
i.MX 6 BSP Porting Guide

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Chapter 1

Porting U-Boot from an i.MX 6 Reference Board to an i.MX 6 Custom Board

1.1 U-Boot Overview

This chapter provides a step-by-step guide that explains how to add i.MX 6 custom board support for U-Boot.

This developer guide is based on the U-Boot v2013.04 package. For the i.MX patches, refer to the release notes.

1.2 Obtaining the Source Code for the U-Boot

The following steps describe how to obtain the source code.

1. Install Yocto Project. See the *Freescale Yocto Project User's Guide*.
2. In Yocto Project, set the U-Boot preferred provider to u-boot-imx. Confirm that the `sources/meta-fsl-bsp-release/imx/meta-fsl-arm/conf` has the line `PREFERRED_PROVIDER_u-boot_mx6 = "u-boot-imx"`

The U-Boot code is now located at `<build directory>/tmp/work/<machine>-poky-linux-gnueabi/u-boot-fslc/<version>/git`, where `<machine>` can be one of the following:

- imx6qsabresd
- imx6qsabreauto
- imx6dlsabresd
- imx6dlsabreauto
- imx6solosabreauto
- imx6slevk

The U-Boot main directory is referred to as `<UBOOT_DIR>`. It is also assumed that your shell working directory is `<UBOOT_DIR>`.

1.2.1 Preparing the Code

The following steps describes how to prepare the code.

1. Copy the board directory, as shown below:

```
$cp -R board/freescale/mx6_<reference board name> board/freescale/mx6_<custom board name>
```

2. Copy the existing mx6<reference board name>.h board configuration file as mx6<custom board name>.h, as shown below:

```
$cp include/configs/mx6<reference board name>.h include/configs/mx6<custom board name>.h
```

NOTE

The configuration files for the i.MX 6 are located at include/configs. The files associated with the boards are:

- i.MX 6 SABRE-SD:
 - mx6sabresd_common.h
 - mx6sabresd.h
- i.MX 6 SABRE-AI:
 - mx6sabresd_common.h
 - mx6sabreauto.h
- i.MX 6SL EVK:
 - mx6slevk.h

NOTE

You should pay attention to the following configurations when using a new board.

- *CONFIG_LOADADDR*: Normally your uImage will be loaded to this address for boot.
- *CONFIG_SYS_MALLOC_LEN*: Heap memory size.
- *CONFIG_STACKSIZE*: Stack size.
- *CONFIG_NR_DRAM_BANKS*: Number of ddr banks.
- *CONFIG_DDR_MB*: Configure the DDR size in
- *MB.PHYS_SDRAM*: Physical address for the DDR memory
- Config file is important for U-Boot. It determines the size, functionality, and performance of u-boot.bin.

3. Create one entry in <UBOOT_DIR>/boards.cfg for the new -based configuration. This file is in alphabetical order. The instruction is an example for i.MX 6Quad board:

```
mx6q<customer_board_name>      arm      armv7      mx6q<customer_board_name>
freescale      mx6
```



```
mx6q<customer_board_name>:IMX_CONFIG=board/freescale/mx6q<customer_board_name>/
mx6q.cfg,MX6Q,DEFAULT_FDT_FILE="imx6q-<customer_board_name>.dtb",DDR_MB
2048,SYS_USE_SPINOR
```

NOTE

U-Boot project developers recommend adding any new board to the MAKEALL script and running this script to validate that the new code has not broken any other platform build. This is a requirement if you plan to submit a patch back to the U-Boot community. For further information, see the U-Boot README file.

4. Rename

```
board/freescale/mx6<reference board name>/mx6<reference board name>.c
```

to

```
board/freescale/mx6<custom board name>/mx6<custom board name>.c.
```

5. Change the line

```
COBJS := mx6<reference board name>.o (inside board/freescale/mx6<custom board
name>/Makefile)
```

to

```
COBJS := mx6<custom board name>.o
```

NOTE

The remaining instructions build the U-Boot manually and do not use Yocto Project.

6. Create a shell script under <UBOOT_DIR> named build_u-boot.sh.

The file contents are as follows:

```
#!/bin/bash
export ARCH=arm
export CROSS_COMPILE=<path to cross compiler prefix> (e.g.
/opt/poky/1.4.1/sysroots/i686-pokysdk-linux/usr/bin/cortexa9hf-vfp-neon-poky-linux-
gnueabi/arm-poky-linux-gnueabi-
make distclean;
make mx6<custom board name>
make
```

7. Compile U-Boot by using ./build_u-boot.sh

8. If everything is correct, you should now have u-boot.bin, which indicates that your build setup is correct and ready to be customized.

The new i.MX 6 custom board that you have created is an exact copy of the i.MX 6 reference board, but the boards are two independent builds. This allows you to proceed to the next step: customizing the code to suit the new hardware design.

1.3 Customizing the i.MX 6 Custom Board Code

The new i.MX 6 custom board is a part of the U-Boot source tree, but it is a duplicate of the i.MX 6 reference board code and needs to be customized.

The DDR technology is a potential key difference between the two boards.

If there is a difference in the DDR technology between the two boards, the DDR initialization needs to be ported. DDR initialization is coded in the DCD table, inside the boot header of the U-Boot image. When porting bootloader, kernel or driver code, you must have the schematics easily accessible for reference.

1.3.1 Changing the DCD Table for i.MX 6 DDR3LPDDR2 Initialization

Before you initialize the memory interface, you need to configure the relevant I/O pins with the right mode and impedance, and then initialize the MMDC module.

1. To port to the custom board, the DDR needs to be initialized properly.
2. Open the file

```
board/freescale/mx6<customer_board_name>/ddr.cfg
```

3. Modify all items in this file to match the memory specifications. These code blocks will be read by the ROM code to initialize your DDR memory.

1.3.2 Booting with the Modified U-Boot

This section describes how to compile and write u-boot.bin to an SD card.

If the DDR configuration (board/freescale/mx6<customer_board_name>/ddr.cfg) was modified successfully, you can compile and write u-boot.imx to an SD card. To verify this, insert the SD card into the SD card socket of the CPU board and power on the board.

The following message should be displayed on the console if your board was based on the i.MX 6Quad SABRE_SD:

```
U-Boot 2013.04-02326-gd20319c (Sep 13 2013 - 15:44:53)

CPU:   Freescale i.MX6Q rev1.2 at 792 MHz
CPU:   Temperature 31 C, calibration data: 0x5804d87d
Reset cause: POR
Board: MX6Q/SDL-SabreSD
I2C:   ready
DRAM:  1 GiB
```

```

MMC:   FSL_SDHC: 0, FSL_SDHC: 1, FSL_SDHC: 2
In:    serial
Out:   serial
Err:   serial
Found PFUZE100! deviceid=10,revid=10
Net:   FEC [PRIME]
Hit any key to stop autoboot:  0
U-Boot >

```

The following message should be displayed on the console if your custom board was based on the i.MX 6SoloLite EVK:

```

U-Boot 2013.04-02326-gd20319c (Sep 13 2013 - 15:44:53)
CPU: Freescale i.MX6SL rev1.2 at 396 MHz
CPU: Temperature 31 C, calibration data: 0x5804d87d
Reset cause: POR
Board: MX6SLEVK
I2C: ready
DRAM: 1 GiB
MMC: FSL_SDHC: 0
In: serial
Out: serial
Err: serial
Found PFUZE100! deviceid=10,revid=11
Net: FEC
Hit any key to stop autoboot:  0
U-Boot >

```

1.3.3 Adding New Driver Initialization Code to Board Files

The following steps describe how to add new driver and how to initialize code.

1. Find `mx6<customer_board>.c` in `board/freescale/mx6<customer_board>/`.
2. Edit `mx6<customer_board>.c` and add new driver initialization code, including clock, iomux, and gpio.
3. Put driver initialization function into `board_init` or `board_late_init`.

NOTE

- The `board_early_init_f()` function will be called at the very early phase if you define `CONFIG_BOARD_EARLY_INIT_F`. You can put the UART/SPI-NOR/NAND iomux setup function which requires to be set up at the very early phase.
- The `board_init()` function will be called between `board_early_init_f` and `board_late_init`. You can do some general board-level setup here. If you do not define `CONFIG_BOARD_EARLY_INIT_F`, do not

call `printf` before the uart setup is finished. Otherwise, the system may be down.

- **board_late_init()** function will be called fairly later. To debug the initialization code, put the initialization function into it.

1.3.4 Further Customization at System Boot

To further customize your U-Boot board project, use the first function that system boot calls on:

```
start_armboot in "lib_arm/board.c".
board_early_init_f()
board_init()
```

All board initialization is executed inside this function. It starts by running through the **init_sequence[]** array of function pointers.

The first board dependent function inside the **init_sequence[]** array is **board_early_init_f()**. **board_early_init_f()** is implemented inside `board/freescale/mx6<custom board name>.c`.

The following line of code is most important:

```
...
setup_iomux_uart();
...
```

NOTE

If a device tree is used, the machine ID is not used. The compatible string of the DTS file is used to match the board. The device tree for file each boot variation is specified in the machine configuration files in the `meta-fsl-arm/conf/machine` directory.

1.3.5 Customizing the Printed Board Name

To customize the printed board name, use the **checkboard()** function.

This function is called from the **init_sequence[]** array implemented inside `board/freescale/mx6<custom board name>.c`. There are two ways to use **checkboard()** to customize the printed board name. The brute force way or by using a more flexible identification method if implemented on the custom board.

To customize the brute force way, delete `identify_board_id()` inside `checkboard()` and replace `printf("Board: ");` with `printf("Board: i.MX 6 on <custom board>\n");`

If this replacement is not made, the custom board may use another identification method. The identification can be detected and printed by implementing the `__print_board_info()` function according to the identification method on the custom board.

1.4 Debugging

There are two ways for debugging:

- Use Realview ICE.
- Use printf.

1.4.1 Using RealView ICE for Debugging

Generally, we use RealView ICE to debug at a very early stage, for example, before uart initialization, or when it is difficult to debug with printf.

1. Make sure that your RealView ICE supports Cortex-A9. If not, you need to upgrade the firmware and the RealView software.
2. Load U-Boot (which is an elf file) in the root directory of U-Boot fully, or just symbol (faster) to debug step by step.

