body row 4</td>
<td>...</td>
<td>...</td>
<td>too</td>
</tr>
</tbody>
</table>

List tables are much easier to maintain, but don't support row or column spans:

```
.. list-table:: Table title
   :widths: 15 20 40
   :header-rows: 1

   * - Heading 1
     - Heading 2
     - Heading 3
   * - body row 1, column 1
     - body row 1, column 2
     - body row 1, column 3
   * - body row 2, column 1
     - body row 2, column 2
     - body row 2, column 3
```

This example would render as:

```
Table 8.2: Table title

<table>
<thead>
<tr>
<th>Heading 1</th>
<th>Heading 2</th>
<th>Heading 3</th>
</tr>
</thead>
<tbody>
<tr>
<td>body row 1, column 1</td>
<td>body row 1, column 2</td>
<td>body row 1, column 3</td>
</tr>
<tr>
<td>body row 2, column 1</td>
<td>body row 2, column 2</td>
<td>body row 2, column 3</td>
</tr>
</tbody>
</table>
```

The :widths: parameter lets you define relative column widths. The default is equal column widths. If you have a three-column table and you want the first column to be half as wide as the other two equal-width columns, you can specify :widths: 1 2 2. If you'd like the browser to set the column widths automatically based on the column contents, you can use :widths: auto.
File names and Commands

Sphinx extends reST by supporting additional inline markup elements (called “roles”) used to tag text with special meanings and allow style output formatting. (You can refer to the Sphinx Inline Markup documentation for the full list).

For example, there are roles for marking filenames (:file:`name`) and command names such as make (:command:`make`). You can also use the `inline code` markup (double backticks) to indicate a filename.

For references to files that are in the Zephyr GitHub tree, a special role can be used that creates a hyperlink to that file. For example a reference to the reST file used to create this document can be generated using :zephyr_file:`doc/contribute/documentation/index.rst` that will show up as doc/contribute/documentation/index.rst, a link to the “blob” file in the github repo. There's also a :zephyr_raw:`doc/guides/documentation/index.rst` role that will link to the “raw” content, doc/contribute/documentation/index.rst. (You can click on these links to see the difference.)

Internal Cross-Reference Linking

Traditional ReST links are only supported within the current file using the notation:

Refer to the `internal-linking` page

which renders as,

Refer to the internal-linking page

Note the use of a trailing underscore to indicate an outbound link. In this example, the label was added immediately before a heading, so the text that's displayed is the heading text itself. You can change the text that's displayed as the link writing this as:

Refer to the `show this text instead <internal-linking>` page

which renders as,

Refer to the show this text instead page

External Cross-Reference Linking

With Sphinx's help, we can create link-references to any tagged text within the Zephyr Project documentation.

Target locations in a document are defined with a label directive:

.. _my label name:

Heading

======

Note the leading underscore indicating an inbound link. The content immediately following this label must be a heading, and is the target for a :ref:`my label name` reference from anywhere within the Zephyr documentation. The heading text is shown when referencing this label. You can also change the text that's displayed for this link, such as:

:ref:`some other text <my label name>`

To enable easy cross-page linking within the site, each file should have a reference label before its title so it can be referenced from another file. These reference labels must be unique across the whole site, so generic names such as “samples” should be avoided. For example the top of this document's .rst file is:
Documentation Guidelines for the Zephyr Project

Other .rst documents can link to this document using the :ref:`doc_guidelines` tag and it will show up as Documentation Guidelines. This type of internal cross reference works across multiple files, and the link text is obtained from the document source so if the title changes, the link text will update as well.

You can also define links to any URL and then reference it in your document. For example, with this label definition in the document:

```
.. _Zephyr Wikipedia Page:
    https://en.wikipedia.org/wiki/Zephyr_(operating_system)
```

you can reference it with:

Read the `Zephyr Wikipedia Page`_ for more information about the project.

```any` links

Within the Zephyr project, we've defined the default role to be “any”, meaning if you just write a phrase in back-ticks, e.g., `doc_guidelines`, Sphinx will search through all domains looking for something called doc_guidelines to link to. In this case it will find the label at the top of this document, and link to doc_guidelines. This can be useful for linking to doxygen-generated links for function names and such, but will cause a warning such as:

```
WARNING: 'any' reference target not found: doc_guidelines
```

if you misspelled `doc_guidelines` as `doc_giudelines`.

Non-ASCII Characters

You can insert non-ASCII characters such as a Trademark symbol (™), by using the notation |trade|. Available replacement names are defined in an include file used during the Sphinx processing of the reST files. The names of these replacement characters are the same as used in HTML entities used to insert characters in HTML, e.g., &trade; and are defined in the file sphinx_build/substitutions.txt as listed here:

```
.. |br| raw:: html .. force a line break in HTML output (blank lines needed here)

<br />
```

```
.. |p| raw:: html .. force a blank line in HTML output (blank lines needed here)

<p></p>
```

```
.. These are replacement strings for non-ASCII characters used within the project using the same name as the html entity names (e.g., &copy;) for that character

.. |copy| unicode:: U+000A9 .. COPYRIGHT SIGN

.. |ltrim:

.. |trade| unicode:: U+02122 .. TRADEMARK SIGN
```

(continues on next page)
We've kept the substitutions list small but others can be added as needed by submitting a change to the substitutions.txt file.

**Code and Command Examples**

Use the reST code-block directive to create a highlighted block of fixed-width text, typically used for showing formatted code or console commands and output. Smart syntax highlighting is also supported (using the Pygments package). You can also directly specify the highlighting language. For example:

```
.. code-block:: c

struct z_object {
    char *name;
    uint8_t perms[CONFIG_MAX_THREAD_BYTES];
    uint8_t type;
    uint8_t flags;
    uint32_t data;
} __packed;
```

Note the blank line between the code-block directive and the first line of the code-block body, and the body content is indented three spaces (to the first non-white space of the directive name).

This would be rendered as:

```
struct z_object {
    char *name;
    uint8_t perms[CONFIG_MAX_THREAD_BYTES];
    uint8_t type;
    uint8_t flags;
    uint32_t data;
} __packed;
```

You can specify other languages for the code-block directive, including c, python, and rst, and also console, bash, or shell. If you want no syntax highlighting, use the language none, for example:

```
.. code-block:: none

This would be a block of text styled with a background and box, but with no syntax highlighting.
```

Would display as:

```
This would be a block of text styled with a background and box, but with no syntax highlighting.
```
There's a shorthand for writing code blocks too: end the introductory paragraph with a double colon (::) and indent the code block content by three spaces. On output, only one colon will be shown. The highlighting package makes a best guess at the type of content in the block and highlighting purposes.

Images

Images are included in documentation by using an image directive:

```restructuredtext
.. image:: ../../../../images/doc-gen-flow.png
   :align: center
   :alt: alt text for the image
```

or if you'd like to add an image caption, use:

```restructuredtext
.. figure:: ../../../../images/doc-gen-flow.png
   :alt: image description

   Caption for the figure
```

The file name specified is relative to the document source file, and we recommend putting images into an images folder where the document source is found. The usual image formats handled by a web browser are supported: JPEG, PNG, GIF, and SVG. Keep the image size only as large as needed, generally at least 500 px wide but no more than 1000 px, and no more than 250 KB unless a particularly large image is needed for clarity.

Tabs, spaces, and indenting

Indenting is significant in reST file content, and using spaces is preferred. Extra indenting can (unintentionally) change the way content is rendered too. For lists and directives, indent the content text to the first non-white space in the preceding line. For example:

```restructuredtext
* List item that spans multiple lines of text
  showing where to indent the continuation line.

1. And for numbered list items, the continuation line should align with the text of the line above.

   .. code-block::

      The text within a directive block should align with the first character of the directive name.
```

Keep the line length for documentation less than 80 characters to make it easier for reviewing in GitHub. Long lines because of URL references are an allowed exception.

zephyr-app-commands Directive

This is a Zephyr directive for generating consistent documentation of the shell commands needed to manage (build, flash, etc.) an application.

For example, to generate commands to build samples/hello_world for qemu_x86 use:

```restructuredtext
.. zephyr-app-commands::
   :zephyr-app: samples/hello_world
   :board: qemu_x86
   :goals: build
```
Directive options:

:tool:
which tool to use. Valid options are currently 'cmake', 'west' and 'all'. The default is 'west'.

:app:
path to the application to build.

:zephyr-app:
path to the application to build, this is an app present in the upstream zephyr repository. Mutually exclusive with :app:.

:cd-into:
if set, build instructions are given from within the :app: folder, instead of outside of it.

:generator:
which build system to generate. Valid options are currently 'ninja' and 'make'. The default is 'ninja'. This option is not case sensitive.

:host-os:
which host OS the instructions are for. Valid options are 'unix', 'win' and 'all'. The default is 'all'.

:board:
if set, the application build will target the given board.

:shield:
if set, the application build will target the given shield.

:conf:
if set, the application build will use the given configuration file. If multiple conf files are provided, enclose the space-separated list of files with quotes, e.g., “a.conf b.conf”.

:gen-args:
if set, additional arguments to the CMake invocation

:build-args:
if set, additional arguments to the build invocation

:build-dir:
if set, the application build directory will APPEND this (relative, Unix-separated) path to the standard build directory. This is mostly useful for distinguishing builds for one application within a single page.

:goals:
a whitespace-separated list of what to do with the app (in 'build', 'flash', 'debug', 'debugserver', 'run'). Commands to accomplish these tasks will be generated in the right order.

:maybe-skip-config:
if set, this indicates the reader may have already created a build directory and changed there, and will tweak the text to note that doing so again is not necessary.

:compact:
if set, the generated output is a single code block with no additional comment lines

:west-args:
if set, additional arguments to the west invocation (ignored for CMake)

For example, the .. zephyr-app-commands listed above would render like this in the generated HTML output:

```shell
# From the root of the zephyr repository
west build -b qemu_x86 samples/hello_world
```
Alternative Tabbed Content

As introduced in the *Getting Started Guide*, you can provide alternative content to the reader via a tabbed interface. When the reader clicks on a tab, the content for that tab is displayed, for example:

```
.. tabs::
    .. tab:: Apples
        Apples are green, or sometimes red.
    .. tab:: Pears
        Pears are green.
    .. tab:: Oranges
        Oranges are orange.
```

will display as:

Apples
Apples are green, or sometimes red.
Pears
Pears are green.
Oranges
Oranges are orange.

Tabs can also be grouped, so that changing the current tab in one area changes all tabs with the same name throughout the page. For example:

Linux
Linux Line 1
macOS
macOS Line 1
Windows
Windows Line 1
Linux
Linux Line 2
macOS
macOS Line 2
Windows
Windows Line 2

In this latter case, we're using .. group-tab:: instead of simply .. tab::: Under the hood, we're using the sphinx-tabs extension that's included in the Zephyr setup. Within a tab, you can have most any content other than a heading (code-blocks, ordered and unordered lists, pictures, paragraphs, and such). You can read more about sphinx-tabs from the link above.
Instruction Steps

Also introduced in the *Getting Started Guide* is a style that makes it easy to create tutorial guides with clearly identified steps. Add the .. rst-class:: numbered-step directive immediately before a second-level heading (by project convention, a heading underlined with asterisks ******, and it will be displayed as a numbered step, sequentially numbered within the document. For example:

```
.. rst-class:: numbered-step

Put your right hand in
***************
```

Put your right hand in

See the doc/develop/getting_started/index.rst source file and compare with the *Getting Started Guide* to see a full example. As implemented, only one set of numbered steps is intended per document.

For instructions on building the documentation, see *Documentation Generation*.

### 8.3.2 Documentation Generation

These instructions will walk you through generating the Zephyr Project's documentation on your local system using the same documentation sources as we use to create the online documentation found at https://docs.zephyrproject.org

**Documentation overview**

Zephyr Project content is written using the reStructuredText markup language (.rst file extension) with Sphinx extensions, and processed using Sphinx to create a formatted stand-alone website. Developers can view this content either in its raw form as .rst markup files, or you can generate the HTML content and view it with a web browser directly on your workstation. This same .rst content is also fed into the Zephyr Project's public website documentation area (with a different theme applied).

You can read details about reStructuredText, and Sphinx from their respective websites.

The project's documentation contains the following items:

- ReStructuredText source files used to generate documentation found at the [https://docs.zephyrproject.org](https://docs.zephyrproject.org) website. Most of the reStructuredText sources are found in the /doc directory, but others are stored within the code source tree near their specific component (such as /samples and /boards)
- Doxygen-generated material used to create all API-specific documents also found at [https://docs.zephyrproject.org](https://docs.zephyrproject.org)
- Script-generated material for kernel configuration options based on Kconfig files found in the source code tree

The reStructuredText files are processed by the Sphinx documentation system, and make use of the breathe extension for including the doxygen-generated API material. Additional tools are required to generate the documentation locally, as described in the following sections.

**Installing the documentation processors**

Our documentation processing has been tested to run with:

- Doxygen version 1.8.13
- Graphviz 2.43
In order to install the documentation tools, first install Zephyr as described in [Getting Started Guide](#). Then install additional tools that are only required to generate the documentation, as described below:

**Linux**

On Ubuntu Linux:

```bash
sudo apt-get install --no-install-recommends doxygen graphviz librsvg2-bin \
texlive-latex-base texlive-latex-extra latexmk texlive-fonts-recommended
```

On Fedora Linux:

```bash
sudo dnf install doxygen graphviz texlive-latex latexmk \
texlive-collection-fontsrecommended librsvg2-tools
```

On Clear Linux:

```bash
sudo swupd bundle-add texlive graphviz
```

On Arch Linux:

```bash
sudo pacman -S graphviz doxygen librsvg texlive-core texlive-bin \
texlive-latexextra texlive-fontsextra
```

**macOS**

Use `brew` and `tlmgr` to install the tools:

```bash
brew install doxygen graphviz mactex librsvg
tlmgr install latexmk
tlmgr install collection-fontsrecommended
```

**Windows**

Open a `cmd.exe` window as **Administrator** and run the following command:

```bash
choco install doxygen.install graphviz strawberryperl miktex rsvg-convert
```

---

**Fig. 8.1: Schematic of the documentation build process**

- Latexmk version 4.56
- All Python dependencies listed in the repository file `scripts/requirements-doc.txt`
**Note:** On Windows, the Sphinx executable `sphinx-build.exe` is placed in the `Scripts` folder of your Python installation path. Depending on how you have installed Python, you might need to add this folder to your `PATH` environment variable. Follow the instructions in Windows Python Path to add those if needed.

**Documentation presentation theme**

Sphinx supports easy customization of the generated documentation appearance through the use of themes. Replace the theme files and do another `make html` and the output layout and style is changed. The `read-the-docs` theme is installed as part of the Get Zephyr and install Python dependencies step you took in the getting started guide.

**Running the documentation processors**

The `/doc` directory in your cloned copy of the Zephyr project git repo has all the `.rst` source files, extra tools, and Makefile for generating a local copy of the Zephyr project's technical documentation. Assuming the local Zephyr project copy is in a folder `zephyr` in your home folder, here are the commands to generate the `html` content locally:

```bash
# On Linux/macOS
cd ~/zephyr/doc
# On Windows
cd %userprofile%\zephyr\doc

# Use cmake to configure a Ninja-based build system:
cmake -GNinja -B_build .

# Enter the build directory
cd _build

# To generate HTML output, run ninja on the generated build system:
ninja html
# If you modify or add .rst files, run ninja again:
ninja html

# To generate PDF output, run ninja on the generated build system:
ninja pdf
```

**Warning:** The documentation build system creates copies in the build directory of every `.rst` file used to generate the documentation, along with dependencies referenced by those `.rst` files. This means that Sphinx warnings and errors refer to the copies, and not the version-controlled original files in Zephyr. Be careful to make sure you don’t accidentally edit the copy of the file in an error message, as these changes will not be saved.

Depending on your development system, it will take up to 15 minutes to collect and generate the HTML content. When done, you can view the HTML output with your browser started at `doc/_build/html/index.html` and if generated, the PDF file is available at `doc/_build/pdf/zephyr.pdf`.

If you want to build the documentation from scratch just delete the contents of the build folder and run `cmake` and then `ninja` again.
Note: If you add or remove a file from the documentation, you need to re-run CMake.

On Unix platforms a convenience `doc/Makefile` can be used to build the documentation directly from there:

```bash
 cd ~/zephyr/doc

# To generate HTML output
make html

# To generate PDF output
make pdf
```

Filtering expected warnings

There are some known issues with Sphinx/Breathe that generate Sphinx warnings even though the input is valid C code. While these issues are being considered for fixing we have created a Sphinx extension that allows to filter them out based on a set of regular expressions. The extension is named `zephyr_warnings_filter` and it is located at `doc/_extensions/zephyr/warnings_filter.py`. The warnings to be filtered out can be added to the `doc/known-warnings.txt` file.

The most common warning reported by Sphinx/Breathe is related to duplicate C declarations. This warning may be caused by different Sphinx/Breathe issues:

- Multiple declarations of the same object are not supported
- Different objects (e.g. a struct and a function) can not share the same name
- Nested elements (e.g. in a struct or union) can not share the same name

Developer-mode Document Building

When making and testing major changes to the documentation, we provide an option to temporarily stub-out the auto-generated Devicetree bindings documentation so the doc build process runs faster.

To enable this mode, set the following option when invoking cmake:

```bash
-DDT_TURBO_MODE=1
```

or invoke make with the following target:

```bash
 cd ~/zephyr

# To generate HTML output without detailed Kconfig
make html-fast
```

Linking external Doxygen projects against Zephyr

External projects that build upon Zephyr functionality and wish to refer to Zephyr documentation in Doxygen (through the use of @ref), can utilize the tag file exported at `zephyr.tag`

Once downloaded, the tag file can be used in a custom `doxyfile.in` as follows:

```bash
TAGFILES = "'/path/to/zephyr.tag=https://docs.zephyrproject.org/latest/doxygen/html/"
```

For additional information refer to Doxygen External Documentation.
8.4 Contributing External Components

In some cases it is desirable to leverage existing, external source code in order to avoid re-implementing basic functionality or features that are readily available in other open source projects.

This section describes the circumstances under which external source code can be imported into Zephyr, and the process that governs the inclusion.

There are three main factors that will be considered during the inclusion process in order to determine whether it will be accepted. These will be described in the following sections.

8.4.1 Software License

**Note:** External source code licensed under the Apache-2.0 license is not subject to this section.

Integrating code into the Zephyr Project from other projects that use a license other than the Apache 2.0 license needs to be fully understood in context and approved by the Zephyr governing board, as described in the Zephyr project charter. The board will automatically reject licenses that have not been approved by the Open Source Initiative (OSI). See the Submission and review process section for more details.

By carefully reviewing potential contributions and also enforcing a Developer Certification of Origin (DCO) for contributed code, we ensure that the Zephyr community can develop products with the Zephyr Project without concerns over patent or copyright issues.

8.4.2 Merit

Just like with any other regular contribution, one that contains external code needs to be evaluated for merit. However, in the particular case of code that comes from an existing project, there are additional questions that must be answered in order to accept the contribution. More specifically, the following will be considered by the Technical Steering Committee and evaluated carefully before the external source code is accepted into the project:

- Is this the most optimal way to introduce the functionality to the project? Both the cost of implementing this internally and the one incurred in maintaining an externally developed codebase need to be evaluated.
- Is the external project being actively maintained? This is particularly important for source code that deals with security or cryptography.
- Have alternatives to the particular implementation proposed been considered? Are there other open source project that implement the same functionality?

8.4.3 Mode of integration

There are two ways of integrating external source code into the Zephyr Project, and careful consideration must be taken to choose the appropriate one for each particular case.

Integration in the main tree

The first way to integrate external source code into the project is to simply import the source code files into the main zephyr repository. This automatically implies that the imported source code becomes part of the “mainline” codebase, which in turn requires that:

- The code is formatted according to the Zephyr Coding Style
• The code adheres to the project’s *Coding Guidelines*
• The code is subject to the same checks and verification requirements as the rest of the code in the
  main tree, including static analysis
• All files contain an SPDX tag if not already present
• An entry is added to the licensing page `<zephyr_licensing>`

This mode of integration can be applicable to both small and large external codebases, but it is typically used more commonly with the former.

**Integration as a module**

The second way of integrating external source code into the project is to import the whole or parts of the third-party open source project into a separate repository, and then include it under the form of a *module*.

With this approach the code is considered as being developed externally, and thus it is not automatically subject to the requirements of the previous section.

### 8.4.4 Ongoing maintenance

Regardless of the mode of integration, external source code that is integrated in Zephyr requires regular ongoing maintenance. The submitter of the proposal to integrate external source code must therefore commit to maintain the integration of such code for the foreseeable future. This may require adding an entry in the *MAINTAINERS.yml* as part of the process.

### 8.4.5 Submission and review process

Before external source code can be included in the project, it must be reviewed and accepted by the Technical Steering Committee (TSC) and, in some cases, by the Zephyr governing board.

A request for external source code integration must be made by creating a new issue in the Zephyr project issue tracking system on GitHub with details about the source code and how it integrates into the project.

Follow the steps below to begin the submission process:

1. Make sure to read through the *Contributing External Components* section in detail, so that you are informed of the criteria used by the TSC and board in order to approve or reject a request
2. Use the *New External Source Code Issue* to open an issue
3. Fill out all required sections, making sure you provide enough detail for the TSC to assess the merit of the request. Optionally you can also create a Pull Request that demonstrates the integration of the external source code and link it to from the issue
4. Wait for feedback from the TSC, respond to any additional questions added as GitHub issue comments

If, after consideration by the TSC, the conclusion is that integrating external source code is the best solution, and the external source code is licensed under the Apache-2.0 license, the submission process is complete and the external source code can be integrated.

If, however, the external source code uses a license other than Apache-2.0, then these additional steps must be followed:

1. The TSC chair will forward the link to the GitHub issue created during the early submission process to the Zephyr governing board for further review
2. The Zephyr governing board has two weeks to review and ask questions:
   • If there are no objections, the matter is closed. Approval can be accelerated by unanimous approval of the board before the two weeks are up
• If a governing board member raises an objection that cannot be resolved via email, the board will meet to discuss whether to override the TSC approval or identify other approaches that can resolve the objections.

3. On approval of the Zephyr TSC and governing board the submission process is complete.

The flowchart below shows an overview of the process:

Fig. 8.2: Submission process

8.5 Binary Blobs

In the context of an operating system that supports multiple architectures and many different IC families, some functionality may be unavailable without the help of executable code distributed in binary form. Binary blobs (or blobs for short) are files containing proprietary machine code or data in a binary format, e.g. without corresponding source code released under an OSI approved license.

Zephyr supports downloading and using third-party binary blobs via its built-in mechanisms, with some important caveats, described in the following sections. It is important to note that all the information in this section applies only to upstream (vanilla) Zephyr.

There are no limitations whatsoever (except perhaps license compatibility) in the support for binary blobs in forks or third-party distributions of Zephyr. In fact, Zephyr's build system supports arbitrary use cases related to blobs. This includes linking against libraries, flashing images to targets, etc. Users are therefore free to create Zephyr-based downstream software which uses binary blobs if they cannot meet the requirements described in this page.

8.5.1 Software license

Most binary blobs are distributed under proprietary licenses which vary significantly in nature and conditions. It is up to the vendor to specify the license as part of the blob submission process. Blob vendors may impose a click-through or other EULA-like workflow when users fetch and install blobs.
8.5.2 Hosting

Blobs must be hosted on the Internet and managed by third-party infrastructure. Two potential examples are Git repositories and web servers managed by individual hardware vendors.

The Zephyr Project does not host binary blobs in its Git repositories or anywhere else.

8.5.3 Fetching blobs

Blobs are fetched from official third-party sources by the `west blobs` command.

The blobs themselves must be specified in the `module.yml` files included in separate Zephyr module repositories maintained by their respective vendors. This means that in order to include a reference to a binary blob to the upstream Zephyr distribution, a module repository must exist first or be created as part of the submission process.

Each blob which may be fetched must be individually identified in the corresponding `module.yml` file. A specification for a blob must contain:

- An abstract description of the blob itself
- Version information
- A reference to vendor-provided documentation
- The blob’s type, which must be one of the allowed types
- A checksum for the blob, which `west blobs` checks after downloading. This is required for reproducibility and to allow bisecting issues as blobs change using Git and west
- License text applicable to the blob or a reference to such text, in SPDX format

See the corresponding section for a more formal definition of the fields.

The `west blobs` command can be used to list metadata of available blobs and to fetch blobs from user-selected modules.

The `west blobs` command only fetches and stores the binary blobs themselves. Any accompanying code, including interface header files for the blobs, must be present in the corresponding module repository.

8.5.4 Tainting

Inclusion of binary blobs will taint the Zephyr build. The definition of tainting originates in the Linux kernel and, in the context of Zephyr, a tainted image will be one that includes binary blobs in it.

Tainting will be communicated to the user in the following manners:

- One or more Kconfig options `TAINT_BLOBS_*` will be set to y
- The Zephyr build system, during its configuration phase, will issue a warning. It will be possible to disable the warning using Kconfig
- The `west spdx` command will include the tainted status in its output
- The kernel’s default fatal error handler will also explicitly print out the kernel’s tainted status

8.5.5 Allowed types

The following binary blob types are acceptable in Zephyr:

- Precompiled libraries: Hardware enablement libraries, distributed in precompiled binary form, typically for SoC peripherals. An example could be an enablement library for a wireless peripheral
• Firmware images: An image containing the executable code for a secondary processor or CPU. This can be full or partial (typically delta or patch data) and is generally copied into RAM or flash memory by the main CPU. An example could be the firmware for the core running a Bluetooth LE Controller.

• Miscellaneous binary data files. An example could be pre-trained neural network model data

Hardware agnostic features provided via a proprietary library are not acceptable. For example, a proprietary and hardware agnostic TCP/IP stack distributed as a static archive would be rejected.

Note that just because a blob has an acceptable type does not imply that it will be unconditionally accepted by the project; any blob may be rejected for other reasons on a case by case basis (see library-specific requirements below). In case of disagreement, the TSC is the arbiter of whether a particular blob fits in one of the above types.

8.5.6 Precompiled library-specific requirements

This section contains additional requirements specific to precompiled library blobs.

Any person who wishes to submit a precompiled library must represent that it meets these requirements. The project may remove a blob from the upstream distribution if it is discovered that the blob fails to meet these requirements later on.

Interface header files

The precompiled library must be accompanied by one or more header files, distributed under a non-copyleft OSI approved license, that define the interface to the library.

Allowed dependencies

This section defines requirements related to external symbols that a library blob requires the build system to provide.

• The blob must not depend on Zephyr APIs directly. In other words, it must have been possible to build the binary without any Zephyr source code present at all. This is required for loose coupling and maintainability, since Zephyr APIs may change and such blobs cannot be modified by all project maintainers.

• Instead, if the code in the precompiled library requires functionality provided by Zephyr (or an RTOS in general), an implementation of an OS abstraction layer (aka porting layer) can be provided alongside the library. The implementation of this OS abstraction layer must be in source code form, released under an OSI approved license and documented using Doxygen.

Toolchain requirements

Precompiled library blobs must be in a data format which is compatible with and can be linked by a toolchain supported by the Zephyr Project. This is required for maintainability and usability. Use of such libraries may require special compiler and/or linker flags, however. For example, a porting layer may require special flags, or a static archive may require use of specific linker flags.

Limited scope

Allowing arbitrary library blobs carries a risk of degrading the degree to which the upstream Zephyr software distribution is open source. As an extreme example, a target with a zephyr kernel clock driver that is just a porting layer around a library blob would not be bootable with open source software.
To mitigate this risk, the scope of upstream library blobs is limited. The project maintainers define an open source test suite that an upstream target must be able to pass using only open source software included in the mainline distribution and its modules. The open source test suite currently consists of:

- samples/philosophers
- tests/kernel

The scope of this test suite may grow over time. The goal is to specify tests for a minimal feature set which must be supported via open source software for any target with upstream Zephyr support.

At the discretion of the release team, the project may remove support for a hardware target if it cannot pass this test suite.

### 8.5.7 Support and maintenance

The Zephyr Project is not expected to be responsible for the maintenance and support of contributed binary blobs. As a consequence, at the discretion of the Zephyr Project release team, and on a case-by-case basis:

- GitHub issues reported on the zephyr repository tracker that require use of blobs to reproduce may not be treated as bugs
- Such issues may be closed as out of scope of the Zephyr project

This does not imply that issues which require blobs to reproduce will be closed without investigation. For example, the issue may be exposing a bug in a Zephyr code path that is difficult or impossible to trigger without a blob. Project maintainers may accept and attempt to resolve such issues.

However, some flexibility is required because project maintainers may not be able to determine if a given issue is due to a bug in Zephyr or the blob itself, may be unable to reproduce the bug due to lack of hardware, etc.

Blobs must have designated maintainers that must be responsive to issue reports from users and provide updates to the blobs to address issues. At the discretion of the Zephyr Project release team, module revisions referencing blobs may be removed from `zephyr/west.yml` at any time due to lack of responsiveness or support from their maintainers. This is required to maintain project control over bit-rot, security issues, etc.

The submitter of the proposal to integrate a binary blob must commit to maintain the integration of such blob for the foreseeable future.

### 8.5.8 Submission and review process

For references to binary blobs to be included in the project, they must be reviewed and accepted by the Technical Steering Committee (TSC). This process is only required for new binary blobs, updates to binary blobs follow the `module update procedure`.

A request for integration with binary blobs must be made by creating a new issue in the Zephyr project issue tracking system on GitHub with details about the blobs and the functionality they provide to the project.

Follow the steps below to begin the submission process:

1. Make sure to read through the `Binary Blobs` section in detail, so that you are informed of the criteria used by the TSC in order to approve or reject a request
2. Use the New Binary Blobs Issue to open an issue
3. Fill out all required sections, making sure you provide enough detail for the TSC to assess the merit of the request. Additionally you must also create a Pull Request that demonstrates the integration of the binary blobs and then link to it from the issue
4. Wait for feedback from the TSC, respond to any additional questions added as GitHub issue comments.

If, after consideration by the TSC, the submission of the binary blob(s) is approved, the submission process is complete and the binary blob(s) can be integrated.
Chapter 9

Project and Governance

9.1 TSC Project Roles

9.1.1 Main Roles

TSC projects generally will involve *Maintainers*, *Collaborators*, and *Contributors*:

**Maintainer**: lead Collaborators on an area identified by the TSC (e.g. Architecture, code subsystems, etc.). Maintainers shall also serve as the area’s representative on the TSC as needed. Maintainers may become voting members of the TSC under the guidelines stated in the project Charter.

**Collaborator**: A highly involved Contributor in one or more areas. May become a Maintainer with approval of existing TSC voting members.

**Contributor**: anyone in the community that contributes code or documentation to the project. Contributors may become Collaborators by approval of the existing Collaborators and Maintainers of the particular code base areas or subsystems.

**Contributor**

A *Contributor* is a developer who wishes to contribute to the project, at any level. Contributors are granted the following rights and responsibilities:

- Right to contribute code, documentation, translations, artwork, etc.
- Right to report defects (bugs) and suggestions for enhancement.
- Right to participate in the process of reviewing contributions by others.
- Right to initiate and participate in discussions in any communication methods.
- Right to approach any member of the community with matters they believe to be important.
- Right to participate in the feature development process.
- Responsibility to abide by decisions, once made. They are welcome to provide new, relevant information to reopen decisions.
- Responsibility for issues and bugs introduced by one's own contributions.
- Responsibility to respect the rules of the community.
- Responsibility to provide constructive advice whenever participating in discussions and in the review of contributions.
Contributors are initially only given Read access to the Zephyr GitHub repository. Specifically, at the Read access level, Contributors are not allowed to assign reviewers to their own pull requests. An automated process will assign reviewers. You may also share the pull request on the Zephyr devel mailing list or on the Zephyr Discord Server.

Contributors who show dedication and skill are granted the Triage permission level to the Zephyr GitHub repository.

You may nominate yourself, or another GitHub user, for promotion to the Triage permission level by creating a GitHub issue, using the nomination template.

Contributors granted the Triage permission level are permitted to add reviewers to a pull request and can be added as a reviewer by other GitHub users. Contributor votes on pull requests are not counted with respect to accepting and merging a pull request. However, Contributors comments and requested changes should still be considered by the pull request author.

**Collaborator**

A **Collaborator** is a Contributor who is also responsible for the maintenance of Zephyr source code. Their opinions weigh more when decisions are made, in a fully meritocratic fashion.

Collaborators have the following rights and responsibilities, in addition to those listed for Contributors:

- Right to set goals for the short and medium terms for the project being maintained, alongside the Maintainer.
- Responsibility to participate in the feature development process.
- Responsibility to review relevant code changes within reasonable time.
- Responsibility to ensure the quality of the code to expected levels.
- Responsibility to participate in community discussions.
- Responsibility to mentor new contributors when appropriate
- Responsibility to participate in the quality verification and release process, when those happen.

Contributors are promoted to the Collaborator role by adding the GitHub user name to one or more collaborators sections of the **MAINTAINERS File** in the Zephyr repository.

Collaborator votes on pull requests can block or approve the pull request.

**Maintainer**

A **Maintainer** is a Collaborator who is also responsible for knowing, directing and anticipating the needs of a given zephyr source code area.

Maintainers have the following rights and responsibilities, in addition to those listed for Contributors and Collaborators:

- Right to set the overall architecture of the relevant subsystems or areas of involvement.
- Right to make decisions in the relevant subsystems or areas of involvement, in conjunction with the collaborators.