NOTE

We can make optimization level 0 in rules.mk, which is easier for debugging in RealView ICE.

1.4.2 Using printf for debugging

This is the most common method we use in debugging. You can print your value in the driver for debugging.

NOTE

If you want to use printf in early stages, such as in `board_init`, we can put uart initialization code earlier, such as in the `board_early_init_f()`.

Chapter 2

Configuring the IOMUX Controller

2.1 IOMUX Overview

Before using the pins (or pads), users must select the desired function and correct values for characteristics such as voltage level, drive strength, and hysteresis. You can configure a set of registers from the IOMUX controller.

i.MX 6Dual/6Quad

For detailed information about each pin, see the "External Signals and Pin Multiplexing" chapter in the i.MX 6Dual/6Quad Multimedia Applications Processor Reference Manual. For additional information about the IOMUX controller block, see the "IOMUX Controller (IOMUXC)" chapter in the i.MX 6Dual/6Quad Multimedia Applications Processor Reference Manual.

i.MX 6DualLite

For detailed information about each pin, see the "External Signals and Pin Multiplexing" chapter in the i.MX 6DualLite Multimedia Applications Processor Reference Manual. For additional information about the IOMUX controller block, see the "IOMUX Controller (IOMUXC)" chapter in the i.MX 6DualLite Multimedia Applications Processor Reference Manual.

i.MX 6SoloLite

For detailed information about each pin, see the "External Signals and Pin Multiplexing" chapter in the i.MX 6SoloLite Multimedia Applications Processor Reference Manual. For additional information about the IOMUX controller block, see the "IOMUX Controller (IOMUXC)" chapter in the i.MX 6SoloLite Multimedia Applications Processor Reference Manual.

2.2 Information for Setting IOMUX Controller Registers

The IOMUX controller contains four sets of registers that affect the i.MX 6Dual/6Quadi.MX/6DualLite/i.MX 6Solo/i.MX 6SoloLite registers.

- General-purpose registers (IOMUXC_GPRx)-consist of registers that control PLL frequency, voltage, and other general purpose sets.
- "Daisy Chain" control registers (IOMUXC_<Instance_port>_SELECT_INPUT)-control the input path to a module when more than one pad may drive the module's input
- MUX control registers (changing pad modes):
 - Select which of the pad's eight different functions (also called ALT modes) is used.
 - Set the pad functions individually or by group using one of the following registers:
 - IOMUXC_SW_MUX_CTL_PAD_<PAD NAME>
 - IOMUXC_SW_MUX_CTL_GRP_<GROUP NAME>
- Pad control registers (changing pad characteristics):
 - Set pad characteristics individually or by group using one of the following registers:
 - IOMUXC_SW_PAD_CTL_PAD_<PAD_NAME>
 - IOMUXC_SW_PAD_CTL_GRP_<GROUP NAME>
 - Pad characteristics are:
 - SRE (1 bit slew rate control)-Slew rate control bit; selects between FAST/SLOW slew rate output. Fast slew rate is used for high frequency designs.
 - DSE (2 bits drive strength control)-Drive strength control bits; selects the drive strength (low, medium, high, or max).
 - ODE (1 bit open drain control)-Open drain enable bit; selects open drain or CMOS output.
 - HYS (1 bit hysteresis control)-Selects between CMOS or Schmitt Trigger when pad is an input.
 - PUS (2 bits pull up/down configuration value)-Selects between pull up or down and its value.
 - PUE (1 bit pull/keep select)-Selects between pull up or keeper. A keeper circuit help assure that a pin stays in the last logic state when the pin is no longer being driven.
 - PKE (1 bit enable/disable pull up, pull down or keeper capability)-Enable or disable pull up, pull down, or keeper.

- `DDR_MODE_SEL` (1 bit `ddr_mode` control)-Needed when interfacing DDR memories.
- `DDR_INPUT` (1 bit `ddr_input` control)-Needed when interfacing DDR memories.

2.3 Using IOMUX in the Device Tree - Example

This is an example which shows how to use IOMUX in the Device Tree

```

usdhc@0219c000 { /* uSDHC4 */
    fsl,card-wired;
    vmmc-supply = <&reg_3p3v>;
    status = "okay";
    pinctrl-names = "default";
    pinctrl-0 = <&pinctrl_usdhc4_1>;
};
iomuxc@020e0000 {
    compatible = "fsl,imx6q-iomuxc";
    reg = <0x020e0000 0x4000>;

    /* shared pinctrl settings */
    usdhc4 {
        pinctrl_usdhc4_1: usdhc4grp-1 {
            fsl,pins = <
0x17059                MX6QDL_PAD_SD4_CMD__SD4_CMD
0x10059                MX6QDL_PAD_SD4_CLK__SD4_CLK
0x17059                MX6QDL_PAD_SD4_DAT0__SD4_DATA0
0x17059                MX6QDL_PAD_SD4_DAT1__SD4_DATA1
0x17059                MX6QDL_PAD_SD4_DAT2__SD4_DATA2
0x17059                MX6QDL_PAD_SD4_DAT3__SD4_DATA3
0x17059                MX6QDL_PAD_SD4_DAT4__SD4_DATA4
0x17059                MX6QDL_PAD_SD4_DAT5__SD4_DATA5
0x17059                MX6QDL_PAD_SD4_DAT6__SD4_DATA6
0x17059                MX6QDL_PAD_SD4_DAT7__SD4_DATA7 0x17059
                                >;
        };
    };
    ....
};

```

For details, see:

[Documentation/devicetree/bindings/pinctrl/fsl,imx-pinctrl.txt](#)

[Documentation/devicetree/bindings/pinctrl/fsl,imx6*-pinctrl.txt](#)

Chapter 3

Registering a New UART Driver

3.1 Enabling UART on Kernel Menuconfig

Enable the UART driver on Linux menuconfig. This option is located at:

```
-> Device Drivers
    -> Character devices
        -> Serial drivers
            <*> IMX serial port support
            [*] Console on IMX serial port
```

After enabling the UART driver, build the Linux kernel and boot the board.

3.2 UART Settings

By default, the UART is configured as follows:

- Baud Rate: 9600
- Data bits: 8
- Parity: None
- Stop bits: 1
- Flow Control: None

3.3 File Names and Locations

There are three Linux source code directories that contain relevant UART files.

The header file is available in the directory <linux source code directory>/drivers/tty/serial/

Table 3-1. Available Files-First Set

File	Description
imx.c	uart driver

Table below lists the UART files that are available on the directory <linux source code directory>/arch/arm/plat-mxc/include/mach/

Table 3-2. Available Files-Second Set

File	Description
imx_uart.h	UART header containing UART configuration and data structures

Chapter 4

Adding Support for SDHC

4.1 SDHC Overview

uSDHC has 14 associated I/O signals.

The following list describes the associated I/O signals.

Signal Overview

- The SD_CLK is an internally generated clock used to drive the MMC, SD, and SDIO cards.
- The CMD I/O is used to send commands and receive responses to/from the card. Eight data lines (DAT7~DAT0) are used to perform data transfers between the SDHC and the card.
- The SD_CD# and SD_WP are card detection and write protection signals directly routed from the socket. These two signals are active low (0). A low on SD_CD# means that a card is inserted and a high on SD_WP means that the write protect switch is active.
- SD_LCTL is an output signal used to drive an external LED to indicate that the SD interface is busy.
- SD_RST_N is an output signal used to reset the MMC card. This should be supported by the card.
- SD_VSELECT is an output signal used to change the voltage of the external power supplier. SD_CD#, SD_WP, SD_LCTL, SD_RST_N, and SD_VSELECT are all optional for system implementation. If the uSDHC is desired to support a 4-bit data transfer, DAT7~DAT4 can also be optional and tied to high.

Adding uSDHC support in the device tree

Example for adding uSDHC support in the device tree:

```
usdhc@02194000 { /* uSDHC2 */
    compatible = "fsl,imx6q-usdhc";
    reg = <0x02194000 0x4000>;
```

SDHC Overview

```
interrupts = <0 23 0x04>;
clocks = <&clks 164>, <&clks 164>, <&clks 164>;
clock-names = "ipg", "ahb", "per";
pinctrl-names = "default";
pinctrl-0 = <&pinctrl_usdhc2_1>;
cd-gpios = <&gpio2 2 0>;
wp-gpios = <&gpio2 3 0>;
bus-width = <8>;
no-1-8-v;
keep-power-in-suspend;
enable-sdio-wakeup;
status = "okay";
};
```

For more information, see:

The binding document at [linux/Documentation/devicetree/bindings/mmc/fsl-imx-esdhc.txt](#).

[arch/arm/boot/dts/imx6qdl.dtsi](#)

[arch/arm/boot/dts/imx6qdl-sabresd.dtsi](#)

Support of SD3.0

SD3.0 requires 3.3V and 1.8V for signal voltage. Voltage selection needs to be implemented on your platform.

Support of SDIO

In most cases, SDIO requires more power than SD/MMC memory cards. Make sure that the power supply is in the SD slot while using SDIO, or apply an external power to SDIO instead.

Chapter 5

Configuring the SPI NOR Flash Memory Technology Device (MTD) Driver

5.1 SPI NOR Overview

This chapter describes how to set up the SPI NOR Flash memory technology device (MTD) driver.

This driver uses the SPI interface to support the SPI-NOR data Flash devices. By default, the SPI NOR Flash MTD driver creates static MTD partitions.

The NOR MTD implementation provides necessary information for the upper-layer MTD driver.

5.2 Source Code Structure

The SPI NOR MTD driver is implemented in the following file:

```
linux/drivers/mtd/devices/m25p80.c
```

Since the size is only 4 MB, we do not implement partitions for the SPI NOR.

5.2.1 Configuration Options

Freescale's BSP supports the following SPI NOR Flash models.

- "M25P32-VMW3TGB" "m25p32"

Those models are defined in the structure

```
static const struct spi_device_id m25p_ids[],
```

located at

```
drivers/mtd/devices/m25p80.c
```

5.2.2 Selecting SPI NOR on the Linux Image

Follow these steps to enable support for SPI NOR:

1. Add the pinctrl for the spi. For example:

```
ecspi1 {
pinctrl_ecspi1_1: ecspi1grp-1 {
    fsl,pins = <
        MX6Q_PAD_EIM_D17__ECSPI1_MISO 0x100b1
        MX6Q_PAD_EIM_D18__ECSPI1_MOSI 0x100b1
        MX6Q_PAD_EIM_D16__ECSPI1_SCLK 0x100b1
    >;
};
pinctrl_ecspi1_2: ecspi1cr-1 {
    fsl,pins = <
        MX6Q_PAD_KEY_COL1__ECSPI1_MISO 0x100b1
        MX6Q_PAD_KEY_ROW0__ECSPI1_MOSI 0x100b1
        MX6Q_PAD_KEY_COL0__ECSPI1_SCLK 0x100b1
    >;
};
};
```

2. Enable the SPI. For example:

```
ecspi@02008000 { /* eCSPI1 */
    fsl,spi-num-chipselects = <1>;
    cs-gpios = <&gpio3 19 0>;
    pinctrl-names = "default";
    pinctrl-0 = <&pinctrl_ecspi1_1 &pinctrl_ecspi1_sabreauto>;
    status = "okay"; /* pin conflict with WEIM NOR */

    flash: m25p80@0 {
        #address-cells = <1>;
        #size-cells = <1>;
        compatible = "st,m25p32";
        spi-max-frequency = <20000000>;
        reg = <0>;
    };
};
```

5.3 Changing the SPI Interface Configuration

The i.MX 6 SoC has five ECSPI interfaces. By default, the BSP configures ECSPI-1 interface in the master mode to connect to the SPI NOR Flash.

5.4 Hardware Operation

SPI NOR Flash is SPI compatible with frequencies up to 66 MHz.

The memory is organized in pages of 512 bytes or 528 bytes. SPI NOR Flash also contains two SRAM buffers of 512/528 bytes each, which allows data reception while a page in the main memory is being reprogrammed. It also allows the writing of a continuous data stream.

Unlike conventional Flash memories that are accessed randomly, the SPI NOR Flash accesses data sequentially. It operates from a single 2.7-3.6 V power supply for program and read operations.

SPI NOR Flashes are enabled through a chip select pin and accessed through a three-wire interface: serial input, serial output, and serial clock.

5.4.1 Software Operation

In a Flash-based embedded Linux system, a number of Linux technologies work together to implement a file system.

The following figure illustrates the relationships between standard components.

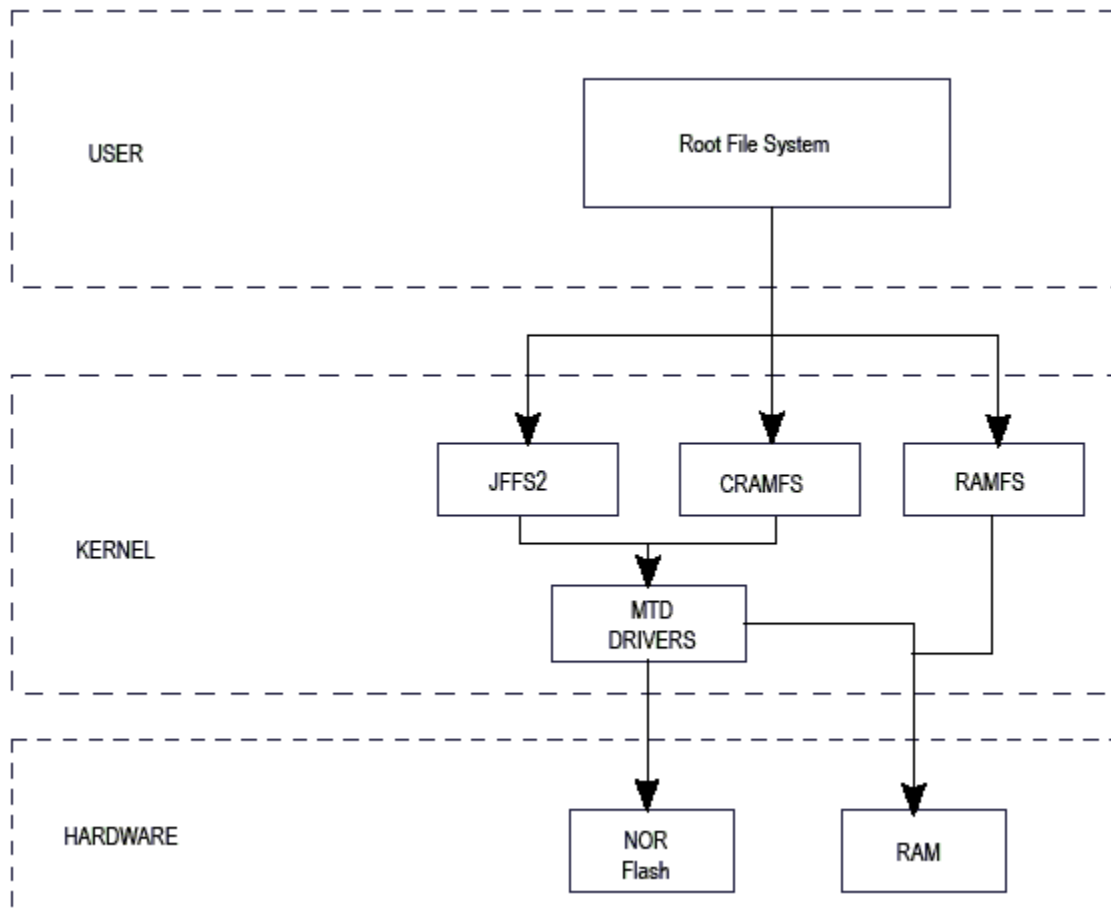


Figure 5-1. Components of a Flash-based file system

The MTD subsystem for Linux is a generic interface to memory devices such as Flash and RAM which provides simple read, write, and erase access to physical memory devices. Devices called mtdblock devices can be mounted by JFFS, JFFS2, and CRAMFS file systems. The SPI NOR MTD driver is based on the MTD data Flash driver in the kernel by adding SPI accesses.

In the initialization phase, the SPI NOR MTD driver detects a data Flash by reading the JEDEC ID. The driver then adds the MTD device. The SPI NOR MTD driver also provides the interfaces to read, write, erase NOR Flash.

Chapter 6

Connecting an LVDS Panel to an i.MX 6Dual/6Quad/6Solo/6DualLite Reference Board

6.1 LVDS Overview

This chapter describes how to connect the LVDS panel to an i.MX 6Dual/6Quad/6Solo/6DualLite reference board. The i.MX 6Dual/6Quad/6Solo/6DualLite processor has an LVDS display bridge (LDB) block that drives LVDS panels without external bridges. The LDB supports the flow of synchronous RGB data from the IPU to external display devices through the LVDS interface. This support covers the following activities:

- Connectivity to relevant devices-display with an LVDS receiver.
- Arranging the data as required by the external display receiver and by LVDS display standards.
- Synchronization and control capabilities.

6.1.1 Connecting an LVDS Panel to the i.MX 6Dual/6Quad/6DualLite Reference Board

The following LVDS panels were tested on the i.MX 6Dual/6Quad/6DualLite reference boards:

- HannStar display (model number: HSD100PXN1)

The kernel command line for 24-bit LVDS panels (4 pairs of LVDS data signals) displays the following lines if the panel is properly connected:

```
LVDS0 and LVDS1 on the board: video=mxcfb0:dev=ldb,LDB-XGA,if=RGB24 video=mxcfb1:dev=ldb,LDB-XGA,if=RGB24 ldb=sep0
```

The kernel command line for 18-bit LVDS panels (3 pairs of LVDS data signals) displays the following lines if the panel is properly connected:

```
LVDS0 and LVDS1 on the board: video=mxcfb0:dev=ldb,LDB-XGA,if=RGB666 video=mxcfb1:dev=ldb,LDB-XGA,if=RGB666 ldb=sep0
```

6.2 Enabling an LVDS Channel

The LDB driver source code is available at `linux/drivers/video/mxc/ldb.c`.

When the LDB device is probed by the mxc display core driver, the driver uses platform data information from DTS file to configure the LDB's reference resistor mode and also tries to match video modes for external display devices with an LVDS interface. The display signal polarities and LDB control bits are set according to the matched video modes.

The LVDS channel mapping mode and the LDB bit mapping mode of LDB are set according to the boot up LDB option chosen by the user.

An LVDS channel is enabled as follows:

1. Set the parent clock of `ldb_di_clk` and the parent clock rate.
2. Set the rate of `ldb_di_clk`.
3. Set the LDB in a proper mode, including display signals' polarities, LVDS channel mapping mode, bit mapping mode, and reference resistor mode.
4. Enable both `ldb_di_clk` and its parent clock.

6.2.1 Locating Menu Configuration Options

Linux kernel configuration options are provided for the build-in status to enable this module. To locate these options, perform the following steps:

1. Go to the root of the kernel tree.
2. Make `menuconfig`.
3. Follow this sequence: Device Drivers > Graphics support > MXC Framebuffer support > Synchronous Panel Framebuffer > MXC LDB

6.3 LDB Ports

The following figure shows the LDB block.