- Responsibility to convey the direction of the relevant subsystem or areas to the TSC
- Responsibility to ensure all contributions of the project have been reviewed within reasonable time.
- Responsibility to enforce the code of conduct.

Contributors or Collaborators are promoted to the Maintainer role by adding the GitHub user name to one or more maintainers sections of the **MAINTAINERS File** in the Zephyr repository.

Maintainer votes on pull requests can block or approve the pull request.
9.1.2 Role Retirement

- Individuals elected to the following Project roles, including, Maintainer, Release Engineering Team member, Release Manager, but are no longer engaged in the project as described by the rights and responsibilities of that role, may be requested by the TSC to retire from the role they are elected.
- Such a request needs to be raised as a motion in the TSC and be approved by the TSC voting members. By approval of the TSC the individual is considered to be retired from the role they have been elected.
- The above applies to elected TSC Project roles that may be defined in addition.

9.1.3 Teams and Supporting Activities

Assignee

An Assignee is one of the maintainers of a subsystem or code being changed. Assignees are set either automatically based on the code being changed or set by the other Maintainers, the Release Engineering team can set an assignee when the latter is not possible.

- Right to dismiss stale reviews and seek reviews from additional maintainers, developers and contributors
- Right to block pull requests from being merged
- Responsibility to re-assign a pull request if they are the original submitter of the code
- Responsibility to drive the pull request to a mergeable state
- Solicit approvals from maintainers of the subsystems affected
- Responsibility to drive the escalation process

Release Engineering Team

A team of active Maintainers involved in multiple areas.

- The members of the Release Engineering team are expected to fill the Release Manager role based on a defined cadence and selection process.
- The cadence and selection process are defined by the Release Engineering team and are approved by the TSC.
- The team reports directly into the TSC.

Release Engineering team has the following rights and responsibilities:

- Right to merge code changes to the zephyr tree following the project rules.
- Right to revert any changes that have broken the code base.
- Right to close any stale changes after <N> months of no activity.
- Responsibility to take directions from the TSC and follow them.
- Responsibility to coordinate code merges with maintainers.
- Responsibility to merge all contributions regardless of their origin and area if they have been approved by the respective maintainers and follow the merge criteria of a change.
- Responsibility to keep the Zephyr code base in a working and passing state (as per CI)

Joining the Release Engineering team
• Maintainers highly involved in the project may be nominated by a TSC voting member to join the
Release Engineering team. Nominees may become members of the team by approval of the existing
TSC voting members.

• To ensure a functional Release Engineering team the TSC shall periodically review the team’s fol-
lowed processes, the appropriate size, and the membership composition (ensure, for example, that
team members are geographically distributed across multiple locations and time-zones).

**Release Manager**

A *Maintainer* responsible for driving a specific release to completion following the milestones and the
roadmap of the project for this specific release.

• TSC has to approve a release manager.

A Release Manager is a member of the Release Engineering team and has the rights and responsibilities
of that team in addition to the following:

• Right to manage and coordinate all code merges after the code freeze milestone (M3, see program
management overview.)

• Responsibility to drive and coordinate the triaging process for the release

• Responsibility to create the release notes of the release

• Responsibility to notify all stakeholders of the project, including the community at large about the
status of the release in a timely manner.

• Responsibility to coordinate with QA and validation and verify changes either directly or through
QA before major changes and major milestones.

**Roles / Permissions**

<table>
<thead>
<tr>
<th>Role</th>
<th>Admin</th>
<th>Merge Rights</th>
<th>Member</th>
<th>Owner</th>
<th>Collaborator</th>
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</thead>
<tbody>
<tr>
<td>Main Roles</td>
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<tr>
<td>Contributor</td>
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</table>

**9.1.4 MAINTAINERS File**

Generic guidelines for deciding and filling in the Maintainers’ list

• The MAINTAINERS.yml file shall replace the CODEOWNERS file and will be used for both setting
assignees and reviewers.

• We should keep the granularity of code maintainership at a manageable level

• We should be looking for maintainers for areas of code that are orphaned (i.e. without an explicit
maintainer)
  
  – Un-maintained areas should be indicated clearly in the MAINTAINERS file

• All submitted pull requests should have an assignee

• We Introduce an area/subsystem hierarchy to address the above point
- Parent-area maintainer should be acting as default substitute/fallback assignee for unmaintained sub-areas
- Area maintainer gets precedence over parent-area maintainer

- Pull requests may be re-assigned if this is needed or more appropriate
  - Re-assigned by original assignee (see “Assignee” slide)

- In general, updates to the MAINTAINERS file should be in a standalone commit alongside other changes introducing new files and directories to the tree.

- Major changes to the file, including the addition of new areas with new maintainers should come in as standalone pull requests and require TSC review.

- If additional review by the TSC is required, the maintainers of the file should send the requested changes to the TSC and give members of the TSC two (2) days to object to any of the changes to maintainership of areas or the addition of new maintainers or areas.

- Path, collaborator and name changes do not require a review by the TSC.

- Addition of new areas without a maintainer do not require review by the TSC.

- The MAINTAINERS file itself shall have a maintainer

- Architectures, core components, sub-systems, samples, tests
  - Each area shall have an explicit maintainer

- Boards (incl relevant samples, tests), SoCs (incl DTS) * May have a maintainer, shall have a higher-level platform maintainer

- Drivers
  - Shall have a driver-area (and API) maintainer
  - Could have individual driver implementation maintainers but preferably collaborator/contributors
  - In the above case, platform-specific PRs may be re-assigned to respective collaborator/contributor of driver implementation

9.1.5 Release Activity

Merge Criteria

- All continuous integration checks have passed
  - Codeowners
  - Device Tree
  - Documentation
  - Gitlint
  - Identity/Emails
  - Kconfig
  - License
  - Checkpatch (Coding Style)
  - Pylint
  - Integration Tests (Via twister) on emulation/simulation platforms
- Simulated Bluetooth Tests

- Planned
  - Footprint
  - Code coverage
  - Coding Guidelines
  - Static Analysis (Coverity)
  - Documentation coverage (APIs)

- PR template with checklist

- Minimal of 2 approvals
  - A collaborator from the same subsystem.
  - Alternately another maintainer of another subsystem
  - Approval by the assignee

- A minimum review period of 2 days, 4 hours for trivial changes (see *Give reviewers time to review before code merge*). Hotfixes can be merged at any time after CI passes.

- All required checks are passing

**Escalation Process**

- Contributors may object to change requests or decisions made by Maintainers.

- Process
  - Resolve in the PR among assignee, maintainers and reviewer
    * Assignee to act as moderator if applicable
- Optionally resolve in the dev review meeting with more Maintainers and project stakeholders
  * The involved parties and the Assignee to be present when the (escalated) issue is discussed
- TSC: Assignees can escalate to the TSC voting members and get a binding resolution in the TSC.
- Assignee to ensure the resolution of the escalation is reflected in the PR review.

9.2 Release Process

The Zephyr project releases on a time-based cycle, rather than a feature-driven one. Zephyr releases represent an aggregation of the work of many contributors, companies, and individuals from the community.

A time-based release process enables the Zephyr project to provide users with a balance of the latest technologies and features and excellent overall quality. A roughly 4-month release cycle allows the project to coordinate development of the features that have actually been implemented, allowing the project to maintain the quality of the overall release without delays because of one or two features that are not ready yet.

The Zephyr release model was loosely based on the Linux kernel model:

- Release tagging procedure:
  - linear mode on main branch,
  - release branches for maintenance after release tagging.
- Each release period will consist of a development phase followed by a stabilization phase. Release candidates will be tagged during the stabilization phase. During the stabilization phase, only stabilization changes such as bug fixes and documentation will be merged unless granted a special exemption by the Technical Steering Committee.
  - Development phase: all changes are accepted (subject to approval from the respective maintainers).
  - Stabilisation phase: the release manager creates a vN-rc1 tag and the tree enters the stabilization phase
  - CI sees the tag, builds and runs tests; Test teams analyse the report from the build and test run and give an ACK/NAK to the build
  - The release owner, with test teams and any other needed input, determines if the release candidate is a go for release
  - If it is a go for a release, the release owner lays a tag release vN at the same point

![Fig. 9.1: Release Cycle](image)
9.2.1 Development Phase

A relatively straightforward discipline is followed with regard to the merging of patches for each release. At the beginning of each development cycle, the main branch is said to be open for development. At that time, code which is deemed to be sufficiently stable (and which is accepted by the maintainers and the wide community) is merged into the mainline tree. The bulk of changes for a new development cycle (and all of the major changes) will be merged during this time.

The development phase lasts for approximately two months. At the end of this time, the release owner will declare that the development phase is over and releases the first of the release candidates. For the codebase release which is destined to be 3.1.0, for example, the release which happens at the end of the development phase will be called 3.1.0-rc1. The -rc1 release is the signal that the time to merge new features has passed, and that the time to stabilize the next release of the code base has begun.

9.2.2 Stabilization Phase

Over the next weeks, only patches which fix problems should be submitted to the mainline. On occasion, a more significant change will be allowed, but such occasions are rare and require a TSC approval (Change Control Board). As a general rule, if you miss submitting your code during the development phase for a given feature, the best thing to do is to wait for the next development cycle. (An occasional exception is made for drivers for previously unsupported hardware; if they do not touch any other in-tree code, they cannot cause regressions and should be safe to add at any time).

As fixes make their way into the mainline, the patch rate will slow over time. The mainline release owner releases new -rc drops once or twice a week; a normal series will get up to somewhere between -rc4 and -rc6 before the code base is considered to be sufficiently stable and the release criteria have been achieved at which point the final 3.1.0 release is made.

At that point, the whole process starts over again.

9.2.3 Release Quality Criteria

The current backlog of prioritized bugs shall be used as a quality metric to gate the final release. The following counts shall be used:

<table>
<thead>
<tr>
<th>Table 9.2: Bug Count Release Thresholds</th>
</tr>
</thead>
<tbody>
<tr>
<td>High</td>
</tr>
<tr>
<td>0</td>
</tr>
</tbody>
</table>

Note: The “low” bug count target of <50 will be a phased approach starting with 150 for release 2.4.0, 100 for release 2.5.0, and 50 for release 2.6.0
### 9.2.4 Release Milestones

#### Table 9.3: Release Milestones

<table>
<thead>
<tr>
<th>Timeline</th>
<th>Checkpoint</th>
<th>Description</th>
<th>Owner</th>
</tr>
</thead>
<tbody>
<tr>
<td>T-5M</td>
<td>Planning</td>
<td>Finalize dates for release, Assign release owner and agree on project wide goals for this release.</td>
<td>TSC</td>
</tr>
<tr>
<td>T-7W</td>
<td>Review target milestones</td>
<td>Finalize target milestones for features in flight.</td>
<td>Release Engineering</td>
</tr>
<tr>
<td>T-4W</td>
<td>Release Announcement</td>
<td>Release owner announces feature freeze and timeline for release.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-3W</td>
<td>Feature Freeze (RC1)</td>
<td>No new features, ONLY stabilization and cosmetic changes, bug and doc fixes are allowed.</td>
<td>Release Engineering</td>
</tr>
<tr>
<td>T-2W</td>
<td>2nd Release Candidate</td>
<td>No new features, ONLY stabilization and cosmetic changes, bug and doc fixes are allowed.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-1W</td>
<td>Hard Freeze (RC3)</td>
<td>Only blocker bug fixes, documentation and changes to release notes are allowed. Release notes need to be complete by this checkpoint. Release Criteria is met.</td>
<td>Release Manager</td>
</tr>
<tr>
<td>T-0W</td>
<td>Release</td>
<td></td>
<td>Release Manager</td>
</tr>
</tbody>
</table>

### 9.2.5 Releases

The following syntax should be used for releases and tags in Git:

- Release `[Major].[Minor].[Patch Level]`
- Release Candidate `[Major].[Minor].[Patch Level]-rc[RC Number]`
- Tagging:
  - `v[Major].[Minor].[Patch Level]-rc[RC Number]`
  - `v[Major].[Minor].[Patch Level]`
  - `v[Major].[Minor].99` - A tag applied to main branch to signify that work on `v[Major].[Minor+1]` has started. For example, `v1.7.99` will be tagged at the start of `v1.8` process. The tag corresponds to `VERSION_MAJOR/VERSION_MINOR/PATCHLEVEL` macros as defined for a work-in-progress main branch version. Presence of this tag allows generation of sensible output for “git describe” on main branch, as typically used for automated builds and CI tools.

### Long Term Support (LTS)

Long-term support releases are designed to be supported and maintained for an extended period and is the recommended release for products and the auditable branch used for certification.

An LTS release is defined as:

- **Product focused**
- **Extended Stabilisation period**: Allow for more testing and bug fixing
- **Stable APIs**
- **Quality Driven Process**
- **Long Term**: Maintained for an extended period of time (at least 2.5 years) overlapping previous LTS release for at least half a year.
Product Focused  Zephyr LTS is the recommended release for product makers with an extended support and maintenance which includes general stability and bug fixes, security fixes.

An LTS includes both mature and new features. API and feature maturity is documented and tracked. The footprint and scope of mature and stable APIs expands as we move from one LTS to the next giving users access to bleeding edge features and new hardware while keeping a stable foundation that evolves over time.

Extended Stabilisation Period  Zephyr LTS development cycle differs from regular releases and has an extended stabilization period. Feature freeze of regular releases happens 3-4 weeks before the scheduled release date. The stabilization period for LTS is extended by 3 weeks with the feature freeze occurring 6-7 weeks before the anticipated release date. The time between code freeze and release date is extended in this case.

Stable APIs  Zephyr LTS provides a stable and long-lived foundation for developing products. To guarantee stability of the APIs and the implementation of such APIs it is required that any release software that makes the core of the OS went through the Zephyr API lifecycle and stabilized over at least 2 releases. This guarantees that we release many of the highlighted and core features with mature and well-established implementations with stable APIs that are supported during the lifetime of the release LTS.

- API Freeze (LTS - 2)
  - All stable APIs need to be frozen 2 releases before an LTS. APIs can be extended with additional features, but the core implementation is not modified. This is valid for the following subsystems for example:
    * Device Drivers (i2c.h, spi.h)...
    * Kernel (k_):  
    * OS services (logging,debugging, ..)
    * DTS: API and bindings stability
    * Kconfig
  - New APIs for experimental features can be added at any time as long as they are standalone and documented as experimental or unstable features/APIs.

- Feature Freeze (LTS - 1) - No new features or overhaul/restructuring of code covering major LTS features.
- Kernel + Base OS
- Additional advertised LTS features
- Auxiliary features on top of and/or extending the base OS and advertised LTS features can be added at any time and should be marked as experimental if applicable

Quality Driven Process The Zephyr project follows industry standards and processes with the goal of providing a quality oriented releases. This is achieved by providing the following products to track progress, integrity and quality of the software components provided by the project:

- Compliance with published coding guidelines, style guides and naming conventions and documentation of deviations.
- Regular static analysis on the complete tree using available commercial and open-source tools and documentation of deviations and false positives.
- Documented components and APIs
- Requirements Catalog
- Verification Plans
- Verification Reports
- Coverage Reports
- Requirements Traceability Matrix (RTM)
- SPDX License Reports

Each release is created with the above products to document the quality and the state of the software when it was released.

Long Term Support and Maintenance A Zephyr LTS release is published every 2 years and is branched and maintained independently from the main tree for at least 2.5 years after it was released. Support and maintenance for an LTS release stops at least half a year after the following LTS release is published.

Changes and fixes flow in both directions. However, changes from main branch to an LTS branch will be limited to fixes that apply to both branches and for existing features only.

All fixes for an LTS branch that apply to the mainline tree shall be submitted to mainline tree as well.

Auditable Code Base

An auditable code base is to be established from a defined subset of Zephyr OS features and will be limited in scope. The LTS, development tree, and the auditable code bases shall be kept in sync after the audit branch is created, but with a more rigorous process in place for adding new features into the audit branch used for certification.

This process will be applied before new features move into the auditable code base.
The initial and subsequent certification targets will be decided by the Zephyr project governing board. Processes to achieve selected certification will be determined by the Security and Safety Working Groups and coordinated with the TSC.

### 9.2.6 Release Procedure

This section documents the Release manager responsibilities so that it serves as a knowledge repository for Release managers.

#### Release Checklist

Each release has a GitHub issue associated with it that contains the full checklist. After a release is complete, a checklist for the next release is created.

#### Tagging

The final release and each release candidate shall be tagged using the following steps:

**Note:** Tagging needs to be done via explicit git commands and not via GitHub's release interface. The GitHub release interface does not generate annotated tags (it generates 'lightweight' tags regardless of release or pre-release). You should also upload your gpg public key to your GitHub account, since the instructions below involve creating signed tags. However, if you do not have a gpg public key you can opt to remove the -s option from the commands below.

**Release Candidate**

**Note:** This section uses tagging 1.11.0-rc1 as an example, replace with the appropriate release candidate version.

1. Update the version variables in the VERSION file located in the root of the Git repository to match the version for this release candidate. The EXTRAVERSION variable is used to identify the rc[RC Number] value for this candidate:

   ```
   EXTRAVERSION = rc1
   ```

2. Post a PR with the updated VERSION file using release: Zephyr 1.11.0-rc1 as the commit subject. Merge the PR after successful CI.

3. Tag and push the version, using an annotated tag:

   ```
   $ git pull
   $ git tag -s -m "Zephyr 1.11.0-rc1" v1.11.0-rc1
   $ git push git@github.com:zephyrproject-rtos/zephyr.git v1.11.0-rc1
   ```

4. Send an email to the mailing lists (announce and devel) with a link to the release