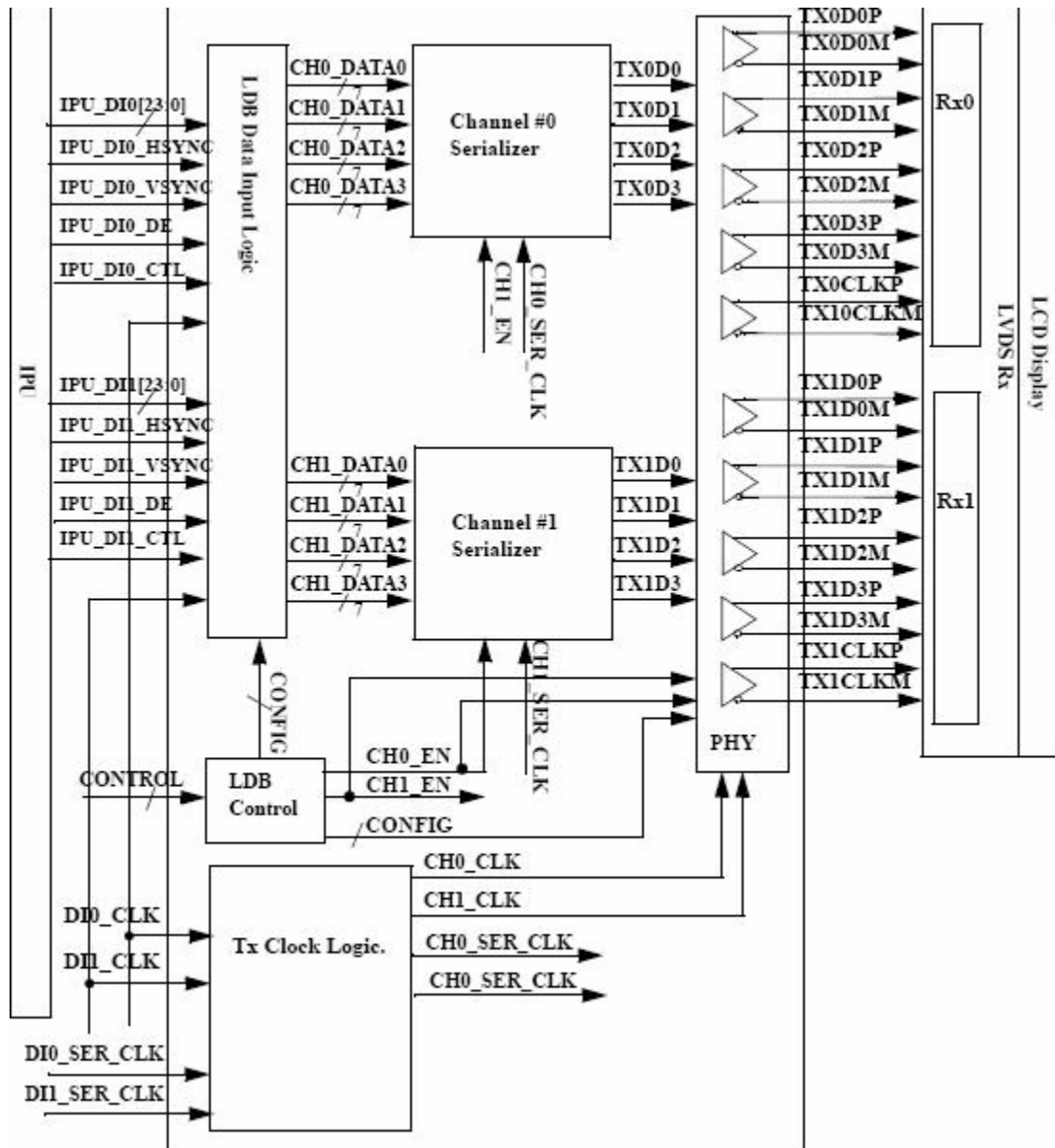


Figure 6-1. i.MX 6 LVDS Display Bridge (LDB) Block

The LDB has the following ports:

- Two input parallel display ports.
- Two output LVDS channels
- Control signals to configure LDB parameters and operations.
- Clocks from the SoC PLLs.

6.3.1 Input Parallel Display Ports

The LDB is configurable to support either one or two (DI0, DI1) parallel RGB input ports. The LDB only supports synchronous access mode.

Each RGB data interface contains the following:

- RGB data of 18 or 24 bits
- Pixel clock
- Control signals
- HSYNC, VSYNC, DE, and one additional optional general purpose control
- Transfers a total of up to 28 bits per data interface per pixel clock cycle

The LDB supports the following data rates:

- For dual-channel output: up to 170 MHz pixel clock (such as UXGA-1600 x 1200 at 60 Hz + 35% blanking)
- For single-channel output: up to 85 MHz per interface. (such as WXGA-1366 x 768 at 60 Hz + 35% blanking).

6.3.2 Output LVDS Ports

The LDB has two LVDS channels, which are used to communicate RGB data and controls to external LCD displays either through the LVDS interface or through LVDS receivers. Each channel consists of four data pairs and one clock pair, with a pair indicating an LVDS pad that contains PadP and PadM.

The LVDS ports may be used as follows:

- One single-channel output
- One dual channel output: single input, split to two output channels
- Two identical outputs: single input sent to both output channels
- Two independent outputs: two inputs sent, each to a distinct output channel

6.4 Additional Information

For additional information, see the following reference materials:

- i.MX 6 Multimedia Applications Processor Reference Manual
- i.MX 6 Linux Reference Manual, included as a part of the Linux BSP

Chapter 7

Supporting the i.MX 6Dual/6Quad/6Solo/6DualLite Camera Sensor with CSI

7.1 CSI Overview

This chapter provides information about how to use the expansion connector to include support for a new camera sensor on an i.MX 6Dual/6Quad/6DualLite reference board.

It describes the following operations:

- Configuring the CSI unit in test mode ([Configuring the CSI Unit in Test Mode](#))
- Adding support for a new CMOS sensor in the i.MX 6Dual/6Quad/6Solo/6DualLite BSP ([Adding Support for a New CMOS Camera Sensor](#))
- Setting up and using the I²C interface to handle your camera bus ([Using the I²C Interface](#))
- Loading and testing the camera module ([Loading and Testing the Camera Module](#))

It also provides reference information about the following:

- Required software and hardware
- i.MX 6Dual/6Quad/6Solo/6DualLite reference CSI interfaces layout ([i.MX 6Dual/6Quad/6Solo/6DualLite CSI Interfaces Layout](#))
- CMOS sensor interfaces (CSI) supported by the i.MX 6Dual/6Quad/6Solo/6DualLite (IPU) ([CMOS Interfaces Supported by the i.MX 6Dual/6Quad/6Solo/6DualLite](#))
- i.MX 6Dual/6Quad/6Solo/6DualLite SABRE-SD CSI parallel interface ([i.MX 6Dual/6Quad/6Solo/6DualLite CSI Parallel Interface](#))
- i.MX 6Dual/6Quad/6Solo/6DualLite CSI test mode ([Timing Data Mode Protocols](#))

7.1.1 Required Software

In Freescale BSPs, all capture devices support the V4L2 standard.

Therefore, only the CMOS-dependent layer needs to be modified to include a new CMOS sensor. All other layers have been developed to work with V4L2.

Required development tools are as follows:

- i.MX 6 Linux L3.10.9 or newer

7.1.2 i.MX 6Dual/6Quad/6Solo/6DualLite CSI Interfaces Layout

The following figure shows the camera interface layout on an i.MX 6Solo/6DualLite SABRE-SD board.

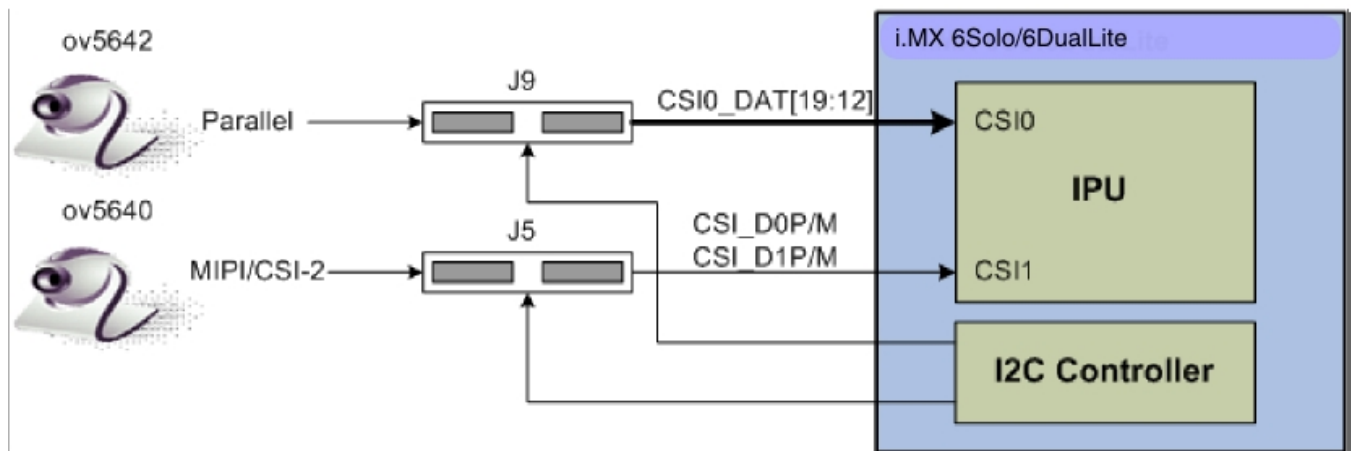


Figure 7-1. Camera Interface Layout

CSI0 is used as a parallel sensor input interface. CSI1 is used as a MIPI sensor input interface.

7.1.3 Configuring the CSI Unit in Test Mode

This chapter uses the test mode for its example scenario of a new camera driver that generates a chess board.

When you set the TEST_GEN_MODE register, the device is in test mode, which is used for debugging. The CSI generates a frame automatically and sends it to one of the destination units. The sent frame is a chess board composed of black and configured color squares. The configured color is set with the registers PG_B_VALUE, PG_G_VALUE, and PG_R_VALUE. The data can be sent in different frequencies according to the configuration of DIV_RATIO register.

When CSI is in test mode, configure the CSI unit with a similar configuration to the described settings in the following table. Call `ipu_csi_init_interface()` to configure the CSI interface protocol, formats, and features.

Table 7-1. Settings for Test Mode

Bit Field	Value	Description
CSI0_DATA_DEST	0x4	Destination is IDMAC via SMFC
CSI0_DIV_RATIO	0x0	SENSB_MCLK rate = HSP_CLK rate
CSI0_EXT_VSYNC	0x1	External VSYNC mode
CSI0_DATA_WIDTH	0x1	8 bits per color
CSI0_SENS_DATA_FORMAT	0x0	Full RGB or YUV444
CSI0_PACK_TIGHT	0x0	Each component is written as a 16 bit word where the MSB is written to bit #15. Color extension is done for the remaining least significant bits.
CSI0_SENS_PRTCL	0x1	Non-gated clock sensor timing/data mode.
CSI0_SENS_PIX_CLK_POL	0x1	Pixel clock is inverted before applied to internal circuitry.
CSI0_DATA_POL	0x0	Data lines are directly applied to internal circuitry.
CSI0_HSYNC_POL	0x0	HSYNC is directly applied to internal circuitry.
CSI0_VSYNC_POL	0x0	VSYNC is directly applied to internal circuitry.