**Final Release**

**Note:** This section uses tagging 1.11.0 as an example, replace with the appropriate final release version.

When all final release criteria has been met and the final release notes have been approved and merged into the repository, the final release version will be set and repository tagged using the following procedure:
1. Update the version variables in the VERSION file located in the root of the Git repository. Set EXTRAVERSION variable to an empty string to indicate final release:

EXTRAVERSION =

2. Post a PR with the updated VERSION file using release: Zephyr 1.11.0 as the commit subject. Merge the PR after successful CI.

3. Tag and push the version, using two annotated tags:

   ```
   $ git pull
   $ git tag -s -m "Zephyr 1.11.0" v1.11.0
   $ git push git@github.com:zephyrproject-rtos/zephyr.git v1.11.0
   ```

4. Find the new v1.11.0 tag at the top of the releases page and edit the release with the Edit tag button with the following:

   - Copy the overview of docs/releases/release-notes-1.11.rst into the release notes textbox and link to the full release notes file on docs.zephyrproject.org.

5. Send an email to the mailing lists (announce and devel) with a link to the release

**Listing all closed GitHub issues**

The release notes for a final release contain the list of GitHub issues that have been closed during the development process of that release.

In order to obtain the list of issues closed during the release development cycle you can do the following:

1. Look for the last release before the current one and find the day it was tagged:

   ```
   $ git show -s --format=%ci v1.10.0
   tag v1.10.0
   Tagger: Kumar Gala <kumar.gala@linaro.org>
   Zephyr 1.10.0
   2017-12-08 13:32:22 -0600
   ```

2. Use available release tools to list all the issues that have been closed between that date and the day of the release.

### 9.3 Feature Tracking

For feature tracking we use Github labels to classify new features and enhancements. The following is the description of each category:

**Enhancement**

Changes to existing features that are not considered a bug and would not block a release. This is an incremental enhancement to a feature that already exists in Zephyr.

**Feature request**

A request for the implementation or inclusion of a new unit of functionality that is not part of any release plans yet, that has not been vetted, and needs further discussion and details.

**Feature**

A committed and planned unit of functionality with a detailed design and implementation proposal and an owner. Features must go through an RFC process and must be vetted and discussed in the TSC before a target milestone is set.
Hardware Support
A request or plan to port an existing feature or enhancement to a particular hardware platform. This ranges from porting Zephyr itself to a new architecture, SoC or board to adding an implementation of a peripheral driver API for an existing hardware platform.

Meta
A label to group other GitHub issues that are part of a single feature or unit of work.

The following workflow should be used to process features:

This is the formal way for asking for a new feature in Zephyr and indicating its importance to the project. Often, the requester may have a readiness and willingness to drive implementation of the feature in an upcoming release, and should assign the request to themselves. If not though, an owner will be assigned after evaluation by the TSC. A feature request can also have a companion RFC with more details on the feature and a proposed design or implementation.

- Label new features requests as feature-request
- The TSC discusses new feature-request items regularly and triages them. Items are examined for similarity with existing features, how they fit with the project goals and other timeline considerations. The priority is determined as follows:
  - High = Next milestone
  - Medium = As soon as possible
  - Low = Best effort
- After the initial discussion and triaging, the label is moved from feature-request to feature with the target milestone and an assignee.

All items marked as feature-request are non-binding and those without an assignee are open for grabs, meaning that they can be picked up and implemented by any project member or the community. You should contact an assigned owner if you’d like to discuss or contribute to that feature’s implementation.

9.3.1 Proposals and RFCs

Many changes, including bug fixes and documentation improvements can be implemented and reviewed via the normal GitHub pull request workflow.

Many changes however are “substantial” and need to go through a design process and produce a consensus among the project stakeholders.

The “RFC” (request for comments) process is intended to provide a consistent and controlled path for new features to enter the project.

Contributors and project stakeholders should consider using this process if they intend to make “substantial” changes to Zephyr or its documentation. Some examples that would benefit from an RFC are:

- A new feature that creates new API surface area, and would require a feature flag if introduced.
- The modification of an existing stable API
- The removal of features that already shipped as part of Zephyr.
- The introduction of new idiomatic usage or conventions, even if they do not include code changes to Zephyr itself.

The RFC process is a great opportunity to get more eyeballs on proposals coming from contributors before it becomes a part of Zephyr. Quite often, even proposals that seem “obvious” can be significantly improved once a wider group of interested people have a chance to weigh in.

The RFC process can also be helpful to encourage discussions about a proposed feature as it is being designed, and incorporate important constraints into the design while it’s easier to change, before the design has been fully implemented.

Some changes do not require an RFC:
• Rephrasing, reorganizing or refactoring
• Addition or removal of warnings
• Addition of new boards, SoCs or drivers to existing subsystems
• …

The process in itself consists in creating a GitHub issue with the RFC label that documents the proposal thoroughly. There is an RFC template included in the main Zephyr GitHub repository that serves as a guideline to write a new RFC.

As with Pull Requests, RFCs might require discussion in the context of one of the Zephyr meetings in order to move it forward in cases where there is either disagreement or not enough voiced opinions in order to proceed. Make sure to either label it appropriately or include it in the corresponding GitHub project in order for it to be examined during the next meeting.

9.3.2 Roadmap and Release Plans

Project roadmaps and release plans are both important tools for the project, but they have very different purposes and should not be confused. A project roadmap communicates the high-level overview of a project's strategy, while a release plan is a tactical document designed to capture and track the features planned for upcoming releases.

- The project roadmap communicates the why; a release plan details the what
- A release plan spans only a few months; a product roadmap might cover a year or more

Project Roadmap

The project roadmap should serve as a high-level, visual summary of the project's strategic objectives and expectations.

If built properly, the roadmap can be a valuable tool for several reasons. It can help the project present its plan in a compelling way to existing and new stakeholders, to help recruit new members and it can be a helpful resource the team and community can refer to throughout the project's development, to ensure they are still executing according to plan.

As such, the roadmap should contain only strategic-level details, major project themes, epics, and goals.

Release Plans

The release plan comes into play when the project roadmap's high-level strategy is translated into an actionable plan built on specific features, enhancements, and fixes that need to go into a specific release or milestone.

The release plan communicates those features and enhancements slated for your project' next release (or the next few releases). So it acts as more of a project plan, breaking the big ideas down into smaller projects the community and main stakeholders of the project can make progress on.

Items labeled as features are short or long term release items that shall have an assignee and a milestone set.

9.4 Code Flow and Branches

9.4.1 Introduction

The zephyr Git repository has three types of branches:
main
Which contains the latest state of development

*topic-*
Topic branches that are used for shared development of a new feature

vx.y-branch
Branches which track maintenance releases based on a major release

Development in topic branches before features go to mainline allows teams to work independently on a subsystem or a feature, improves efficiency and turnaround time, and encourages collaboration and streamlines communication between developers.

Changes submitted to a development topic branch can evolve and improve incrementally in a branch, before they are submitted to the mainline tree for final integration.

By dedicating an isolated branch to complex features, it’s possible to initiate in-depth discussions around new additions before integrating them into the official project.

9.4.2 Roles and Responsibilities

Development topic branch owners have the following responsibilities:

• Use the infrastructure and tools provided by the project (GitHub, Git)

• Review changes coming from team members and request review from branch owners when submitting changes.

• Keep the branch in sync with upstream and update on a regular basis.

• Push changes frequently to upstream using the following methods:
  – GitHub pull requests: for example, when reviews have not been done in the local branch (one-man branch).
  – Merge requests: When a set of changes has been done in a local branch and has been reviewed and tested in a topic branch.

9.5 Modifying Contributions made by other developers

9.5.1 Scenarios

Zephyr contributors and collaborators are encouraged to assist as reviewers in pull requests, so that patches may be approved and merged to Zephyr's main branch as part of the original pull requests. The authors of the pull requests are responsible for amending their original commits following the review process.

There are occasions, however, when a contributor might need to modify patches included in pull requests that are submitted by other Zephyr contributors. For instance, this is the case when:

• a developer cherry-picks commits submitted by other contributors into their own pull requests in order to:
  – integrate useful content which is part of a stale pull request, or
  – get content merged to the project’s main branch as part of a larger patch

• a developer pushes to a branch or pull request opened by another contributor in order to:
  – assist in updating pull requests in order to get the patches merged to the project’s main branch
  – drive stale pull requests to completion so they can be merged
9.5.2 Accepted policies

A developer who intends to cherry-pick and potentially modify patches sent by another contributor shall:

- clarify in their pull request the reason for cherry-picking the patches, instead of assisting in getting the patches merged in their original pull request, and
- invite the original author of the patches to their pull request review.

A developer who intends to force-push to a branch or pull request of another Zephyr contributor shall clarify in the pull request the reason for pushing and for modifying the existing patches (e.g. stating that it is done to drive the pull request review to completion, when the pull request author is not able to do so).

Note: Developers should try to limit the above practice to pull requests identified as stale. Read about how to identify pull requests as stale in development processes and tools.

If the original patches are substantially modified, the developer can either:

- (preferably) reach out to the original author and request them to acknowledge that the modified patches may be merged while having the original sign-off line and author identity, or
- submit the modified patches as their own work (i.e. with their own sign-off line and author identity). In this case, the developer shall identify in the commit message(s) the original source the submitted work is based on (mentioning, for example, the original PR number).

Note: Contributors should uncheck the box “Allow Edits By Maintainers” to indicate that they do not wish their patches to be amended, inside their original branch or pull request, by other Zephyr developers.

9.6 Development Environment and Tools

9.6.1 Code Review

GitHub is intended to provide a framework for reviewing every commit before it is accepted into the code base. Changes, in the form of Pull Requests (PR) are uploaded to GitHub but don’t actually become a part of the project until they’ve been reviewed, passed a series of checks (CI), and are approved by maintainers. GitHub is used to support the standard open source practice of submitting patches, which are then reviewed by the project members before being applied to the code base.

Pull requests should be appropriately labeled, and linked to any relevant bug or feature tracking issues.

The Zephyr project uses GitHub for code reviews and Git tree management. When submitting a change or an enhancement to any Zephyr component, a developer should use GitHub. GitHub automatically assigns a responsible reviewer on a component basis, as defined in the CODEOWNERS file stored with the code tree in the Zephyr project repository. A limited set of release managers are allowed to merge a pull request into the main branch once reviews are complete.

Give reviewers time to review before code merge

The Zephyr project is a global project that is not tied to a certain geography or timezone. We have developers and contributors from across the globe. When changes are proposed using pull request, we need to allow for a minimal review time to give developers and contributors the opportunity to review and comment on changes. There are different categories of changes and we know that some changes do require reviews by subject matter experts and owners of the subsystem being changed. Many changes fall under the “trivial” category that can be addressed with general reviews and do not need to be queued for a maintainer or code-owner review. Additionally, some changes might require further discussions.
and a decision by the TSC or the Security working group. To summarize the above, the diagram below proposes minimal review times for each category:

![Diagram showing pull request classes](image)

**Workflow**
- An author of a change can suggest in his pull-request which category a change should belong to. A project maintainers or TSC member monitoring the inflow of changes can change the label of a pull request by adding a comment justifying why a change should belong to another category.
- The project will use the label system to categorize the pull requests.
- Changes should not be merged before the minimal time has expired.

**Categories/Labels**

**Hotfix** Any change that is a fix to an issue that blocks developers from doing their daily work, for example CI breakage, Test breakage, Minor documentation fixes that impact the user experience.

Such fixes can be merged at any time after they have passed CI checks. Depending on the fix, severity, and availability of someone to review them (other than the author) they can be merged with justification without review by one of the project owners.

**Trivial** Trivial changes are those that appear obvious enough and do not require maintainer or code-owner involvement. Such changes should not change the logic or the design of a subsystem or component. For example a trivial change can be:

- Documentation changes
• Configuration changes
• Minor Build System tweaks
• Minor optimization to code logic without changing the logic
• Test changes and fixes
• Sample modifications to support additional configuration or boards etc.

Maintainer Any changes that touch the logic or the original design of a subsystem or component will need to be reviewed by the code owner or the designated subsystem maintainer. If the code changes is initiated by a contributor or developer other than the owner the pull request needs to be assigned to the code owner who will have to drive the pull request to a mergeable state by giving feedback to the author and asking for more reviews from other developers.

Security Changes that appear to have an impact to the overall security of the system need to be reviewed by a security expert from the security working group.

TSC and Working Groups Changes that introduce new features or functionality or change the way the overall system works need to be reviewed by the TSC or the responsible Working Group. For example for stable API changes, the proposal needs to be presented in the Architecture meeting so that the relevant stakeholders are made aware of the change.

A Pull-Request should have an Assignee

• An assignee to a pull request should not be the same as the author of the pull-request
• An assignee to a pull request is responsible for driving the pull request to a mergeable state
• An assignee is responsible for dismissing stale reviews and seeking reviews from additional developers and contributors
• Pull requests should not be merged without an approval by the assignee.

Pull Request should not be merged by author without review

All pull requests need to be reviewed and should not be merged by the author without a review. The following exceptions apply:

• Hot fixes: Fixing CI issues, reverts, and system breakage
• Release related changes: Changing version file, applying tags and release related activities without any code changes.

Developers and contributors should always seek review, however there are cases when reviewers are not available and there is a need to get a code change into the tree as soon as possible.

Reviewers shall not ‘Request Changes’ without comments or justification

Any change requests (-1) on a pull request have to be justified. A reviewer should avoid blocking a pull-request with no justification. If a reviewer feels that a change should not be merged without their review, then: Request change of the category: for example:

• Trivial -> Maintainer
• Assign Pull Request to yourself, this will mean that a pull request should not be merged without your approval.
Pull Requests should have at least 2 approvals before they are merged

A pull-request shall be merged only with two positive reviews (approval). Beside the person merging the pull-request (merging != approval), two additional approvals are required to be able to merge a pull request. The person merging the request can merge without approving or approve and merge to get to the 2 approvals required.

Reviewers should keep track of pull requests they have provided feedback to

If a reviewer has requested changes in a pull request, he or she should monitor the state of the pull request and/or respond to mention requests to see if his feedback has been addressed. Failing to do so, negative reviews shall be dismissed by the assignee or an owner of the repository. Reviews will be dismissed following the criteria below:

- The feedback or concerns were visibly addressed by the author
- The reviewer did not revisit the pull request after 2 week and multiple pings by the author
- The review is unrelated to the code change or asking for unjustified structural changes such as:
  - Split the PR
  - Can you fix this unrelated code that happens to appear in the diff
  - Can you fix unrelated issues
  - Etc.

Closing Stale Issues and Pull Requests

- The Pull requests and issues sections on Github are NOT discussion forums. They are items that we need to execute and drive to closure. Use the mailing lists for discussions.
- In case of both issues and pull-requests the original poster needs to respond to questions and provide clarifications regarding the issue or the change. After one week without a response to a request, a second attempt to elicit a response from the contributor will be made. After one more week without a response the item may be closed (draft and DNM tagged pull requests are excluded).

9.6.2 Continuous Integration

All changes submitted to GitHub are subject to tests that are run on emulated platforms and architectures to identify breakage and regressions that can be immediately identified. Testing using Twister additionally performs build tests of all boards and platforms. Documentation changes are also verified through review and build testing to verify doc generation will be successful.

Any failures found during the CI test run will result in a negative review assigned automatically by the CI system. Developers are expected to fix issues and rework their patches and submit again.

The CI infrastructure currently runs the following tests:

- Run “checkpatch” for code style issues (can vote -1 on errors; see note)
- Gitlint: Git commit style based on project requirements
- License Check: Check for conflicting licenses
- Run “twister” script
  - Run kernel tests in QEMU (can vote -1 on errors)
  - Build various samples for different boards (can vote -1 on errors)
- Verify documentation builds correctly.
**Note:** “checkpatch” is a Perl script that uses regular expressions to extract information that requires a C language parser to process accurately. As such it sometimes issues false positives. Known cases include constructs like:

```c
static uint8_t __aligned(PAGE_SIZE) page_pool[X_MAX * POOL_PAGES];
IOPCTL_Type *base = config->base;
```

Both lines produce a diagnostic regarding spaces around the * operator: the first is misidentified as a pointer type declaration that would be correct as PAGE_SIZE * POOL_PAGES while the second is misidentified as a multiplication expression that would be correct as IOPCTL_Type * base.

Maintainers can override the -1 in cases where the CI infrastructure gets the wrong answer.

### 9.6.3 Labeling issues and pull requests in GitHub

The project uses GitHub issues and pull requests (PRs) to track and manage daily and long-term work and contributions to the Zephyr project. We use GitHub **labels** to classify and organize these issues and PRs by area, type, priority, and more, making it easier to find and report on relevant items.

All GitHub issues or pull requests must be appropriately labeled. Issues and PRs often have multiple labels assigned, to help classify them in the different available categories. When reviewing a PR, if it has missing or incorrect labels, maintainers shall fix it.

This saves us all time when searching, reduces the chances of the PR or issue being forgotten, speeds up reviewing, avoids duplicate issue reports, etc.

These are the labels we currently have, grouped by applicability:

#### Labels applicable to issues only

- **priority:** {high|medium|low}
  
  To classify the impact and importance of a bug or feature.

  Note: Issue priorities are generally set or changed during the bug-triage or TSC meetings.

  - **Regression**
    Something, which was working, but does not anymore (bug subtype).

  - **Enhancement**
    Changes/Updates/Additions to existing features.

  - **Feature request**
    A request for a new feature.

  - **Feature**
    A planned feature with a milestone.

  - **Hardware Support**
    Covers porting an existing feature (including Zephyr itself) to new hardware.

  - **Duplicate**
    This issue is a duplicate of another issue (please specify).

  - **Good first issue**
    Good for a first time contributor to take.

- **Release Notes**
Issues that need to be mentioned in release notes as known issues with additional information.

Any issue must be classified and labeled as either Bug, Enhancement, RFC, Feature, Feature Request or Hardware Support. More information on how feature requests are handled and become features can be found in Feature Tracking.

Labels applicable to pull requests only

The issue or PR describes a change to a stable API.

- **Hotfix**
  Fix for an issue blocking development.
  - **Trivial**
  - **Maintainer**
  Maintainer review required.
  - **Security Review**
  To be reviewed by a security expert.
  - **DNM**
  This PR should not be merged (Do Not Merge). For work in progress, GitHub "draft" PRs are preferred.
  - **Needs review**
  The PR needs attention from the maintainers.
  - **Backport**
  The PR is a backport or should be backported.
  - **Licensing**
  The PR has licensing issues which require a licensing expert to review it.

**Note:** For all labels applicable to PRs: Please note that the label, together with PR complexity, affects how long a merge should be held to ensure proper review. See review process for details.

Labels applicable to both pull requests and issues

- **area:** *
  Indicates Zephyr subsystems (e.g., area: Kernel, area: I2C, area: Memory Management), project functions (e.g., area: Debugging, area: Documentation, area: Process), or other categories (e.g., area: Coding Style, area: MISRA-C) affected by the bug or the pull request.
  An area maintainer should be able to filter by an area label and find all issues and PRs which relate to that area.
  - **platform:** *
  An issue or PR which affects only a particular platform.
  - **dev-review**
  The issue is to be discussed in the following dev-review if time permits.
  - **TSC**
  TSC stands for Technical Steering Committee. The issue is to be discussed in the following TSC meeting if time permits.
9.7 Bug Reporting

To maintain traceability and relation between proposals, changes, features, and issues, it is recommended to cross-reference source code commits with the relevant GitHub issues and vice versa. Any changes that originate from a tracked feature or issue should contain a reference to the feature by mentioning the corresponding issue or pull-request identifiers.

At any time it should be possible to establish the origin of a change and the reason behind it by following the references in the code.

9.7.1 Reporting a regression issue

It could happen that the issue being reported is identified as a regression, as the use case is known to be working on earlier commit or release. In this case, providing directly the guilty commit when submitting the bug gains a lot of time in the eventual bug fixing.

To identify the commit causing the regression, several methods could be used, but tree bisecting method is an efficient one that doesn’t require deep code expertise and can be used by every one.

For this, `git bisect` is the recommended tool.

Recommendations on the process:

- Run `west update` on each bisection step.
- Once the bisection is over and a culprit identified, verify manually the result.
9.8 Communication and Collaboration

The Zephyr project mailing lists are used as the primary communication tool by project members, contributors, and the community. The mailing list is open for topics related to the project and should be used for collaboration among team members working on the same feature or subsystem or for discussing project direction and daily development of the code base. In general, bug reports and issues should be entered and tracked in the bug tracking system (GitHub Issues) and not broadcasted to the mailing list, the same applies to code reviews. Code should be submitted to GitHub using the appropriate tools.

9.9 Code Documentation

9.9.1 API Documentation

Well documented APIs enhance the experience for developers and are an essential requirement for defining an API’s success. Doxygen is a general purpose documentation tool that the Zephyr project uses for documenting APIs. It generates either an on-line documentation browser (in HTML) and/or provides input for other tools that is used to generate a reference manual from documented source files. In particular, doxygen’s XML output is used as an input when producing the Zephyr project’s online documentation.

9.9.2 Reference to Requirements

APIs for the most part document the implementation of requirements or advertised features and can be traced back to features. We use the API documentation as the main interface to trace implementation back to documented features. This is done using custom _doxygen_ tags that reference requirements maintained somewhere else in a requirement catalogue.

9.9.3 Test Documentation

To help understand what each test does and which functionality it tests we also document all test code using the same tools and in the same context and generate documentation for all unit and integration tests maintained in the same environment. Tests are documented using references to the APIs or functionality they validate by creating a link back to the APIs and by adding a reference to the original requirements.

9.9.4 Documentation Guidelines

Test Code

The Zephyr project uses several test methodologies, the most common being the Ztest framework. Test documentation should only be done on the entry test functions (usually prefixed with test_) and those that are called directly by the Ztest framework. Those tests are going to appear in test reports and using their name and identifier is the best way to identify them and trace back to them from requirements.

Test documentation should not interfere with the actual API documentation and needs to follow a new structure to avoid confusion. Using a consistent naming scheme and following a well-defined structure we will be able to group this documentation in its own module and identify it uniquely when parsing test data for traceability reports. Here are a few guidelines to be followed:

- All test code documentation should be grouped under the all_tests doxygen group
- All test documentation should be under doxygen groups that are prefixed with tests_

The custom doxygen @verify directive signifies that a test verifies a requirement:
To get coverage of how an implementation or a piece of code satisfies a requirements, we use the `satisfy` alias in doxygen:

```c
/**
 * @brief Give a semaphore.
 *
 * This routine gives @a sem, unless the semaphore is already at its maximum permitted count.
 *
 * @note Can be called by ISRs.
 *
 * @param sem Address of the semaphore.
 *
 * @satisfy{@req{015}}
 */
__syscall void k_sem_give(struct k_sem *sem);
```

To generate the matrix, you will first need to build the documentation, specifically you will need to build the doxygen XML output:

```
$ make doxygen
```

Parse the generated XML data from doxygen to generate the traceability matrix.

The Zephyr project defines a development process workflow using GitHub Issues to track feature, enhancement, and bug reports together with GitHub Pull Requests (PRs) for submitting and reviewing changes. Zephyr community members work together to review these Issues and PRs, managing feature enhancements and quality improvements of Zephyr through its regular releases, as outlined in the program management overview.

We can only manage the volume of Issues and PRs, by requiring timely reviews, feedback, and responses from the community and contributors, both for initial submissions and for followup questions and clarifications. Read about the project’s development processes and tools and specifics about review timelines to learn about the project’s goals and guidelines for our active developer community.
TSC Project Roles describes in detail the Zephyr project roles and associated permissions with respect to the development process workflow.

9.10 Terminology

- mainline: The main tree where the core functionality and core features are being developed.
- subsystem/feature branch: is a branch within the same repository. In our case, we will use the term branch also when referencing branches not in the same repository, which are a copy of a repository sharing the same history.
- upstream: A parent branch the source code is based on. This is the branch you pull from and push to, basically your upstream.
- LTS: Long Term Support
Chapter 10

Security

These documents describe the requirements, processes, and developer guidelines for ensuring security is addressed within the Zephyr project.

10.1 Zephyr Security Overview

10.1.1 Introduction

This document outlines the steps of the Zephyr Security Subcommittee towards a defined security process that helps developers build more secure software while addressing security compliance requirements. It presents the key ideas of the security process and outlines which documents need to be created. After the process is implemented and all supporting documents are created, this document is a top-level overview and entry point.

Overview and Scope

We begin with an overview of the Zephyr development process, which mainly focuses on security functionality.

In subsequent sections, the individual parts of the process are treated in detail. As depicted in Figure 1, these main steps are:

1. **Secure Development**: Defines the system architecture and development process that ensures adherence to relevant coding principles and quality assurance procedures.

2. **Secure Design**: Defines security procedures and implement measures to enforce them. A security architecture of the system and relevant sub-modules is created, threats are identified, and countermeasures designed. Their correct implementation and the validity of the threat models are checked by code reviews. Finally, a process shall be defined for reporting, classifying, and mitigating security issues.

3. **Security Certification**: Defines the certifiable part of the Zephyr RTOS. This includes an evaluation target, its assets, and how these assets are protected. Certification claims shall be determined and backed with appropriate evidence.

Intended Audience

This document is a guideline for the development of a security process by the Zephyr Security Subcommittee and the Zephyr Technical Steering Committee. It provides an overview of the Zephyr security process for (security) engineers and architects.
Nomenclature

In this document, the keywords "MUST", "MUST NOT", "REQUIRED", "SHALL", "SHALL NOT", "SHOULD", "SHOULD NOT", "RECOMMENDED", "MAY", and "OPTIONAL" are to be interpreted as described in [?].

These words are used to define absolute requirements (or prohibitions), highly recommended requirements, and truly optional requirements. As noted in RFC-2119, “These terms are frequently used to specify behavior with security implications. The effects on security of not implementing a MUST or SHOULD, or doing something the specification says MUST NOT or SHOULD NOT be done may be very subtle. Document authors should take the time to elaborate the security implications of not following recommendations or requirements as most implementors will not have had the benefit of the experience and discussion that produced the specification.”

Security Document Update

This document is a living document. As new requirements, features, and changes are identified, they will be added to this document through the following process:

1. Changes will be submitted from the interested party(ies) via pull requests to the Zephyr documentation repository.
2. The Zephyr Security Subcommittee will review these changes and provide feedback or acceptance of the changes.
3. Once accepted, these changes will become part of the document.

10.1.2 Current Security Definition

This section recapitulates the current status of secure development within the Zephyr RTOS. Currently, focus is put on functional security and code quality assurance, although additional security features are scoped.

The three major security measures currently implemented are:

- **Security Functionality** with a focus on cryptographic algorithms and protocols. Support for cryptographic hardware is scoped for future releases. The Zephyr runtime architecture is a monolithic binary and removes the need for dynamic loaders, thereby reducing the exposed attack surface.
• **Quality Assurance** is driven by using a development process that requires all code to be reviewed before being committed to the common repository. Furthermore, the reuse of proven building blocks such as network stacks increases the overall quality level and guarantees stable APIs. Static code analyses are provided by Coverity Scan.

• **Execution Protection** including thread separation, stack and memory protection is currently available in the upstream Zephyr RTOS starting with version 1.9.0 (stack protection). Memory protection and thread separation was added in version 1.10.0 for X86 and in version 1.11.0 for ARM and ARC.

These topics are discussed in more detail in the following subsections.

**Security Functionality**

The security functionality in Zephyr hinges mainly on the inclusion of cryptographic algorithms, and on its monolithic system design.

The cryptographic features are provided through a set of cryptographic libraries. Applications can choose TinyCrypt2 or mbedTLS based on their needs. TinyCrypt2 supports key cryptographic algorithms required by the connectivity stacks. TinyCrypt2, however, only provides a limited set of algorithms. mbedTLS supports a wider range of algorithms, but at the cost of additional requirements such as malloc support. Applications can choose the solution that matches their individual requirements. Future work may include APIs to abstract the underlying crypto library choice.

APIs for vendor specific cryptographic IPs in both hardware and software are planned, including secure key storage in the form of secure access modules (SAMs), Trusted Platform Modules (TPMs), and Trusted Execution Environments (TEEs).

The security architecture is based on a monolithic design where the Zephyr kernel and all applications are compiled into a single static binary. System calls are implemented as function calls without requiring context switches. Static linking eliminates the potential for dynamically loading malicious code.

Additional protection features are available in later releases. Stack protection mechanisms are provided to protect against stack overruns. In addition, applications can take advantage of thread separation features to split the system into privileged and unprivileged execution environments. Memory protection features provide the capability to partition system resources (memory, peripheral address space, etc) and assign resources to individual threads or groups of threads. Stack, thread execution level, and memory protection constraints are enforced at the time of context switch.

**Quality Assurance**

The Zephyr project uses an automated quality assurance process. The goal is to have a process including mandatory code reviews, feature and issue management/tracking, and static code analyses.

Code reviews are documented and enforced using a voting system before getting checked into the repository by the responsible subsystem's maintainer. The main goals of the code review are:

- Verifying correct functionality of the implementation
- Increasing the readability and maintainability of the contributed source code
- Ensuring appropriate usage of string and memory functions
- Validation of the user input
- Reviewing the security relevant code for potential issues

The current coding principles focus mostly on coding styles and conventions. Functional correctness is ensured by the build system and the experience of the reviewer. Especially for security relevant code, concrete and detailed guidelines need to be developed and aligned with the developers (see: *Secure Coding*).
Static code analyses are run on the Zephyr code tree on a regular basis using the open source Coverity Scan tool. Coverity Scan now includes complexity analysis.

Bug and issue tracking and management is performed using Jira. The term “survivability” was coined to cover pro-active security tasks such as security issue categorization and management. Initial effort has been started on the definition of vulnerability categorization and mitigation processes within Jira.

Issues determined by Coverity should have more stringent reviews before they are closed as non issues (at least another person educated in security processes need to agree on non-issue before closing).

A security subcommittee has been formed to develop a security process in more detail; this document is part of that process.

**Execution Protection**

Execution protection is supported and can be categorized into the following tasks:

- **Memory separation**: Memory will be partitioned into regions and assigned attributes based on the owner of that region of memory. Threads will only have access to regions they control.

- **Stack protection**: Stack guards would provide mechanisms for detecting and trapping stack overruns. Individual threads should only have access to their own stacks.

- **Thread separation**: Individual threads should only have access to their own memory resources. As threads are scheduled, only memory resources owned by that thread will be accessible. Topics such as program flow protection and other measures for tamper resistance are currently not in scope.

**System Level Security (Ecosystem, …)**

System level security encompasses a wide variety of categories. Some examples of these would be:

- Secure/trusted boot
- Over the air (OTA) updates
- External Communication
- Device authentication
- Access control of onboard resources
  - Flash updating
  - Secure storage
  - Peripherals
- Root of trust
- Reduction of attack surface

Some of these categories are interconnected and rely on multiple pieces to be in place to produce a full solution for the application.

### 10.1.3 Secure Development Process

The development of secure code shall adhere to certain criteria. These include coding guidelines and development processes that can be roughly separated into two categories related to software quality and related to software security. Furthermore, a system architecture document shall be created and kept up-to-date with future development.
Fig. 10.2: Figure 2: Zephyr System Architecture
System Architecture

A high-level schematic of the Zephyr system architecture is given in Figure 2. It separates the architecture into an OS part (**kernel + OS Services**) and a user-specific part (**Application Services**). The OS part itself contains low-level, platform specific drivers and the generic implementation of I/O APIs, file systems, kernel-specific functions, and the cryptographic library.

A document describing the system architecture and design choices shall be created and kept up to date with future development. This document shall include the base architecture of the Zephyr OS and an overview of important submodules. For each of the modules, a dedicated architecture document shall be created and evaluated against the implementation. These documents shall serve as an entry point to new developers and as a basis for the security architecture. Please refer to the Zephyr subsystem documentation for detailed information.

Secure Coding

Designing an open software system such as Zephyr to be secure requires adhering to a defined set of design standards. These standards are included in the Zephyr Project documentation, specifically in its Secure Coding section. In [?], the following, widely accepted principles for protection mechanisms are defined to prevent security violations and limit their impact:

- **Open design** as a design principle incorporates the maxim that protection mechanisms cannot be kept secret on any system in widespread use. Instead of relying on secret, custom-tailored security measures, publicly accepted cryptographic algorithms and well established cryptographic libraries shall be used.

- **Economy of mechanism** specifies that the underlying design of a system shall be kept as simple and small as possible. In the context of the Zephyr project, this can be realized, e.g., by modular code [?] and abstracted APIs.

- **Complete mediation** requires that each access to every object and process needs to be authenticated first. Mechanisms to store access conditions shall be avoided if possible.

- **Fail-safe defaults** defines that access is restricted by default and permitted only in specific conditions defined by the system protection scheme, e.g., after successful authentication. Furthermore, default settings for services shall be chosen in a way to provide maximum security. This corresponds to the “Secure by Default” paradigm [?].

- **Separation of privilege** is the principle that two conditions or more need to be satisfied before access is granted. In the context of the Zephyr project, this could encompass split keys [?].

- **Least privilege** describes an access model in which each user, program and thread shall have the smallest possible subset of permissions in the system required to perform their task. This positive security model aims to minimize the attack surface of the system.

- **Least common mechanism** specifies that mechanisms common to more than one user or process shall not be shared if not strictly required. The example given in [?] is a function that should be implemented as a shared library executed by each user and not as a supervisor procedure shared by all users.

- **Psychological acceptability** requires that security features are easy to use by the developers in order to ensure its usage and the correctness of its application.

In addition to these general principles, the following points are specific to the development of a secure RTOS:

- **Complementary Security/Defense in Depth**: do not rely on a single threat mitigation approach. In case of the complementary security approach, parts of the threat mitigation are performed by the underlying platform. In case such mechanisms are not provided by the platform, or are not trusted, a defense in depth [?] paradigm shall be used.

- **Less commonly used services off by default**: to reduce the exposure of the system to potential attacks, features or services shall not be enabled by default if they are only rarely used (a threshold
of 80% is given in [?]). For the Zephyr project, this can be realized using the configuration management. Each functionality and module shall be represented as a configuration option and needs to be explicitly enabled. Then, all features, protocols, and drivers not required for a particular use case can be disabled. The user shall be notified if low-level options and APIs are enabled but not used by the application.

- **Change management**: to guarantee a traceability of changes to the system, each change shall follow a specified process including a change request, impact analysis, ratification, implementation, and validation phase. In each stage, appropriate documentation shall be provided. All commits shall be related to a bug report or change request in the issue tracker. Commits without a valid reference shall be denied.

Based on these design principles and commonly accepted best practices, a secure development guide shall be developed, published, and implemented into the Zephyr development process. Further details on this are given in the Secure Design section.

**Quality Assurance**

The quality assurance part encompasses the following criteria:

- **Adherence to the Coding Conventions** with respect to coding style, naming schemes of modules, functions, variables, and so forth. This increases the readability of the Zephyr code base and eases the code review. These coding conventions are enforced by automated scripts prior to check-in.

- **Adherence to Deployment Guidelines** is required to ensure consistent releases with a well-documented feature set and a trackable list of security issues.

- **Code Reviews** ensure the functional correctness of the code base and shall be performed on each proposed code change prior to check-in. Code reviews shall be performed by at least one independent reviewer other than the author(s) of the code change. These reviews shall be performed by the subsystem maintainers and developers on a functional level and are to be distinguished from security reviews as laid out in the Secure Design section. Refer to the Project and Governance documentation for more information.

- **Static Code Analysis** tools efficiently detect common coding mistakes in large code bases. All code shall be analyzed using an appropriate tool prior to merges into the main repository. This is not per individual commit, but is to be run on some interval on specific branches. It is mandatory to remove all findings or waive potential false-positives before each release. Waivers shall be documented centrally and in the form of a comment inside the source code itself. The documentation shall include the employed tool and its version, the date of the analysis, the branch and parent revision number, the reason for the waiver, the author of the respective code, and the approver(s) of the waiver. This shall as a minimum run on the main release branch and on the security branch. It shall be ensured that each release has zero issues with regard to static code analysis (including waivers). Refer to the Project and Governance documentation for more information.

- **Complexity Analyses** shall be performed as part of the development process and metrics such as cyclomatic complexity shall be evaluated. The main goal is to keep the code as simple as possible.

- **Automation**: the review process and checks for coding rule adherence are a mandatory part of the precommit checks. To ensure consistent application, they shall be automated as part of the precommit procedure. Prior to merging large pieces of code in from subsystems, in addition to review process and coding rule adherence, all static code analysis must have been run and issues resolved.

**Release and Lifecycle Management**

Lifecycle management contains several aspects:

- **Device management** encompasses the possibility to update the operating system and/or security related sub-systems of Zephyr enabled devices in the field.
• **Lifecycle management**: system stages shall be defined and documented along with the transactions between the stages in a system state diagram. For security reasons, this shall include locking of the device in case an attack has been detected, and a termination if the end of life is reached.

• **Release management** describes the process of defining the release cycle, documenting releases, and maintaining a record of known vulnerabilities and mitigations. Especially for certification purposes the integrity of the release needs to be ensured in a way that later manipulation (e.g. inserting of backdoors, etc.) can be easily detected.

• **Rights management and NDAs**: if required by the chosen certification, the confidentiality and integrity of the system needs to be ensured by an appropriate rights management (e.g. separate source code repository) and non-disclosure agreements between the relevant parties. In case of a repository shared between several parties, measures shall be taken that no malicious code is checked in.

These points shall be evaluated with respect to their impact on the development process employed for the Zephyr project.

### 10.1.4 Secure Design

In order to obtain a certifiable system or product, the security process needs to be clearly defined and its application needs to be monitored and driven. This process includes the development of security related modules in all of its stages and the management of reported security issues. Furthermore, threat models need to be created for currently known and future attack vectors, and their impact on the system needs to be investigated and mitigated. Please refer to the *Secure Coding* outlined in the Zephyr project documentation for detailed information.

The software security process includes:

- **Adherence to the Secure Development Coding** is mandatory to avoid that individual components breach the system security and to minimize the vulnerability of individual modules. While this can be partially achieved by automated tests, it is inevitable to investigate the correct implementation of security features such as countermeasures manually in security-critical modules.

- **Security Reviews** shall be performed by a security architect in preparation of each security-targeted release and each time a security-related module of the Zephyr project is changed. This process includes the validation of the effectiveness of implemented security measures, the adherence to the global security strategy and architecture, and the preparation of audits towards a security certification if required.

- **Security Issue Management** encompasses the evaluation of potential system vulnerabilities and their mitigation as described in *Security Issue Management*.

These criteria and tasks need to be integrated into the development process for secure software and shall be automated wherever possible. On system level, and for each security related module of the secure branch of Zephyr, a directly responsible security architect shall be defined to guide the secure development process.

**Security Architecture**

The general guidelines above shall be accompanied by an architectural security design on system- and module-level. The high level considerations include

- The identification of **security and compliance requirements**

- **Functional security** such as the use of cryptographic functions whenever applicable

- Design of **countermeasures** against known attack vectors

- Recording of security relevant **auditable events**

- Support for **Trusted Platform Modules (TPM)** and **Trusted Execution Environments (TEE)**
- Mechanisms to allow for **in-the-field updates** of devices using Zephyr
- Task scheduler and separation

The security architecture development is based on assets derived from the structural overview of the overall system architecture. Based on this, the individual steps include:

1. **Identification of assets** such as user data, authentication and encryption keys, key generation data (obtained from RNG), security relevant status information.
2. **Identification of threats** against the assets such as breaches of confidentiality, manipulation of user data, etc.
3. **Definition of requirements** regarding security and protection of the assets, e.g. countermeasures or memory protection schemes.

The security architecture shall be harmonized with the existing system architecture and implementation to determine potential deviations and mitigate existing weaknesses. Newly developed sub-modules that are integrated into the secure branch of the Zephyr project shall provide individual documents describing their security architecture. Additionally, their impact on the system level security shall be considered and documented.

**Security Vulnerability Reporting**

Please see *Security Vulnerability Reporting* for information on reporting security vulnerabilities.

**Threat Modeling and Mitigation**

The modeling of security threats against the Zephyr RTOS is required for the development of an accurate security architecture and for most certification schemes. The first step of this process is the definition of assets to be protected by the system. The next step then models how these assets are protected by the system and which threats against them are present. After a threat has been identified, a corresponding threat model is created. This model contains the asset and system vulnerabilities, as well as the description of the potential exploits of these vulnerabilities. Additionally, the impact on the asset, the module it resides in, and the overall system is to be estimated. This threat model is then considered in the module and system security architecture and appropriate counter-measures are defined to mitigate the threat or limit the impact of exploits.

In short, the threat modeling process can be separated into these steps (adapted from [?]):

1. Definition of assets
2. Application decomposition and creation of appropriate data flow diagrams (DFDs)
3. Threat identification and categorization using the [?] and [?] approaches
4. Determination of countermeasures and other mitigation approaches

This procedure shall be carried out during the design phase of modules and before major changes of the module or system architecture. Additionally, new models shall be created or existing ones shall be updated whenever new vulnerabilities or exploits are discovered. During security reviews, the threat models and the mitigation techniques shall be evaluated by the responsible security architect.

From these threat models and mitigation techniques tests shall be derived that prove the effectiveness of the countermeasures. These tests shall be integrated into the continuous integration workflow to ensure that the security is not impaired by regressions.

**Vulnerability Analyses**

In order to find weak spots in the software implementation, vulnerability analyses (VA) shall be performed. Of special interest are investigations on cryptographic algorithms, critical OS tasks, and connectivity protocols.
On a pure software level, this encompasses

- **Penetration testing** of the RTOS on a particular hardware platform, which involves testing the respective Zephyr OS configuration and hardware as one system.

- **Side channel attacks** (timing invariance, power invariance, etc.) should be considered. For instance, ensuring timing invariance of the cryptographic algorithms and modules is required to reduce the attack surface. This applies to both the software implementations and when using cryptographic hardware.

- **Fuzzing tests** shall be performed on both exposed APIs and protocols.

The list given above serves primarily illustration purposes. For each module and for the complete Zephyr system (in general on a particular hardware platform), a suitable VA plan shall be created and executed. The findings of these analyses shall be considered in the security issue management process, and learnings shall be formulated as guidelines and incorporated into the secure coding guide.

If possible (as in case of fuzzing analyses), these tests shall be integrated into the continuous integration process.

### 10.1.5 Security Certification

One goal of creating a secure branch of the Zephyr RTOS is to create a certifiable system or certifiable submodules thereof. The certification scope and scheme is yet to be decided. However, many certification such as Common Criteria require evidence that the evaluation claims are indeed fulfilled, so a general certification process is outlined in the following. Based on the final choices for the certification scheme and evaluation level, this process needs to be refined.

#### Generic Certification Process

In general, the steps towards a certification or precertification (compare) are:

1. The **definition of assets** to be protected within the Zephyr RTOS. Potential candidates are confidential information such as cryptographic keys, user data such as communication logs, and potentially IP of the vendor or manufacturer.

2. Developing a **threat model** and **security architecture** to protect the assets against exploits of vulnerabilities of the system. As a complete threat model includes the overall product including the hardware platform, this might be realized by a split model containing a precertified secure branch of Zephyr which the vendor could use to certify their Zephyr-enabled product.

3. Formulating an **evaluation target** that includes the **certification claims** on the security of the assets to be evaluated and certified, as well as assumptions on the operating conditions.

4. Providing **proof** that the claims are fulfilled. This includes consistent documentation of the security development process, etc.

These steps are partially covered in previous sections as well. In contrast to these sections, the certification process only requires to consider those components that shall be covered by the certification. The security architecture, for example, considers assets on system level and might include items not relevant for the certification.

#### Certification Options

For the security certification as such, the following options can be pursued:

1. **Abstract precertification of Zephyr as a pure software system**: this option requires assumptions on the underlying hardware platform and the final application running on top of Zephyr. If these assumptions are met by the hardware and the application, a full certification can be more easily achieved. This option is the most flexible approach but puts the largest burden on the product vendor.
2. **Certification of Zephyr on specific hardware platform without a specific application in mind:** this scenario describes the enablement of a secure platform running the Zephyr RTOS. The hardware manufacturer certifies the platform under defined assumptions on the application. If these are met, the final product can be certified with little effort.

3. **Certification of an actual product:** in this case, a full product including a specific hardware, the Zephyr RTOS, and an application is certified.

In all three cases, the certification scheme (e.g. FIPS 140-2 [?] or Common Criteria [?]), the scope of the certification (main-stream Zephyr, security branch, or certain modules), and the certification/assurance level need to be determined.

In case of partial certifications (options 1 and 2), assumptions on hardware and/or software are required for certifications. These can include [?]

- **Appropriate physical security** of the hardware platform and its environment.
- **Sufficient protection of storage and timing channels** on the hardware platform itself and all connected devices. (No mentioning of remote connections.)
- Only **trusted/assured applications** running on the device
- The device and its software stack is configured and operated by **properly trained and trusted individuals** with no malicious intent.

These assumptions shall be part of the security claim and evaluation target documents.

### 10.2 Security Vulnerability Reporting

#### 10.2.1 Introduction

Vulnerabilities to the Zephyr project may be reported via email to the vulnerabilities@zephyrproject.org mailing list. These reports will be acknowledged and analyzed by the security response team within 1 week. Each vulnerability will be entered into the Zephyr Project security advisory GitHub. The original submitter will be granted permission to view the issues that they have reported.

#### 10.2.2 Security Issue Management

Issues within this bug tracking system will transition through a number of states according to this diagram:
• New: This state represents new reports that have been entered directly by a reporter. When entered by the response team in response to an email, the issue shall be transitioned directly to Triage.

• Triage: This issue is awaiting Triage by the response team. The response team will analyze the issue, determine a responsible entity, assign it to that individual, and move the issue to the Assigned state. Part of triage will be to set the issue's priority.

• Assigned: The issue has been assigned, and is awaiting a fix by the assignee.

• Review: Once there is a Zephyr pull request for the issue, the PR link will be added to a comment in the issue, and the issue moved to the Review state.

• Accepted: Indicates that this issue has been merged into the appropriate branch within Zephyr.

• Public: The embargo period has ended. The issue will be made publicly visible, the associated CVE updated, and the vulnerabilities page in the docs updated to include the detailed information.
The security advisories created are kept private, due to the sensitive nature of security reports. The issues are only visible to certain parties:

- Members of the PSIRT mailing list
- the reporter
- others, as proposed and ratified by the Zephyr Security Subcommittee. In the general case, this will include:
  - The code owner responsible for the fix.
  - The Zephyr release owners for the relevant releases affected by this vulnerability.

The Zephyr Security Subcommittee shall review the reported vulnerabilities during any meeting with more than three people in attendance. During this review, they shall determine if new issues need to be embargoed.

The guideline for embargo will be based on: 1. Severity of the issue, and 2. Exploitability of the issue. Issues that the subcommittee decides do not need an embargo will be reproduced in the regular Zephyr project bug tracking system.

Security sensitive vulnerabilities shall be made public after an embargo period of at most 90 days. The intent is to allow 30 days within the Zephyr project to fix the issues, and 60 days for external parties building products using Zephyr to be able to apply and distribute these fixes.

Fixes to the code shall be made through pull requests PR in the Zephyr project github. Developers shall make an attempt to not reveal the sensitive nature of what is being fixed, and shall not refer to CVE numbers that have been assigned to the issue. The developer instead should merely describe what has been fixed.

The security subcommittee will maintain information mapping embargoed CVEs to these PRs (this information is within the Github security advisories), and produce regular reports of the state of security issues.

Each issue that is considered a security vulnerability shall be assigned a CVE number. As fixes are created, it may be necessary to allocate additional CVE numbers, or to retire numbers that were assigned.

### 10.2.3 Vulnerability Notification

Each Zephyr release shall contain a report of CVEs that were fixed in that release. Because of the sensitive nature of these vulnerabilities, the release shall merely include a list of CVEs that have been fixed. After the embargo period, the vulnerabilities page shall be updated to include additional details of these vulnerabilities. The vulnerability page shall give credit to the reporter(s) unless a reporter specifically requests anonymity.

The Zephyr project shall maintain a vulnerability-alerts mailing list. This list will be seeded initially with a contact from each project member. Additional parties can request to join this list by filling out the form at the Vulnerability Registry. These parties will be vetted by the project director to determine that they have a legitimate interest in knowing about security vulnerabilities during the embargo period.

Periodically, the security subcommittee will send information to this mailing list describing known embargoed issues, and their backport status within the project. This information is intended to allow them to determine if they need to backport these changes to any internal trees.

When issues have been triaged, this list will be informed of:

- The Zephyr Project security advisory link (GitHub).
- The CVE number assigned.
- The subsystem involved.
- The severity of the issue.

After acceptance of a PR fixing the issue (merged), in addition to the above, the list will be informed of:
- The association between the CVE number and the PR fixing it.
- Backport plans within the Zephyr project.

### 10.2.4 Backporting of Security Vulnerabilities

Each security issue fixed within zephyr shall be backported to the following releases:

- The current Long Term Stable (LTS) release.
- The most recent two releases.

The developer of the fix shall be responsible for any necessary backports, and apply them to any of the above listed release branches, unless the fix does not apply (the vulnerability was introduced after this release was made).

Backports will be tracked on the security advisory.

### 10.2.5 Need to Know

Due to the sensitive nature of security vulnerabilities, it is important to share details and fixes only with those parties that have a need to know. The following parties will need to know details about security vulnerabilities before the embargo period ends:

- Maintainers will have access to all information within their domain area only.
- The current release manager, and the release manager for historical releases affected by the vulnerability (see backporting above).
- The Project Security Incident Response (PSIRT) team will have full access to information. The PSIRT is made up of representatives from platinum members, and volunteers who do work on triage from other members.
- As needed, release managers and maintainers may be invited to attend additional security meetings to discuss vulnerabilities.

### 10.3 Secure Coding

Traditionally, microcontroller-based systems have not placed much emphasis on security. They have usually been thought of as isolated, disconnected from the world, and not very vulnerable, just because of the difficulty in accessing them. The Internet of Things has changed this. Now, code running on small microcontrollers often has access to the internet, or at least to other devices (that may themselves have vulnerabilities). Given the volume they are often deployed at, uncontrolled access can be devastating.

This document describes the requirements and process for ensuring security is addressed within the Zephyr project. All code submitted should comply with these principles.

Much of this document comes from [?].

#### 10.3.1 Introduction and Scope

This document covers guidelines for the Zephyr Project, from a security perspective. Many of the ideas contained herein are captured from other open source efforts.

We begin with an overview of secure design as it relates to Zephyr. This is followed by a section on Secure development knowledge, which gives basic requirements that a developer working on the project will need to have. This section gives references to other security documents, and full details of how to write secure software are beyond the scope of this document. This section also describes vulnerability

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1 An attack resulted in a significant portion of DNS infrastructure being taken down.
knowledge that at least one of the primary developers should have. This knowledge will be necessary for the review process described below this.

Following this is a description of the review process used to incorporate changes into the Zephyr codebase. This is followed by documentation about how security-sensitive issues are handled by the project. Finally, the document covers how changes are to be made to this document.

10.3.2 Secure Coding

Designing an open software system such as Zephyr to be secure requires adhering to a defined set of design standards. In [?], the following, widely accepted principles for protection mechanisms are defined to help prevent security violations and limit their impact:

- **Open design** as a design guideline incorporates the maxim that protection mechanisms cannot be kept secret on any system in widespread use. Instead of relying on secret, custom-tailored security measures, publicly accepted cryptographic algorithms and well established cryptographic libraries shall be used.

- **Economy of mechanism** specifies that the underlying design of a system shall be kept as simple and small as possible. In the context of the Zephyr project, this can be realized, e.g., by modular code [?] and abstracted APIs.

- **Complete mediation** requires that each access to every object and process needs to be authenticated first. Mechanisms to store access conditions shall be avoided if possible.

- **Fail-safe defaults** defines that access is restricted by default and permitted only in specific conditions defined by the system protection scheme, e.g., after successful authentication. Furthermore, default settings for services shall be chosen in a way to provide maximum security. This corresponds to the “Secure by Default” paradigm [?].

- **Separation of privilege** is the principle that two conditions or more need to be satisfied before access is granted. In the context of the Zephyr project, this could encompass split keys [?].

- **Least privilege** describes an access model in which each user, program, and thread, shall have the smallest possible subset of permissions in the system required to perform their task. This positive security model aims to minimize the attack surface of the system.

- **Least common mechanism** specifies that mechanisms common to more than one user or process shall not be shared if not strictly required. The example given in [?] is a function that should be implemented as a shared library executed by each user and not as a supervisor procedure shared by all users.

- **Psychological acceptability** requires that security features are easy to use by the developers in order to ensure their usage and the correctness of its application.

In addition to these general principles, the following points are specific to the development of a secure RTOS:

- **Complementary Security/Defense in Depth**: do not rely on a single threat mitigation approach. In case of the complementary security approach, parts of the threat mitigation are performed by the underlying platform. In case such mechanisms are not provided by the platform, or are not trusted, a defense in depth [?] paradigm shall be used.

- **Less commonly used services off by default**: to reduce the exposure of the system to potential attacks, features or services shall not be enabled by default if they are only rarely used (a threshold of 80% is given in [?]). For the Zephyr project, this can be realized using the configuration management. Each functionality and module shall be represented as a configuration option and needs to be explicitly enabled. Then, all features, protocols, and drivers not required for a particular use case can be disabled. The user shall be notified if low-level options and APIs are enabled but not used by the application.

- **Change management**: to guarantee a traceability of changes to the system, each change shall follow a specified process including a change request, impact analysis, ratification, implementation,
and validation phase. In each stage, appropriate documentation shall be provided. All commits shall be related to a bug report or change request in the issue tracker. Commits without a valid reference shall be denied.

10.3.3 Secure development knowledge

Secure designer

The Zephyr project must have at least one primary developer who knows how to design secure software. This requires understanding the following design principles, including the 8 principles from [?]:

- economy of mechanism (keep the design as simple and small as practical, e.g., by adopting sweeping simplifications)
- fail-safe defaults (access decisions shall deny by default, and projects' installation shall be secure by default)
- complete mediation (every access that might be limited must be checked for authority and be non-bypassable)
- open design (security mechanisms should not depend on attacker ignorance of its design, but instead on more easily protected and changed information like keys and passwords)
- separation of privilege (ideally, access to important objects should depend on more than one condition, so that defeating one protection system won't enable complete access. For example, multi-factor authentication, such as requiring both a password and a hardware token, is stronger than single-factor authentication)
- least privilege (processes should operate with the least privilege necessary)
- least common mechanism (the design should minimize the mechanisms common to more than one user and depended on by all users, e.g., directories for temporary files)
- psychological acceptability (the human interface must be designed for ease of use - designing for "least astonishment" can help)
- limited attack surface (the set of the different points where an attacker can try to enter or extract data)
- input validation with whitelists (inputs should typically be checked to determine if they are valid before they are accepted; this validation should use whitelists (which only accept known-good values), not blacklists (which attempt to list known-bad values)).

Vulnerability Knowledge

A "primary developer" in a project is anyone who is familiar with the project's code base, is comfortable making changes to it, and is acknowledged as such by most other participants in the project. A primary developer would typically make a number of contributions over the past year (via code, documentation, or answering questions). Developers would typically be considered primary developers if they initiated the project (and have not left the project more than three years ago), have the option of receiving information on a private vulnerability reporting channel (if there is one), can accept commits on behalf of the project, or perform final releases of the project software. If there is only one developer, that individual is the primary developer.

At least one of the primary developers must know of common kinds of errors that lead to vulnerabilities in this kind of software, as well as at least one method to counter or mitigate each of them.

Examples (depending on the type of software) include SQL injection, OS injection, classic buffer overflow, cross-site scripting, missing authentication, and missing authorization. See the CWE/SANS top 25 or OWASP Top 10 for commonly used lists.
Zephyr Security Subcommittee

There shall be a “Zephyr Security Subcommittee”, responsible for enforcing this guideline, monitoring reviews, and improving these guidelines.

This team will be established according to the Zephyr Project charter.

10.3.4 Code Review

The Zephyr project shall use a code review system that all changes are required to go through. Each change shall be reviewed by at least one primary developer that is not the author of the change. This developer shall determine if this change affects the security of the system (based on their general understanding of security), and if so, shall request the developer with vulnerability knowledge, or the secure designer to also review the code. Any of these individuals shall have the ability to block the change from being merged into the mainline code until the security issues have been addressed.

10.3.5 Issues and Bug Tracking

The Zephyr project shall have an issue tracking system (such as GitHub) that can be used to record and track defects that are found in the system.

Because security issues are often sensitive, this issue tracking system shall have a field to indicate a security issue. Setting this field shall result in the issue only being visible to the Zephyr Security Subcommittee. In addition, there shall be a field to allow the Zephyr Security Subcommittee to add additional users that will have visibility to a given issue.

This embargo, or limited visibility, shall only be for a fixed duration, with a default being a project-decided value. However, because security considerations are often external to the Zephyr project itself, it may be necessary to increase this embargo time. The time necessary shall be clearly annotated in the issue itself.

The list of issues shall be reviewed at least once a month by the Zephyr Security Subcommittee. This review should focus on tracking the fixes, determining if any external parties need to be notified or involved, and determining when to lift the embargo on the issue. The embargo should not be lifted via an automated means, but the review team should avoid unnecessary delay in lifting issues that have been resolved.

10.3.6 Modifications to This Document

Changes to this document shall be reviewed by the Zephyr Security Subcommittee, and approved by consensus.

10.4 Sensor Device Threat Model

This document describes a threat model for an IoT sensor device. Spelling out a threat model helps direct development effort, and can be used to help prioritize these efforts as well.

This device contains a sensor of some type (for example temperature, or a pressure in a pipe), which sends this data to an SoC running a microcontroller. This microcontroller connects to a cloud service, and relays this sensor data to this service. The cloud service is also able to send configuration data to the device, as well as software update images. A general diagram can be seen in Figure 1:

In this sensor device, the sensor connects with the SoC via an SPI bus, and the SoC has a network interface that it uses to communicate with the cloud service. The particulars of these interfaces can impact the threat model in unexpected ways, and variants on this will need to be considered (for example, using a separate network interface SoC connected via some type of bus).
This model also focuses on communicating via the MQTT-over-TLS protocol, as this seems to be in wide use\(^1\).

### 10.4.1 Assets

One aspect of the threat model to consider are assets involved in the operation of the device. The following list enumerates the assets included in this model:

1. **The bootloader.** This is a small code/data image contained in on-device flash that is the first code to run. In order to establish a root of trust, this image must be immutable. This model assumes that the SoC provides a mechanism to protect a region of the flash from future writes, and that this will be done after this image is programmed into the device, early in production [th-imboot].

2. **The application firmware image.** This asset consists of the remainder of the firmware run by the microcontroller. The distinction is made because this part of the image will need to be updated periodically as security vulnerabilities are discovered. Requirements for updates to this image are:
   
   a. The image shall only be replaced with an authorized image [th-authrepl].
   
   b. When an authorized replacement image is available, the update shall be done in a timely manner [th-timely-update].
   
   c. The image update shall be seen as atomic, meaning that when the image is run, the flash shall contain either the update image in its entirety, or the old image in its entirety [th-atomic-update].

3. **Root certificate list.** In order to authenticate the cloud service (server), the IoT device must have a list of root certificates that are allowed to sign the certificate on the server. For cloud-provider based services, this list will generally be provided by the service provider. Because the root certificates can expire, and possibly be revoked, this list will need to be periodically updated [th-root-certs], [th-root-check].

4. **Client secrets.** To authenticate the client to the service, the client must possess some kind of secret. This is generally a private key, usually either an RSA key or an EC private key. When

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\(^1\) See https://www.slideshare.net/kartben/iot-developer-survey-2018. As of this writing, the three major cloud IoT service providers, AWS IoT, Google Cloud IoT, and Microsoft Azure IoT all provide MQTT over TLS. Some feedback has suggested that some find difficulty with UDP protocols and routing issues on various networks.
establishing communication with the server, the device will use this secret either as part of the TLS establishment, or to sign a message used in the communication.

This secret is generally generated by the service provider, or by software running elsewhere, and must be securely installed on the device. Policy may dictate that this secret be replaced periodically, which will require a way to update the client secret. Typically, the service will allow two or three active keys to allow this update to proceed while the old key is used.

These secrets must be protected from read, and the smallest amount of code necessary shall have access to them. [th-secret-storage]

5. Current date/time. TLS certificate verification requires knowledge of the current date and time in order to determine if the current time falls within the certificate's current validity time. Also, token-based client authentication will generally require the client to sign a message containing a time window that the token is valid. Certificate validation requires the device's notion of date and time to be accurate within a day or so. Token generation generally requires the time to be accurate within 5-10 minutes.

It may be possible to approximate secure time by querying an external time server. Secure NTP is possibly beyond the capabilities of an IoT device. The main risks of having incorrect time are denial of service (the device rejects valid certificates), and the generation of tokens with invalid times. It could be possible to trick the device into generating tokens that are valid in the future, but the attacker would also have to spoof the server's certificate to be able to intercept this. [th-time]

6. Sensor data. The data received from the sensor itself, and delivered to the service shall be delivered without modification or tampering.

7. Device configuration. Various configuration data, such as the hostname of the service to connect to, the address of a time server, frequency and parameters of when sensor data is sent to the service, and other need to be kept by the device. This configuration data will need to be updated periodically as the configuration changes. Updates should be allowed only from authorized parties. [th-conf]

8. Logs. In order to assist with analysis of security issues, the device shall log information about security-pertinent events. IoT devices generally have limited storage, and as such, these logs need to be carefully selected. It may also be possible to send these log events to the cloud service where they can be stored in a more resource-available environment. Types of events that should be logged include:

   a. Firmware image updates. The system should log the download of new images, and when an image is successfully updated.
   
   b. Client secret changes. Changes and new client secrets should be logged.
   
   c. Changes to the device configuration.

[th-logs]

10.4.2 Communication

In addition to assets, the threat model also considers the locations where data or assets are communicated between entities of the system.

1. Flash contents. The flash device contains several regions. The contents of flash can be modified programmatically by the SoC's CPU.

   a. The bootloader. As described in the Assets section, the bootloader is a small section of the flash device containing the code initially run. This section shall be written early in the lifecycle of the device, and the flash device then configured to permanently disallow modification of this section. This configuration should also prevent modification via external interfaces, such as JTAG or SWD debuggers.

   The bootloader is responsible for verifying the signature of the application image as well as updating the application image from the update image when an update is needed.
The bootloader shall verify the signature of the update image before installing it.

The bootloader shall only accept an update image with a newer version number than the current image.

b. **The application image.** The application image contains the code executed during normal operation of the device. Before running this image, the bootloader shall verify a digital signature of the image, to avoid running an image that has been tampered with. The flash/system shall be configured such that after the bootloader has completed, the CPU will be unable to write to the application image.

c. **The update image.** This is an area of flash that holds a new version of the application image. This image will be downloaded and stored by the application during normal operation. When this has completed, the application can trigger a reboot, and the bootloader can install the new image.

d. **Secret storage.** An area of the flash will be used to store client secrets. This area is written and read by a subset of the application image. The application shall be configured to protect this area from both reads and writes by code that does not need to have access to it, giving consideration to possible exploits found within a majority of the application code. Revealing the contents of the secrets would allow the attacker to spoof this device.

Initial secrets shall be placed in the device during a provisioning activity, distinct from normal operation of the device. Later updates can be made under the direction of communication received over a secured channel to the service.

e. **Configuration storage.** There shall be an area to store other configuration information. On resource-constrained devices, it is allowed for this to be stored in the same region as the secret storage, however, this adds additional code that has access to the secret storage area, and as such, more code that must be scrutinized.

f. **Log storage.** The device may have an area of flash where log events can be written.

2. **Sensor/Actuator interface.** In this design, the sensor or actuator communicates with the SoC via a bus, such as SPI. The hardware design shall be made to make intercepting this bus difficult for an attack. Required techniques depend on the sensitivity and use of the sensor data, and can range from having the sensor mounted on the same PCB as the MCU to epoxy potting the entire device.

3. **Communication with cloud service.** Communication between the device, and the cloud service will be done over the general internet. As such, it shall be assumed that an attacker can arbitrarily intercept this channel and, for example, return spoofed DNS results or attempt man-in-the-middle attacks against communication with cloud services.

The device shall use TLS for all communication with the cloud service [th-all-tls]. The TLS stack shall be configured to use only cipher suites that are generally considered secure\(^2\), including forward secrecy. The communication shall be secured by the following:

a. **Cipher suite selection.** The device shall only allow communication with generally agreed secure cipher suites [th-tls-ciphers].

b. **Server certificate verification.** The server presented by the server shall be verified [th-root-check].

i. **Naming.** The certificate shall name the host and service the cloud service server is providing. RFC6125 describes best practices for this. It is permissible for the device to require the certificate to be more restrictive than as described in this RFC, provided the service can use a certificate that can comply.

ii. **Path validation.** The device shall verify that the certificate chain has a valid signature path from a root certificate contained within the device, to the certificate presented by the service. RFC4158 describes this is general. The device is permitted to require a more restricted path, provided the server certificate used complies with this restriction.

\(^2\) As new exploits are discovered, what is considered secure can change. Organizations such as [https://www.ssllabs.com/](https://www.ssllabs.com/) provide information on current ideas of how TLS must be configured to be secure.
iii. **Validity period.** The validity period of all presented certificates shall be checked against the device's best notion of the current time.

c. **Client authentication.** The client shall authenticate itself to the service using a secret known only to that particular device. There are several options, and the technique used is generally mandated by the particular service provider being used [th-tls-client-auth].

i. **TLS client certificates.** The TLS protocol allows the client to present a certificate, and assert its knowledge of the secret described by that certificate. Generally, these certificates will be stored within the service provider. These certificates can be self-signed, or signed by a CA. Since the service provider maintains a list of valid certificates (mapping them to a device identity), having these certificates signed by a CA does not add any additional security, but may be useful in the management of these certificates.

ii. **Token-based authentication.** It is also possible for the client to authenticate itself using the `password` field of the MQTT CONNECT packet. However, the secret itself must not be transmitted in this packet. Instead, a token-based protocol, such as RFC7519's JSON Web Token (JWT) can be used. These tokens will generally have a small validity period (e.g. 1 hour), to prevent them from being reused if they are intercepted. The token shall not be sent until the device has verified the identity of the server.

d. **Random/Entropy source.** Cryptographic communication requires the generation of secure pseudorandom numbers. The device shall use a modern, accepted cryptographic random-bit generator to generate these random numbers. It shall use either a Non-Deterministic Random Bit Generator (True RBG) implemented in hardware within the SoC, or a Deterministic Random Bit Generator (Pseudo RBG) seeded by an entropy source within the SoC. Please see NIST SP 800-90A for information on approved RBGs and NIST SP 800-90B for information on testing a device's entropy source [th-entropy].

4. **Communication with the time service.** Ideally, the device shall contain hardware that maintains a secure time. However, most SoCs in use do not have support for this, and it will be necessary to consult an external time service. RFC4330 and referenced RFCs describe the Simple Network Time Protocol that can be used to query the current time from a network time server.

5. **Device lifecycle.** An IoT device will have a lifecycle from production to destruction and disposal of the device. Aspects of this lifecycle that impact security include initial provisioning, normal operation, re-provisioning, and destruction.

a. **Initial provisioning.** During the initial provisioning stage, it is necessary to program the bootloader, an initial application image, a device secret, and initial configuration data [th-initial-provision]. In addition, the bootloader flash protection shall be installed. Of this information, only the device secret needs to differ per device. This secret shall be securely maintained, and destroyed in all locations outside of the device once it has been programmed [th-initial-secret].

b. **Normal operation.** Normal operation includes the behavior described by the rest of this document.

c. **Re-provisioning.** Sometimes it is necessary to re-provision a device, such as for a different application. One way to do this is to keep the same device secret, and replace the configuration data, as well as the cloud service data associated with the device. It is also possible to program a new device secret, but if this is done it shall be done securely, and the new secret destroyed externally once programmed into the device [th-reprovision].

d. **Destruction.** To prevent the device secret from being used to spoof the device, upon decommissioning, the secret for a particular device shall be rendered ineffective [th-destruction]. Possibilities include:

i. Hardware destruction of the device.

ii. Securely wiping the flash area containing the secret.

iii. Removing the device identity and certificate from the service.

3 Note that merely erasing this flash area is unlikely to be sufficient.
10.4.3 Other Considerations

In addition to the above, network connected devices generally will need a way to configure them to connect to the network environment they are placed in. There are numerous ways of doing this, and it is important for these configuration methods to not circumvent the security requirements described above.

10.4.4 Threats

10.4.5 Notes

10.5 Hardening Tool

Zephyr contains several optional features that make the overall system more secure. As we take advantage of hardware features, many of these options are platform specific and besides it, some of them are unknown by developers.

To address this problem, Zephyr provides a tool that helps to check an application configuration option list against a list of hardening preferences defined by the Security Group. The tool can identify the build target and based on that provides suggestions and recommendations on how to optimize the configuration for security.

10.5.1 Usage

After configure of your application, change directory to the build folder and:

```
# ninja build system:
$ ninja hardenconfig
# make build system:
$ make hardenconfig
```

The output should be similar to the one bellow:

<table>
<thead>
<tr>
<th>name</th>
<th>current</th>
<th>recommended</th>
<th>check result</th>
</tr>
</thead>
<tbody>
<tr>
<td>CONFIG_HW_STACK_PROTECTION</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_BOOT_BANNER</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_PRINTK</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_EARLY_CONSOLE</td>
<td>y</td>
<td>n</td>
<td>FAIL</td>
</tr>
<tr>
<td>CONFIG_OVERRIDE_FRAME_POINTER_DEFAULT</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
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<tr>
<td>CONFIG_DEBUG_INFO</td>
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<td>n</td>
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<tr>
<td>CONFIG_TEST_RANDOM_GENERATOR</td>
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<tr>
<td>CONFIG_BUILD_OUTPUT_STRIPED</td>
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<td>y</td>
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<tr>
<td>CONFIG_STACK_SENTINEL</td>
<td>n</td>
<td>y</td>
<td>FAIL</td>
</tr>
</tbody>
</table>
10.6 Vulnerabilities

This page collects all of the vulnerabilities that are discovered and fixed in each release. It will also often have more details than is available in the releases. Some vulnerabilities are deemed to be sensitive, and will not be publicly discussed until there is sufficient time to fix them. Because the release notes are locked to a version, the information here can be updated after the embargo is lifted.

10.6.1 CVE-2017

CVE-2017-14199

Buffer overflow in getaddrinfo().

- CVE-2017-14199
- Zephyr project bug tracker ZEPSEC-12
- PR6158 fix for 1.11.0

CVE-2017-14201

The shell DNS command can cause unpredictable results due to misuse of stack variables. Use After Free vulnerability in the Zephyr shell allows a serial or telnet connected user to cause denial of service, and possibly remote code execution.

This has been fixed in release v1.14.0.

- CVE-2017-14201
- Zephyr project bug tracker ZEPSEC-17
- PR13260 fix for v1.14.0

CVE-2017-14202

The shell implementation does not protect against buffer overruns resulting in unpredictable behavior. Improper Restriction of Operations within the Bounds of a Memory Buffer vulnerability in the shell component of Zephyr allows a serial or telnet connected user to cause a crash, possibly with arbitrary code execution.

This has been fixed in release v1.14.0.

- CVE-2017-14202
- Zephyr project bug tracker ZEPSEC-18
- PR13048 fix for v1.14.0

10.6.2 CVE-2019

CVE-2019-9506

The Bluetooth BR/EDR specification up to and including version 5.1 permits sufficiently low encryption key length and does not prevent an attacker from influencing the key length negotiation. This allows practical brute-force attacks (aka “KNOB”) that can decrypt traffic and inject arbitrary ciphertext without the victim noticing.

- CVE-2019-9506
• Zephyr project bug tracker ZEPSEC-20
• PR18702 fix for v1.14.0
• PR18659 fix for v2.0.0

10.6.3 CVE-2020

CVE-2020-10019

Buffer Overflow vulnerability in USB DFU of zephyr allows a USB connected host to cause possible remote code execution.

This has been fixed in releases v1.14.2, v2.2.0, and v2.1.1.

• CVE-2020-10019
  • Zephyr project bug tracker ZEPSEC-25
  • PR23460 fix for 1.14.x
  • PR23457 fix for 2.1.x
  • PR23190 fix in 2.2.0

CVE-2020-10021

Out-of-bounds write in USB Mass Storage with unaligned sizes

Out-of-bounds Write in the USB Mass Storage memoryWrite handler with unaligned Sizes.

See NCC-ZEP-024, NCC-ZEP-025, NCC-ZEP-026

This has been fixed in releases v1.14.2, and v2.2.0.

• CVE-2020-10021
  • Zephyr project bug tracker ZEPSEC-26
  • PR23455 fix for v1.14.2
  • PR23456 fix for the v2.1 branch
  • PR23240 fix for v2.2.0

CVE-2020-10022

UpdateHub Module Copies a Variable-Size Hash String Into a Fixed-Size Array

A malformed JSON payload that is received from an UpdateHub server may trigger memory corruption in the Zephyr OS. This could result in a denial of service in the best case, or code execution in the worst case.

See NCC-ZEP-016

This has been fixed in the below pull requests for main, branch from v2.1.0, and branch from v2.2.0.

• CVE-2020-10022
  • Zephyr project bug tracker ZEPSEC-28
  • PR24154 fix for main
  • PR24065 fix for branch from v2.1.0
  • PR24066 fix for branch from v2.2.0
CVE-2020-10023

Shell Subsystem Contains a Buffer Overflow Vulnerability In shell_spaces_trim

The shell subsystem contains a buffer overflow, whereby an adversary with physical access to the device is able to cause a memory corruption, resulting in denial of service or possibly code execution within the Zephyr kernel.

See NCC-ZEP-019

This has been fixed in releases v1.14.2, v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10023
- Zephyr project bug tracker ZEPSEC-29
- PR23646 fix for v1.14.2
- PR23649 fix for branch from v2.1.0
- PR23304 fix for v2.2.0

CVE-2020-10024

ARM Platform Uses Signed Integer Comparison When Validating Syscall Numbers

The arm platform-specific code uses a signed integer comparison when validating system call numbers. An attacker who has obtained code execution within a user thread is able to elevate privileges to that of the kernel.

See NCC-ZEP-001

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10024
- Zephyr project bug tracker ZEPSEC-30
- PR23535 fix for v1.14.2
- PR23498 fix for branch from v2.1.0
- PR23323 fix for v2.2.0

CVE-2020-10027

ARC Platform Uses Signed Integer Comparison When Validating Syscall Numbers

An attacker who has obtained code execution within a user thread is able to elevate privileges to that of the kernel.

See NCC-ZEP-001

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0,

- CVE-2020-10027
- Zephyr project bug tracker ZEPSEC-35
- PR23500 fix for v1.14.2
- PR23499 fix for branch from v2.1.0
- PR23328 fix for v2.2.0
CVE-2020-10028

Multiple Syscalls In GPIO Subsystem Performs No Argument Validation

Multiple syscalls with insufficient argument validation

See NCC-ZEP-006

This has been fixed in releases v1.14.2, and v2.2.0, and in a branch from v2.1.0.

- CVE-2020-10028
- Zephyr project bug tracker ZEPSEC-32
- PR23733 fix for v1.14.2
- PR23737 fix for branch from v2.1.0
- PR23308 fix for v2.2.0 (gpio patch)

CVE-2020-10058

Multiple Syscalls In kscan Subsystem Performs No Argument Validation

Multiple syscalls in the Kscan subsystem perform insufficient argument validation, allowing code executing in userspace to potentially gain elevated privileges.

See NCC-ZEP-006

This has been fixed in a branch from v2.1.0, and release v2.2.0.

- CVE-2020-10058
- Zephyr project bug tracker ZEPSEC-34
- PR23748 fix for branch from v2.1.0
- PR23308 fix for v2.2.0 (kscan patch)

CVE-2020-10059

UpdateHub Module Explicitly Disables TLS Verification

The UpdateHub module disables DTLS peer checking, which allows for a man in the middle attack. This is mitigated by firmware images requiring valid signatures. However, there is no benefit to using DTLS without the peer checking.

See NCC-ZEP-018

This has been fixed in a PR against Zephyr main.

- CVE-2020-10059
- Zephyr project bug tracker ZEPSEC-36
- PR24954 fix on main (to be fixed in v2.3.0)
- PR24954 fix v2.1.0
- PR24954 fix v2.2.0
CVE-2020-10060

UpdateHub Might Dereference An Uninitialized Pointer

In updatehub_probe, right after JSON parsing is complete, objects[1] is accessed from the output structure in two different places. If the JSON contained less than two elements, this access would reference uninitialized stack memory. This could result in a crash, denial of service, or possibly an information leak.

Recommend disabling updatehub until such a time as a fix can be made available.

See NCC-ZEP-030

This has been fixed in a PR against Zephyr main.

- CVE-2020-10060
- Zephyr project bug tracker ZEPSEC-37
- PR27865 fix on main (to be fixed in v2.4.0)
- PR27865 fix for v2.3.0
- PR27865 fix for v2.2.0
- PR27865 fix for v2.1.0

CVE-2020-10061

Error handling invalid packet sequence

Improper handling of the full-buffer case in the Zephyr Bluetooth implementation can result in memory corruption.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10061
- Zephyr project bug tracker ZEPSEC-75
- PR23516 fix for v2.3 (split driver)
- PR23517 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23547 fix for branch from v2.2.0

CVE-2020-10062

Packet length decoding error in MQTT

CVE: An off-by-one error in the Zephyr project MQTT packet length decoder can result in memory corruption and possible remote code execution. NCC-ZEP-031

The MQTT packet header length can be 1 to 4 bytes. An off-by-one error in the code can result in this being interpreted as 5 bytes, which can cause an integer overflow, resulting in memory corruption.

This has been fixed in main for v2.3.

- CVE-2020-10062
- Zephyr project bug tracker ZEPSEC-84
- commit 11b7a37d for v2.3
- NCC-ZEP report (NCC-ZEP-031)
CVE-2020-10063

Remote Denial of Service in CoAP Option Parsing Due To Integer Overflow

A remote adversary with the ability to send arbitrary CoAP packets to be parsed by Zephyr is able to cause a denial of service.

This has been fixed in main for v2.3.

- CVE-2020-10063
- Zephyr project bug tracker ZEPSEC-55
- PR24435 fix in main for v2.3
- PR24531 fix for branch from v2.2
- PR24535 fix for branch from v2.1
- PR24530 fix for branch from v1.14
- NCC-ZEP report (NCC-ZEP-032)

CVE-2020-10064

Improper Input Frame Validation in ieee802154 Processing

- CVE-2020-10064
- Zephyr project bug tracker ZEPSEC-65
- PR24971 fix for v2.4
- PR33451 fix for v1.4

CVE-2020-10065

OOB Write after not validating user-supplied length (<= 0xffff) and copying to fixed-size buffer (default: 77 bytes) for HCI_ACL packets in bluetooth HCI over SPI driver.

- CVE-2020-10065
- Zephyr project bug tracker ZEPSEC-66
- This issue has not been fixed.

CVE-2020-10066

Incorrect Error Handling in Bluetooth HCI core

In hci_cmd_done, the buf argument being passed as null causes nullpointer dereference.

- CVE-2020-10066
- Zephyr project bug tracker ZEPSEC-67
- PR24902 fix for v2.4
- PR25089 fix for v1.4
CVE-2020-10067

Integer Overflow In is_in_region Allows User Thread To Access Kernel Memory

A malicious userspace application can cause a integer overflow and bypass security checks performed by system call handlers. The impact would depend on the underlying system call and can range from denial of service to information leak to memory corruption resulting in code execution within the kernel.

See NCC-ZEP-005

This has been fixed in releases v1.14.2, and v2.2.0.

- CVE-2020-10067
- Zephyr project bug tracker ZEPSEC-27
- PR23653 fix for v1.14.2
- PR23654 fix for the v2.1 branch
- PR23239 fix for v2.2.0

CVE-2020-10068

Zephyr Bluetooth DLE duplicate requests vulnerability

In the Zephyr project Bluetooth subsystem, certain duplicate and back-to-back packets can cause incorrect behavior, resulting in a denial of service.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10068
- Zephyr project bug tracker ZEPSEC-78
- PR23707 fix for v2.3 (split driver)
- PR23708 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23964 fix for v2.2.0

CVE-2020-10069

Zephyr Bluetooth unchecked packet data results in denial of service

An unchecked parameter in bluetooth data can result in an assertion failure, or division by zero, resulting in a denial of service attack.

This has been fixed in branches for v1.14.0, v2.2.0, and will be included in v2.3.0.

- CVE-2020-10069
- Zephyr project bug tracker ZEPSEC-81
- PR23705 fix for v2.3 (split driver)
- PR23706 fix for v2.3 (legacy driver)
- PR23091 fix for branch from v1.14.0
- PR23963 fix for branch from v2.2.0
**CVE-2020-10070**

**MQTT buffer overflow on receive buffer**

In the Zephyr Project MQTT code, improper bounds checking can result in memory corruption and possibly remote code execution. NCC-ZEP-031

When calculating the packet length, arithmetic overflow can result in accepting a receive buffer larger than the available buffer space, resulting in user data being written beyond this buffer.

This has been fixed in main for v2.3.

- CVE-2020-10070
- Zephyr project bug tracker ZEPSEC-85
- commit 0b39cbf3 for v2.3
- NCC-ZEP report (NCC-ZEP-031)

**CVE-2020-10071**

**Insufficient publish message length validation in MQTT**

The Zephyr MQTT parsing code performs insufficient checking of the length field on publish messages, allowing a buffer overflow and potentially remote code execution. NCC-ZEP-031

This has been fixed in main for v2.3.

- CVE-2020-10071
- Zephyr project bug tracker ZEPSEC-86
- commit 989c4713 fix for v2.3
- NCC-ZEP report (NCC-ZEP-031)

**CVE-2020-10072**

**All threads can access all socket file descriptors**

There is no management of permissions to network socket API file descriptors. Any thread running on the system may read/write a socket file descriptor knowing only the numerical value of the file descriptor.

- CVE-2020-10072
- Zephyr project bug tracker ZEPSEC-87
- PR25804 fix for v2.4
- PR27176 fix for v1.4

**CVE-2020-10136**

**IP-in-IP protocol routes arbitrary traffic by default**

- CVE-2020-10136
- Zephyr project bug tracker ZEPSEC-64
CVE-2020-13598

FS: Buffer Overflow when enabling Long File Names in FAT_FS and calling fs_stat
Performing fs_stat on a file with a filename longer than 12 characters long will cause a buffer overflow.

- CVE-2020-13598
- Zephyr project bug tracker ZEPSEC-88
- PR25852 fix for v2.4
- PR28782 fix for v2.3
- PR33577 fix for v1.4

CVE-2020-13599

Security problem with settings and littlefs
When settings is used in combination with littlefs all security related information can be extracted from
the device using MCUmgr and this could be used e.g in bt-mesh to get the device key, network key, app
keys from the device.

- CVE-2020-13599
- Zephyr project bug tracker ZEPSEC-57
- PR26083 fix for v2.4

CVE-2020-13600

Malformed SPI in response for eswifi can corrupt kernel memory

- CVE-2020-13600
- Zephyr project bug tracker ZEPSEC-91
- PR26712 fix for v2.4

CVE-2020-13601

Possible read out of bounds in dns read

- CVE-2020-13601
- Zephyr project bug tracker ZEPSEC-92
- PR27774 fix for v2.4
- PR30503 fix for v1.4

CVE-2020-13602

Remote Denial of Service in LwM2M do_write_op_tlv
In the Zephyr LwM2M implementation, malformed input can result in an infinite loop, resulting in a
denial of service attack.

- CVE-2020-13602
- Zephyr project bug tracker ZEPSEC-56
- PR26571 fix for v2.4
- PR33578 fix for v1.4
CVE-2020-13603

Possible overflow in mempool
- Zephyr offers pre-built ‘malloc’ wrapper function instead.
- The ‘malloc’ function is wrapper for the ‘sys_mem_pool_alloc’ function
- sys_mem_pool_alloc allocates ‘size + WB_UP(sizeof(struct sys_mem_pool_block))’ in an unsafe manner.
- Asking for very large size values leads to internal integer wrap-around.
- Integer wrap-around leads to successful allocation of very small memory.
- For example: calling malloc(0xffffffff) leads to successful allocation of 7 bytes.
- That leads to heap overflow.

CVE-2020-13603
- Zephyr project bug tracker ZEPSEC-111
- PR31796 fix for v2.4
- PR32808 fix for v1.4

10.6.4 CVE-2021

CVE-2021-3319

DOS: Incorrect 802154 Frame Validation for Omitted Source / Dest Addresses
Improper processing of omitted source and destination addresses in ieee802154 frame validation (ieee802154_validate_frame)
This has been fixed in main for v2.5.0
- CVE-2020-3319
- Zephyr project bug tracker GHSA-94jg-2p6q-5364
- PR31908 fix for main

CVE-2021-3320

Mismatch between validation and handling of 802154 ACK frames, where ACK frames are considered during validation, but not during actual processing, leading to a type confusion.
- CVE-2020-3320
- PR31908 fix for main

CVE-2021-3321

Incomplete check of minimum IEEE 802154 fragment size leading to an integer underflow.
- CVE-2020-3321
- Zephyr project bug tracker ZEPSEC-114
- PR33453 fix for v2.4
CVE-2021-3323

Integer Underflow in 6LoWPAN IPHC Header Uncompression
This has been fixed in main for v2.5.0
- CVE-2020-3323
- Zephyr project bug tracker GHSA-89j6-qpxf-pfpc
- PR 31971 fix for main

CVE-2021-3430

Assertion reachable with repeated LL_CONNECTION_PARAM_REQ.
This has been fixed in main for v2.6.0
- CVE-2021-3430
- Zephyr project bug tracker GHSA-46h3-hjcq-2jjr
- PR 33272 fix for main
- PR 33369 fix for 2.5
- PR 33759 fix for 1.14.2

CVE-2021-3431

BT: Assertion failure on repeated LL_FEATURE_REQ
This has been fixed in main for v2.6.0
- CVE-2021-3431
- Zephyr project bug tracker GHSA-7548-5m6f-mqv9
- PR 33340 fix for main
- PR 33369 fix for 2.5

CVE-2021-3432

Invalid interval in CONNECT_IND leads to Division by Zero
This has been fixed in main for v2.6.0
- CVE-2021-3432
- Zephyr project bug tracker GHSA-7364-p4wc-8mj4
- PR 33278 fix for main
- PR 33369 fix for 2.5

CVE-2021-3433

BT: Invalid channel map in CONNECT_IND results to Deadlock
This has been fixed in main for v2.6.0
- CVE-2021-3433
- Zephyr project bug tracker GHSA-3c2f-w4v6-qxrp
• PR 33278 fix for main
• PR 33369 fix for 2.5

CVE-2021-3434

L2CAP: Stack based buffer overflow in le_ecred_conn_req()
This has been fixed in main for v2.6.0
• CVE-2021-3434
  • Zephyr project bug tracker GHSA-8w87-6rfp-cfrm
  • PR 33305 fix for main
  • PR 33419 fix for 2.5
  • PR 33418 fix for 1.14.2

CVE-2021-3435

L2CAP: Information leakage in le_ecred_conn_req()
This has been fixed in main for v2.6.0
• CVE-2021-3435
  • Zephyr project bug tracker GHSA-xhg3-gvj6-4rqh
  • PR 33305 fix for main
  • PR 33419 fix for 2.5
  • PR 33418 fix for 1.14.2

CVE-2021-3436

Bluetooth: Possible to overwrite an existing bond during keys distribution phase when the identity address of the bond is known
During the distribution of the identity address information we don't check for an existing bond with the same identity address. This means that a duplicate entry will be created in RAM while the newest entry will overwrite the existing one in persistent storage.
This has been fixed in main for v2.6.0
• CVE-2021-3436
  • Zephyr project bug tracker GHSA-j76f-35mc-4h63
  • PR 33266 fix for main
  • PR 33432 fix for 2.5
  • PR 33433 fix for 2.4
  • PR 33718 fix for 1.14.2
CVE-2021-3454

Truncated L2CAP K-frame causes assertion failure

For example, sending L2CAP K-frame where SDU length field is truncated to only one byte, causes assertion failure in previous releases of Zephyr. This has been fixed in master by commit 0ba9437 but has not yet been backported to older release branches.

This has been fixed in main for v2.6.0
  • CVE-2021-3454
  • Zephyr project bug tracker GHSA-fx88-6c29-vrp3
  • PR 32588 fix for main
  • PR 33513 fix for 2.5
  • PR 33514 fix for 2.4

CVE-2021-3455

Disconnecting L2CAP channel right after invalid ATT request leads freeze

When Central device connects to peripheral and creates L2CAP connection for Enhanced ATT, sending some invalid ATT request and disconnecting immediately causes freeze.

This has been fixed in main for v2.6.0
  • CVE-2021-3455
  • Zephyr project bug tracker GHSA-7g38-3x9v-v7vp
  • PR 35597 fix for main
  • PR 36104 fix for 2.5
  • PR 36105 fix for 2.4

CVE-2021-3510

Zephyr JSON decoder incorrectly decodes array of array

When using JSON_OBJ_DESCR_ARRAY_ARRAY, the subarray is has the token type JSON_TOK_LIST_START, but then assigns to the object part of the union. arr_parse then takes the offset of the array-object (which has nothing todo with the list) treats it as relative to the parent object, and stores the length of the subarray in there.

This has been fixed in main for v2.7.0
  • CVE-2021-3510
  • Zephyr project bug tracker GHSA-289f-7mw3-2qf4
  • PR 36340 fix for main
  • PR 37816 fix for 2.6

CVE-2021-3581

HCI data not properly checked leads to memory overflow in the Bluetooth stack

In the process of setting SCAN_RSP through the HCI command, the Zephyr Bluetooth protocol stack did not effectively check the length of the incoming HCI data. Causes memory overflow, and then the data in the memory is overwritten, and may even cause arbitrary code execution.
This has been fixed in main for v2.6.0

- CVE-2021-3581
- Zephyr project bug tracker GHSA-8q65-5gqf-fmw5
- PR 35935 fix for main
- PR 35984 fix for 2.5
- PR 35985 fix for 2.4
- PR 35985 fix for 1.14

**CVE-2021-3625**

Buffer overflow in Zephyr USB DFU DNLOAD

This has been fixed in main for v2.6.0

- CVE-2021-3625
- Zephyr project bug tracker GHSA-c3gr-hgvr-f363
- PR 36694 fix for main

**CVE-2021-3835**

Buffer overflow in Zephyr USB device class

This has been fixed in main for v3.0.0

- CVE-2021-3835
- Zephyr project bug tracker GHSA-fm6v-8625-99jf
- PR 42093 fix for main
- PR 42167 fix for 2.7

**CVE-2021-3861**

Buffer overflow in the RNDIS USB device class

This has been fixed in main for v3.0.0

- CVE-2021-3861
- Zephyr project bug tracker GHSA-hvf8-w4h8-gxvj
- PR 39725 fix for main

**CVE-2021-3966**

Usb bluetooth device ACL read cb buffer overflow

This has been fixed in main for v3.0.0

- Zephyr project bug tracker GHSA-hfxq-3w6x-fv2m
- PR 42093 fix for main
- PR 42167 fix for 2.7.0
CVE-2022-0553
Possible to retrieve unencrypted firmware image
This has been fixed in main for v3.0.0
- Zephyr project bug tracker GHSA-wrj2-9vj9-rrcp
- PR 42424 fix for main

CVE-2022-1041
Out-of-bound write vulnerability in the Bluetooth mesh core stack can be triggered during provisioning
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-p449-9hv9-pj38
- PR 45136 fix for main
- PR 45188 fix for v3.0.0
- PR 45187 fix for v2.7.0

CVE-2022-1042
Out-of-bound write vulnerability in the Bluetooth mesh core stack can be triggered during provisioning
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-j7v7-w73r-mm5x
- PR 45066 fix for main
- PR 45135 fix for v3.0.0
- PR 45134 fix for v2.7.0

CVE-2022-1841
Out-of-Bound Write in tcp_flags
This has been fixed in main for v3.1.0
- Zephyr project bug tracker GHSA-5c3j-p8cr-2pgh
- PR 45796 fix for main

CVE-2022-2741
can: denial-of-service can be triggered by a crafted CAN frame
This has been fixed in main for v3.2.0
- Zephyr project bug tracker GHSA-hx5v-j59q-c3j8
- PR 47903 fix for main
- PR 47957 fix for v3.1.0
- PR 47958 fix for v3.0.0
- PR 47959 fix for v2.7.0
Bibliography

[th-imboot] Must boot with an immutable bootloader.
[th-authrepl] Application image shall only be replaced with an authorized image.
[th-timely-update] Application updates shall be done in a timely manner.
[th-atomic-update] Application updates shall be atomic.
[th-root-certs] TLS must have a list of trusted root certificates.
[th-root-check] TLS must verify root certificate from server is valid.
[th-secret-storage] There must be a mechanism to securely store client secrets. The least amount of code necessary shall have access to these secrets.
[th-time] System must have moderately accurate notion of the current date/time.
[th-conf] The system must receive, and keep configuration data.
[th-logs] The system must log security-related events, and either store them locally, or send to a service.
[th-all-tls] All communications with the cloud service shall use TLS.
[th-tls-ciphers] TLS shall be configured to allow only generally agreed cipher suites (including forward secrecy).
[th-tls-client-auth] The device shall authenticate itself with the cloud provider using one of the methods described.
[th-entropy] The TLS layer shall use a modern, accepted cryptographic random-bit generator seeded by an entropy source within the SoC.
[th-initial-provision] The device shall have a per-device secret loaded before deployment.
[th-initial-secret] The initial secret shall be securely maintained, and destroyed in any external location as soon as the device is provisioned.
[th-reprovision] Reprovisioning a device shall be done securely.
[th-destruction] Upon decommissioning, the device secret shall be rendered ineffective.
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The text in the image appears to be a fragment of a documentation page, likely from a technical manual or guide, discussing error codes and functions related to I3C communication protocol. The code samples and descriptions suggest a focus on handling errors and specific functions like `i3c_reg_read_byte`, `i3c_reg_write_byte`, `i3c_reg_update_byte`, `i3c_read`, `i3c_sdr_target_error_codes`, and others. The text is dense with technical terms and variable names, typical of embedded systems or low-level programming documentation.

For a better understanding, one might need to refer to specific sections of the Zephyr Project Documentation for context, as indicated by the footer of the document, which mentions "Zephyr Project Documentation, Release 3.2.99."
Zephyr Project Documentation, Release 3.2.99

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