7.2 Adding Support for a New CMOS Camera Sensor

To add support for a new CMOS camera sensor to your BSP, create a device driver to support it.

This device driver is the optimal location for implementing initialization routines, the power up sequence, power supply settings, the reset signal, and other desired features for your CMOS sensor. It is also the optimal location to set the parallel protocol used between the camera and the i.MX 6Dual/6Quad/6Solo/6DualLite.

Perform the following three steps on the i.MX 6Dual/6Quad/6Solo/6DualLite BSP to create a device driver:

1. Add a camera sensor entry in Kconfig.
2. Create the camera file.
3. Add compilation flag for the new camera sensor.

These steps are described in detail in the following subsections.

7.2.1 Adding a Camera Sensor Entry in Kconfig

Select specific camera drivers in the following location (as shown in figure below):

Adding Support for a New CMOS Camera Sensor

Device Drivers > Multimedia support > Video capture adapters V4L platform devices > MXC Video For Linux Camera > MXC Camera/V4L2 PRP Features support

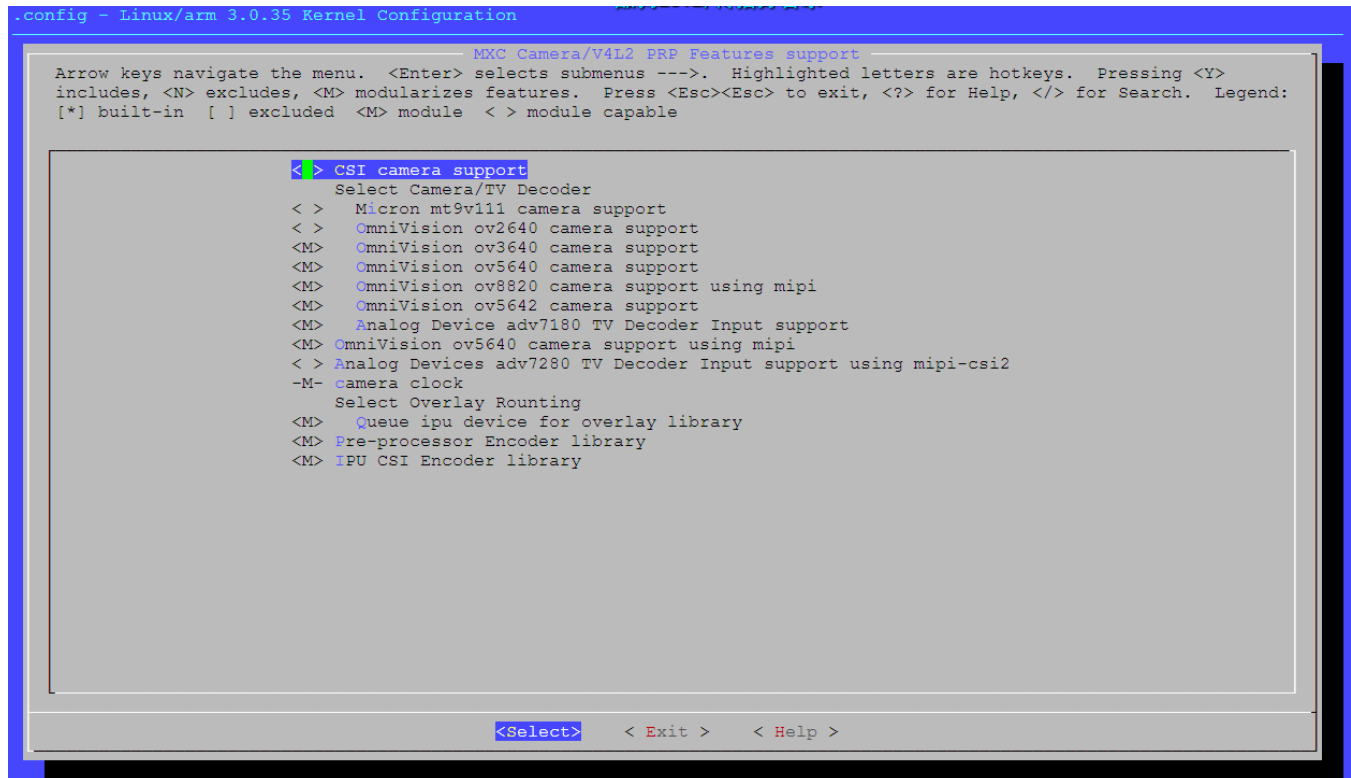


Figure 7-2. MXC Camera/V4L2 PRP Features Support Window

To add a new camera sensor entry on the Kconfig camera file, perform the following steps:

1. Enter the following command into the display specific folder:

```
$ cd linux/drivers/media/video/mxc/capture
```

2. Open the Kconfig file:

```
$ gedit Kconfig &
```

3. Add the entry where you want it to appear:

```
config MXC_IPUV3_CSI0_TEST_MODE
    tristate "IPUv3 CSI0 test mode camera support"
    depends on !VIDEO_MXC_EMMA_CAMERA
    ---help---
    If you plan to use the IPUv3 CSI0 in test mode with your MXC
    system, say Y here.
```

7.2.2 Creating the Camera Sensor File

The camera sensor file enables camera initialization, reset signal generation, power settings, and all sensor-specific code.

NOTE

Before connecting a camera sensor to the i.MX 6Dual/6Quad/6Solo/6DualLite board, you must check whether the sensor is powered with the proper supply voltages and whether the sensor data interface has the correct VIO value. Power supply mismatches can damage either the CMOS or the i.MX 6Dual/6Quad/6Solo/6DualLite.

Create a file with the required panel-specific functions in the following path:

```
linux/drivers/media/video/mxc/capture/
```

The camera file `ipuv3_csi0_chess.c` must include the functions described in table below and may include additional functions and macros required for your driver.

Table 7-2. Required Functions

Function Name	Function Declaration	Description
<code>ioctl_g_ifparm</code>	<code>static int ioctl_g_ifparm(struct v4l2_int_device *s, struct v4l2_ifparm *p)</code>	V4L2 sensor interface handler for <code>VIDIOC_G_PARM</code> ioctl
<code>ioctl_s_power</code>	<code>static int ioctl_s_power(struct v4l2_int_device *s, int on)</code>	V4L2 sensor interface handler for <code>VIDIOC_S_POWER</code> ioctl. Sets sensor module power mode (on or off)
<code>ioctl_g_parm</code>	<code>static int ioctl_g_parm(struct v4l2_int_device *s, struct v4l2_streamparm *a)</code>	V4L2 sensor interface handler for <code>VIDIOC_G_PARM</code> ioctl. Get streaming parameters.
<code>ioctl_s_parm</code>	<code>static int ioctl_s_parm(struct v4l2_int_device *s, struct v4l2_streamparm *a)</code>	V4L2 sensor interface handler for <code>VIDIOC_S_PARM</code> ioctl. Set streaming parameters.
<code>ioctl_g_fmt_cap</code>	<code>static int ioctl_g_fmt_cap(struct v4l2_int_device *s, struct v4l2_format *f)</code>	Returns the sensor's current pixel format in the <code>v4l2_format</code> parameter.
<code>ioctl_g_ctrl</code>	<code>static int ioctl_g_ctrl(struct v4l2_int_device *s, struct v4l2_control *vc)</code>	V4L2 sensor interface handler for <code>VIDIOC_G_CTRL</code> . If the requested control is supported, returns the control's current value from the <code>video_control[]</code> array. Otherwise, it returns <code>-EINVAL</code> if the control is not supported.
<code>ioctl_s_ctrl</code>	<code>static int ioctl_s_ctrl(struct v4l2_int_device *s, struct v4l2_control *vc)</code>	V4L2 sensor interface handler for <code>VIDIOC_S_CTRL</code> . If the requested control is supported, it sets the control's current value in HW (and updates the <code>video_control[]</code> array). Otherwise, it returns <code>-EINVAL</code> if the control is not supported.
<code>ioctl_init</code>	<code>static int ioctl_init(struct v4l2_int_device *s)</code>	V4L2 sensor interface handler for <code>VIDIOC_INT_INIT</code> . Initialize sensor interface.
<code>ioctl_dev_init</code>	<code>static int ioctl_dev_init(struct v4l2_int_device *s)</code>	Initializes the device when slave attaches to the master.
<code>ioctl_dev_exit</code>	<code>static int ioctl_dev_exit(struct v4l2_int_device *s)</code>	De-initializes the device when slave detaches to the master.

After the functions have been created, you need to add additional information to `ipuv3_csi0_chess_slave` and `ipuv3_csi0_chess_int_device`. The device uses this information to register as a V4L2 device.

The following ioctl function references are included:

```
static struct v4l2_int_slave ipuv3_csi0_chess_slave = {
    .ioctls = ipuv3_csi0_chess_ioctl_desc,
    .num_ioctls = ARRAY_SIZE(ipuv3_csi0_chess_ioctl_desc),
};

static struct v4l2_int_device ipuv3_csi0_chess_int_device = {
    ...
    .type = v4l2_int_type_slave,
    ...
};

static int ipuv3_csi0_chess_probe(struct i2c_client *client, const struct i2c_device_id *id)
{
    ...
    retval = v4l2_int_device_register(&ipuv3_csi0_chess_int_device);
    ...
}
```

It is also necessary to modify other files to prepare the BSP for CSI test mode. Change the sensor pixel format from YUV to RGB565 in the `ipu_bg_overlay_sdc.c` file so that the image converter will not perform color space conversion and the input received from the CSI test mode generator will be sent directly to the memory. Additionally, modify `mxc_v4l2_capture.c` to preserve CSI test mode settings which are set by the `ipuv3_csi0_chess_init_mode()` function in the `ipuv3_csi0_chess.c` file.

7.2.3 Adding a Compilation Flag for the New Camera

After camera files are created and the Kconfig file has the entry for your new camera, modify the Makefile to create the new camera module during compilation.

The Makefile is located in the same folder as your new camera file and Kconfig: `linux/drivers/media/video/mxc/capture`.

1. Enter the following into the i.MX 6Dual/6Quad/6Solo/6DualLite camera support folder:

```
$ cd linux/drivers/media/video/mxc/capture
```

2. Open the i.MX 6Dual/6Quad/6Solo/6DualLite camera support Makefile.

```
$ gedit Makefile &
```

3. Add the cmos driver compilation entry to the end of the Makefile.

```
ipuv3_csi0_chess_camera-objs := ipuv3_csi0_chess.o
obj-$(CONFIG_MXC_IPUV3_CSI0_TEST_MODE) += ipuv3_csi0_chess_camera.o
```

The kernel object is created by using the `ipuv3_csi0_chess.c` file. You should have the following files as output:

- `ipuv3_csi0_chess_camera.mod.c`
- `ipuv3_csi0_chess.o`
- `ipuv3_csi0_chess_camera.o`
- `ipuv3_csi0_chess_camera.mod.o`
- `ipuv3_csi0_chess_camera.ko`

7.3 Using the I²C Interface

Many camera sensor modules require a synchronous serial interface for initialization and configuration.

This section uses the `linux/drivers/media/video/mxc/capture/ov5642.c` file as its example code. This file contains a driver that uses the I²C interface for sensor configuration.

After the I²C interface is running, create a new I²C device to handle your camera bus. If the camera sensor file (called `mycamera.c` in the following example code) is located in the same folder as `ov5642.c`, the code is as follows:

```
struct i2c_client * mycamera_i2c_client;

static s32 mycamera_read_reg(u16 reg, u8 *val);
static s32 mycamera_write_reg(u16 reg, u8 val);

static const struct i2c_device_id mycamera_id[] = {
    {"mycamera", 0},
    {}
};

MODULE_DEVICE_TABLE(i2c, mycamera_id);

static struct i2c_driver mycamera_i2c_driver = {
    .driver = {
        .owner = THIS_MODULE,
        .name = "mycamera",
    },
    .probe = mycamera_probe,
    .remove = mycamera_remove,
    .id_table = mycamera_id,
};

static s32 my_camera_write_reg(u16 reg, u8 val)
{
    u8 au8Buf[3] = {0};
    au8Buf[0] = reg >> 8;
    au8Buf[1] = reg & 0xff;
    au8Buf[2] = val;
    if (i2c_master_send(my_camera_i2c_client, au8Buf, 3) < 0) {
        pr_err("%s:write reg error:reg=%x,val=%x\n",__func__, reg, val);
        return -1;
    }
    return 0;
}
```

Using the I2C Interface

```
static s32 my_camera_read_reg(u16 reg, u8 *val)
{
    u8 au8RegBuf[2] = {0};
    u8 u8RdVal = 0;
    au8RegBuf[0] = reg >> 8;
    au8RegBuf[1] = reg & 0xff;

    if (2 != i2c_master_send(my_camera_i2c_client, au8RegBuf, 2)) {
        pr_err("%s:write reg error:reg=%x\n",__func__, reg);
        return -1;
    }

    if (1 != i2c_master_recv(my_camera_i2c_client, &u8RdVal, 1)) { // @ECA
        pr_err("%s:read reg error:reg=%x,val=%x\n",__func__, reg, u8RdVal);
        return -1;
    }

    *val = u8RdVal;
    return u8RdVal;
}

static int my_camera_probe(struct i2c_client *client, const struct i2c_device_id *id)
{
    ...
    my_camera_i2c_client = client;
    ...
}

static __init int mycamera_init(void)
{
    u8 err;
    err = i2c_add_driver(&mycamera_i2c_driver);
    if (err != 0)
        pr_err("%s:driver registration failed, error=%d \n",__func__, err);
    return err;
}

static void __exit mycamera_clean(void)
{
    i2c_del_driver(&mycamera_i2c_driver);
}

module_init(mycamera_init);
module_exit(mycamera_clean);
```

Check `ov5642.c` for the complete example code.

After creating the new I²C device driver, add a new I2C node to your platform dts file.

You may modify the dts file at this point to specify features about your camera such as the CSI interface used (CSI0 or CSI1), the MCLK frequency, and some power supply settings related to the module.

You can now read and write from/to the sensor in the camera sensor file by using the following:

```
retval = mycamera_write_reg(RegAddr, Val);
retval = mycamera_read_reg(RegAddr, &RegVal);
```

7.3.1 Loading and Testing the Camera Module

If your camera driver has been created as a kernel module, as in the example in this chapter, the module must be loaded prior to any camera request attempt.

According to the Makefile information, the camera module is named `ipuv3_csi0_chess_camera.ko`.

To load the V4L2 camera interface and CSI in test mode, execute the following commands:

```
root@freescale /unit_tests$ modprobe ipuv3_csi0_chess_camera
root@freescale /unit_tests$ modprobe mxc_v4l2_capture
```

To test the video0 input (camera), an `mxc_v4l2_overlay` test is included in the BSP. If the `imx-test` package has also been included, open the unit test folder and execute the test.

```
root@freescale ~$ cd /unit_tests/
root@freescale /unit_tests$ ./mxc_v4l2_overlay.out
```

7.4 Additional Reference Information

This section provides reference information about the following:

- [CMOS Interfaces Supported by the i.MX 6Dual/6Quad/6Solo/6DualLite](#)
- [i.MX 6Dual/6Quad/6Solo/6DualLite CSI Parallel Interface](#)
- [Timing Data Mode Protocols](#)

7.4.1 CMOS Interfaces Supported by the i.MX 6Dual/6Quad/6Solo/6DualLite

The camera sensor interface, which is a part of the image processing unit (IPU) module on the i.MX 6Dual/6Quad/6Solo/6DualLite, handles CMOS sensor interfaces. The i.MX 6Dual/6Quad/6Solo/6DualLite IPU is able to handle two camera devices through its CSI ports: one connected to the CSI0 port and the other to the CSI1 port. Both CSI ports are identical and provide glueless connectivity to a wide variety of raw/smart sensors and TV decoders.

Each of the camera ports includes the following features:

- Parallel interface
 - Up to 20-bit input data bus

Additional Reference Information

- A single value in each cycle
- Programmable polarity
- Multiple data formats
 - Interleaved color components, up to 16 bits per value (component)
 - Input Bayer RGB, Full RGB, or YUV 4:4:4, YUV 4:2:2 Component order:UY1VY2 or Y1UY2V, grayscale and generic data
- Scan order: progressive or interlaced
- Frame size: up to 8192 x 4096 pixels
- Synchronization-video mode
 - The sensor is the master of the pixel clock (PIXCLK) and synchronization signals.
 - Synchronization signals are received by using either of the following methods:
 - Dedicated control signals-VSYNC, HSYNC-with programmable pulse width and polarity.
 - Controls embedded in the data stream following loosely the BT.656 protocol with flexibility in code values and location.
 - The image capture is triggered by the MCU or by an external signal (such as a mechanical shutter).
 - Synchronized strobes are generated for up to six outputs-the sensor and camera peripherals (flash, mechanical shutter...).
- Frame rate reduction by periodic skipping of frames.

For details, refer to the "Image Processing Unit (IPU)" chapter in the *i.MX 6Dual/6Quad Applications Processor Reference Manual*, or in the *i.MX 6Solo/6DualLite Applications Processor Reference Manual*.The following figure shows the block diagram.

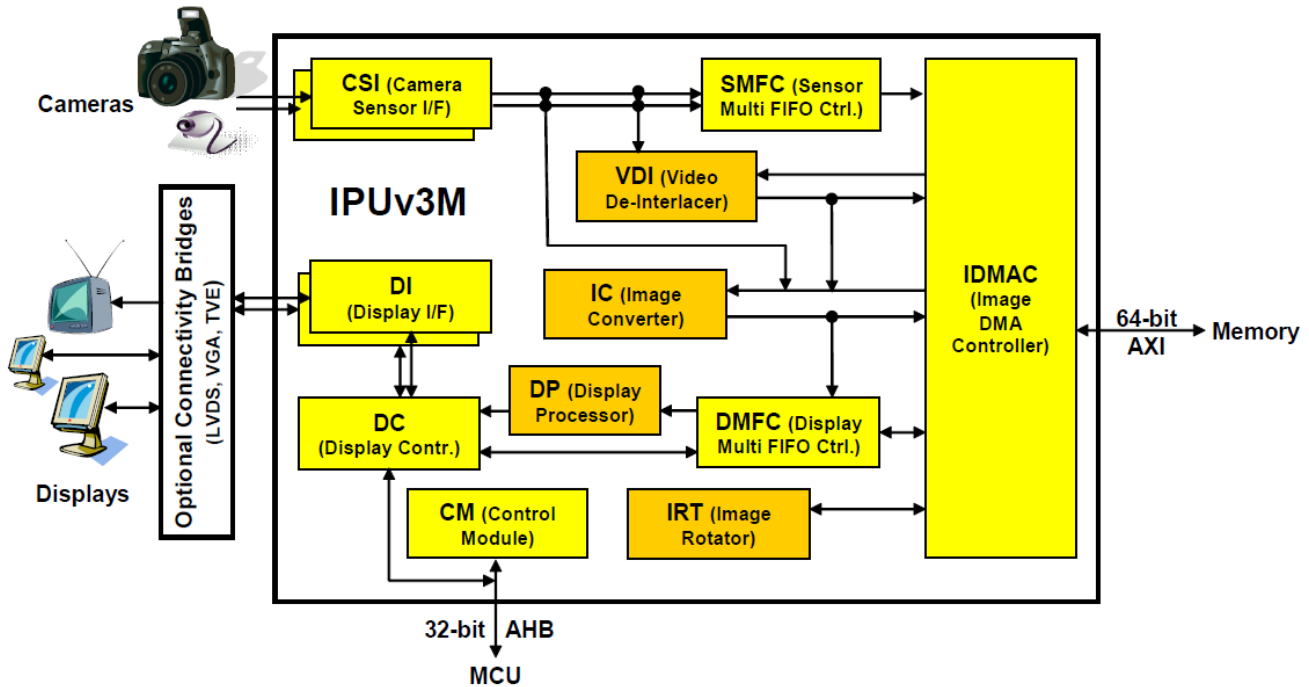


Figure 7-3. IPU Block Diagram

Several sensors can be connected to each of the CSIs. Simultaneous functionality (for sending data) is supported as follows:

- Two sensors can send data independently, each through a different port.
- One stream can be transferred to the VDI or IC for on-the-fly processing while the other one is sent directly to system memory.

The input rate supported by the camera port is as follows:

- Peak: up to 180 MHz (values/sec).
- Average (assuming 35% blanking overhead) for YUV 4:2:2.
 - Pixel in one cycle (BT.1120): up to 135 MP/sec, such as 9 Mpixels at 15 fps.
 - Pixel on two cycles (BT.656): up to 67 MP/sec, such as 4.5 Mpixels at 15 fps.
- On-the-fly processing may be restricted to a lower input rate.

If required, additional cameras can be connected though the USB port.

7.4.2 i.MX 6Dual/6Quad/6Solo/6DualLite CSI Parallel Interface

The CSI obtains data from the sensor, synchronizes the data and the control signals to the IPU clock (HSP_CLK), and transfers the data to the IC and/or SMFC.

The CSI parallel interface (shown in figure below) provides a clock output (MCLK), which is used by the sensor as a clock input reference. The i.MX 6Dual/6Quad/6Solo/6DualLite requests either video or still images through a different interface between the processor and the camera module. In most cases, the interface is a synchronous serial interface such as the I²C. After the frame has been requested, the camera module takes control of the CSI bus, and uses synchronization signals VSYNC, HSYNC, DATA_EN and PIXCLK to send the image frame to the i.MX 6Dual/6Quad/6Solo/6DualLite. The camera sensor creates PIXCLK based on MCLK input.

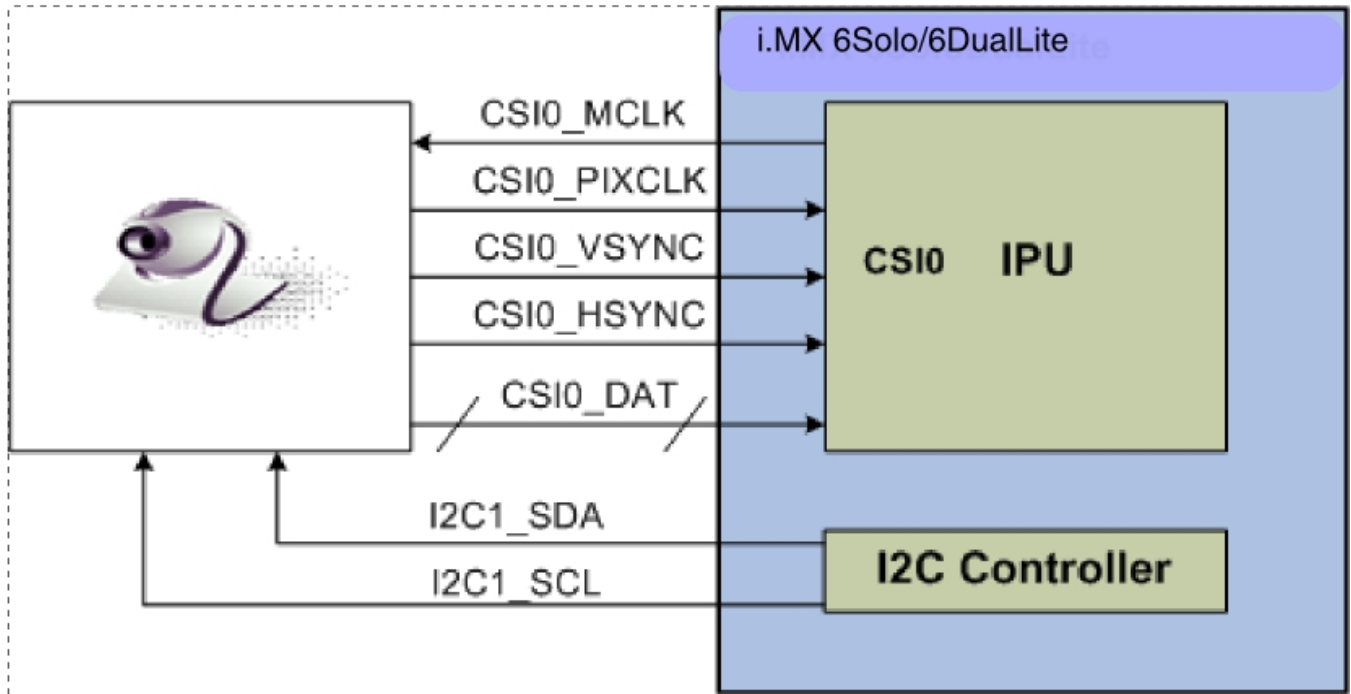


Figure 7-4. Parallel Interface Layout

In parallel interface, a single value arrives in each clock, except in BT.1120 mode when two values arrive per cycle. Each value can be 8-16 bits wide according to the configuration of DATA_WIDTH. If DATA_WIDTH is configured to N, then 20-N LSB bits are ignored.

Therefore, you never need CSIO_DAT[3:0], unless you are using BT.1120 mode, because the maximum pixel width is 16 (CSIO_DAT[19:4]). The expansion port 2 includes CSIO_DAT[19:4], but only CSIO_DAT[19:10] are used for the CSI data bus (10-bit wide data). CSIO_DAT[9:4] are shared with other interfaces and are used for audio and I²C.

CSI can support several data formats according to SENS_DATA_FORMAT configuration. When the data format is YUV, the output of the CSI is always YUV444-even if the data arrives in YUV422 format.

The polarity of the inputs can be configured using the following registers:

- SENS_PIX_CLK_POL
- DATA_POL
- HSYNC_POL
- VSYNC_POL

The following table describes the camera parallel interface provided by the i.MX 6Dual/6Quad/6Solo/6DualLite:

Table 7-3. CSI0 Parallel Interface Signals

Signal	IPU Pin	Description
MCLK	CSI0_MCLK	Master Clock (Output)
PIXCLK	CSI0_PIXCLK	Pixel Clock
VSYNC	CSI0_VSYNC	Vertical Synchronization signal
HSYNC	CSI0_HSYNC	Horizontal Synchronization signal
DATA_EN	CSI0_DATA_EN	Data Enable or Data ready
DATA[19:10]	CSI0_DAT [19:10]	Pixel data bus, optional to [19:4]

[Timing Data Mode Protocols](#), explains how the timing data mode protocols use these signals. Not all signals are used in each timing data mode protocol.

7.4.3 Timing Data Mode Protocols

The CSI interface supports the following four timing/data protocols:

- Gated mode
- Non-gated mode
- BT.656 (Progressive and interlaced)
- BT.1120 (Progressive and interlaced)

In gated mode, VSYNC is used to indicate beginning of a frame, and HSYNC is used to indicate the beginning of a row. The sensor clock is always ticking.

In non-gated mode, VSYNC is used to indicate beginning of a frame, and HSYNC is not used. The sensor clock only ticks when data is valid.

In BT.656 mode, the CSI works according to recommendation ITU-R BT.656. The timing reference signals (frame start, frame end, line start, line end) are embedded in the data bus input.

In BT1120 mode, the CSI works according to recommendation ITU-R BT.1120. The timing reference signals (frame start, frame end, line start, line end) are embedded in the data bus input.

Additional Reference Information

For details, refer to the *i.MX 6Dual/6Quad Applications Processor Reference Manual* or the *i.MX 6Solo/6DualLite Applications Processor Reference Manual*.

Chapter 8

Porting Audio Codecs to a Custom Board

8.1 Audio Overview

This chapter describes how to port audio drivers from the Freescale reference BSP to a custom board.

This procedure varies depending on whether the audio codec on the custom board is the same as, or different than the audio codec on the Freescale reference design. This chapter first describes the common porting task and then various other porting tasks.

8.1.1 Common Porting Task

In order to use the ALSA Audio function, CPU DAI driver, CODEC DAI driver and DAI LINK driver (Machine driver) should be registered in the device tree, and accordingly there must be three nodes in board specified dts file. An example of detailed nodes can be found in arch/arm/boot/dts/imx6qdl-sabresd.dtsi:

```
/* DT binding for CPU DAI driver */
ssi2: ssi@0202c000 {
    fsl,mode = "i2s-slave";
    status = "okay";
};

/* DT binding for CODEC DAI driver */
codec: wm8962@1a {
    compatible = "wlf,wm8962";
    reg = <0x1a>;
    clocks = <&clks 169>;
    DCVDD-supply = <&reg_audio>; /* 1.8v */
    DBVDD-supply = <&reg_audio>; /* 1.8v */
    AVDD-supply = <&reg_audio>; /* 1.8v */
    CPVDD-supply = <&reg_audio>; /* 1.8v */
    MICVDD-supply = <&reg_audio>; /* 3.3v */
    PLLVDD-supply = <&reg_audio>; /* 1.8v */
    SPKVDD1-supply = <&reg_audio>; /* 4.2v */
    SPKVDD2-supply = <&reg_audio>; /* 4.2v */
    gpio-cfg = <
        0x0000 /* 0:Default */
        0x0000 /* 1:Default */
        0x0013 /* 2:FN_DMICCLK */
    >;
};
```

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```
        0x0000 /* 3:Default */
        0x8014 /* 4:FN_DMICCDAT */
        0x0000 /* 5:Default */
    >;
};

/* DT binding for DAI LINK driver */
sound {
    compatible = "fsl,imx6q-sabresd-wm8962",
        "sl,imx-audio-wm8962";
    model = "wm8962-audio";
    si-controller = <&ssi2>;
    uaudio-codec = <&codec>;

    audio-routing =
        "Headphone Jack", "HPOUTL",
        "Headphone Jack", "HPOUTR",
        "Ext Spk", "SPKOUTL",
        "Ext Spk", "SPKOUTR",
        "MICBIAS", "AMIC",
        "IN3R", "MICBIAS",
        "DMIC", "MICBIAS",
        "DMICDAT", "DMIC";
    mux-int-port = <2>;
    mux-ext-port = <3>;
    hp-det-gpios = <&gpio7 8 1>; /*active low*/
    mic-det-gpios = <&gpio1 9 1>; /*active low*/
};
```

NOTE

The specific meaning of the device tree binding can be checked up in binding doc located in Documentation/devicetree/bindings/sound/.

8.1.2 Porting the Reference BSP to a Custom Board (audio codec is the same as in the reference design)

When the audio codec is the same in the reference design and the custom board, ensure that the I/O signals and the power supplies to the codec are properly initialized in order to port the reference BSP to the custom board.

Devicetree uses pin control group for I/O signals' configuration, there are some examples in arch/arm/boot/dts/imx6qdl-sabresd.dtsi and the definitions of those pin control groups can be found in arch/arm/boot/dts/imx6qdl.dtsi.

The essential signals for wm8962 codec are as follows:

- I²C interface signals
- I²S interface signals
- SSI external clock input to wm8962

The following table shows the required power supplies for the wm8962 codec.

Table 8-1. Required Power Supplies

Power Supply Name	Definition	Value
PLLVDD	PLL supply	1.8 V
SPKVDD1	Supply for left speaker drivers	4.2 V
SPKVDD2	Supply for right speaker drivers	4.2 V
DCVDD	Digital core supply	1.8 V
DBVDD	Digital supply	1.8 V
AVDD	Analog supply	1.8 V
CPVDD	Charge pump power supply	1.8 V
MICVDD	Microphone bias amp supply	3.3 V

8.1.3 Porting the Reference BSP to a Custom Board (audio codec is different than the reference design)

When adding support for an audio codec that is different than the one on the Freescale reference design, create new ALSA drivers in order to port the reference BSP to a custom board. The ALSA drivers plug into the ALSA sound framework, which allows the standard ALSA interface to be used to control the codec.

The source code for the ALSA driver is located in the Linux kernel source tree at `linux/sound/soc`. The following table shows the files used for the wm8962 codec support:

Table 8-2. Files for wm8962 Codec Support

File Name	Definition
<code>imx-pcm-dma.c</code>	<ul style="list-style-type: none"> Shared by the stereo ALSA SoC driver, the esai driver, and the spdif driver. Responsible for preallocating DMA buffers and managing DMA channels.
<code>fsl_ssi.c</code>	<ul style="list-style-type: none"> Register the CPU DAI driver for the stereo ALSA SoC Configures the on-chip SSI interfaces
<code>wm8962.c</code>	<ul style="list-style-type: none"> Register the stereo codec and Hi-Fi DAI drivers. Responsible for all direct hardware operations on the stereo codec.
<code>imx-wm8962.c</code>	<ul style="list-style-type: none"> Machine layer code Create the driver device Register the stereo sound card.

NOTE

If using a different codec, adapt the driver architecture shown in table above accordingly. The exact adaptation will depend on the codec chosen. Obtain the codec-specific software from the codec vendor.

Chapter 9

Porting the Ethernet Controller Driver

9.1 Ethernet Controller Overview

This chapter explains how to port the Ethernet controller driver to the i.MX 6 processor.

Using Freescale's standard driver makes porting to the i.MX 6 simple. Porting needs to address the following three areas:

- Pin configuration
- Source code
- Ethernet connection configuration

9.1.1 Pin Configuration

The Ethernet Controller supports three different standard physical media interfaces: a reduced media independent interface (RMII), a media independent interface (MII), and a 4-bit reduced RGMII.

In addition, the Ethernet Controller includes support for different standard MAC-PHY (physical) interfaces for connection to an external Ethernet transceiver. The i.MX Ethernet Controller supports the 10/100 Mbps MII, and 10/100 Mbps RMII. The i.MX 6Dual/6Quad/6Solo/6DualLite FEC also supports 1000 Mbps RGMII, which uses 4-bit reduced GMII operating at 125 MHz.

A brief overview of the device functionality is provided here. For details, see the Ethernet chapter of the *i.MX 6Dual/6Quad/6Solo/6DualLite/6SoloLite Multimedia Applications Processor Reference Manual*.

In MII mode, there are 18 signals defined by the IEEE 802.3 standard and supported by the EMAC. MII, RMII, and RGMII modes use a subset of the 18 signals. These signals are listed in the following table.

Table 9-1. Pin Usage in MII RMII and RGMII Modes

Direction	EMAC Pin Name	MII Usage	RMII Usage	RGMII Usage (not supported by i.MX 6SoloLite)
In/Out	FEC_MDIO	Management Data Input/Output	Management Data Input/output	Management Data Input/Output
Out	FEC_MDC	Management Data Clock	General output	Management Data Clock
Out	FEC_TXD[0]	Data out, bit 0	Data out, bit 0	Data out, bit 0
Out	FEC_TXD[1]	Data out, bit 1	Data out, bit 1	Data out, bit 1
Out	FEC_TXD[2]	Data out, bit 2	Not Used	Data out, bit 2
Out	FEC_TXD[3]	Data out, bit 3	Not Used	Data out, bit 3
Out	FEC_TX_EN	Transmit Enable	Transmit Enable	Transmit Enable
Out	FEC_TX_ER	Transmit Error	Not Used	Not Used
In	FEC_CR_S	Carrier Sense	Not Used	Not Used
In	FEC_COL	Collision	Not Used	Not Used
In	FEC_TX_CLK	Transmit Clock	Not Used	Synchronous clock reference (REF_CLK, can connect from PHY)
In	FEC_RX_ER	Receive Error	Receive Error	Not Used
In	FEC_RX_CLK	Receive Clock	Not Used	Synchronous clock reference (REF_CLK, can connect from PHY)
In	FEC_RX_DV	Receive Data Valid	Receive Data Valid and generate CRS	RXDV XOR RXERR on the falling edge of FEC_RX_CLK.
In	FEC_RXD[0]	Data in, bit 0	Data in, bit 0	Data in, bit 0
In	FEC_RXD[1]	Data in, bit 1	Data in, bit 1	Data in, bit 1
In	FEC_RXD[2]	Data in, bit 2	Not Used	Data in, bit 2
In	FEC_RXD[3]	Data in, bit 3	Not Used	Data in, bit 3

Because i.MX 6 has more functionality than it has physical I/O pins, it uses I/O pin multiplexing.

Every module requires specific pad settings. For each pad there are up to eight muxing options called ALT modes. For further explanation, refer to IOMUX chapter in the *i.MX 6Dual/6Quad/6Solo/6DualLite/6SoloLite Multimedia Applications Processor Reference Manual*.

Please note in designs with an external Ethernet PHY may require an external pin configured as a simple GPIO to reset the Ethernet PHY before enabling physical clock. Otherwise, some PHYs will fail to work correctly.

9.1.2 Source Code

The source code for the Freescale Ethernet Linux environment is located under the `linux/drivers/net/ethernet/freescale/` directory. It contains the following files:

Table 9-2. Source Code Files

File Names	Descriptions
<ul style="list-style-type: none"> • fec.h • fec_main.c • fec_ptp.c 	FEC low-level Ethernet driver:

The driver uses the following compile definitions:

CONFIG_FEC: enables the Ethernet Controller driver.

9.1.3 Ethernet Configuration

This section mainly covers Ethernet driver bring up issues. For more information about Ethernet MAC configuration, refer to *i.MX 6Dual/6Quad/6Solo/6DualLite/6SoloLite Multimedia Applications Processor Reference Manual*.

Note the following during Ethernet driver bring up:

- Configure all I/O pins used by MAC correctly in dts files.
- Check physical input clock and power, physical led1 and led2 lighten on if clock and power input are ok.
- Make sure that MAC tx_clk has the right clock input. Otherwise, MAC cannot work.
- Make sure that the MAC address is set and valid.

By default, the Ethernet driver gets the MAC address from the Ethernet node property "local-mac-address" in dts file. If dts does not have the property, the driver get the MAC address from fuse. If the fuse does not burn the MAC address, the driver gets the MAC address from the Ethernet registers set by the bootloader. If no legal MAC address exists, MAC malfunctions. In this case, add the MAC address in the U-Boot command line for kernel, such as "fec.macaddr=0x00,0x01,0x02,0x03,0x04,0x05" in bootargs.

The Ethernet driver and hardware are designed to comply with the IEEE standards for Ethernet auto-negotiation. See the Ethernet chapter in the *i.MX 6Dual/6Quad/6Solo/6DualLite/6SoloLite Multimedia Applications Processor Reference Manual* for a description of using flow control in full duplex and more.

Chapter 10

Porting USB Host1 and USB OTG

10.1 USB Overview for i.MX 6Dual/6Quad/6Solo/6DualLite

There are up to four USB ports on i.MX 6Dual/6Quad/6Solo/6DualLite serial application processors:

- USB OTG port
- USB H1 port
- USB HSIC1 port
- USB HSIC2 port

NOTE

There is no HSIC2 port on i.MX6SL.

The following power supplies must be provided:

- 5V power supply for USB OTG VBUS
- 5V power supply for USB H1 VBUS
- 3.3V power supply for HSIC1/2 port
- 3.15 +/- 5%V power supply for USB OTG/H1 PHY. Since this power can be routed from USB OTG/H1 VBUS, it indicates that if either of the power supplies is powered up, the USB PHY is powered as well. However, if neither can be powered up, an external power supply is needed.

For the USB OTG port, the following signals are used:

- USB_OTG_CHD_B
- USB_OTG_VBUS
- USB_OTG_DN
- USB_OTG_DP
- USBOTG_ID
- USBOTG_OC_B
- one pin is used to control USB_OTG_VBUS signal

The following signals, needed to set with proper IOMUX, are multiplexed with other pins.

NOTE

For the USBOTG_ID pin, a pin which has an alternate USBOTG_ID function must be used.

- USBOTG_ID
- USBOTG_OC_B
- one pin used to control USB_OTG_VBUS signal

For USB H1 port, the following signals are used:

- USB_H1_VBUS
- USB_H1_DN
- USB_H1_DP
- USBH_OC_B

The following signals are multiplexed with other pins, and need to set with proper IOMUX:

- USBH_OC_B

For USB HSIC 1/2 port, the following signals are used:

- H2_STROBE
- H3_STROBE
- H2_DATA
- H3_DATA

The following signals are multiplexed with other pins, and need to set with proper IOMUX:

- H2_STROBE
- H3_STROBE
- H2_DATA
- H3_DATA

To secure HSIC connection, the USB HSIC port must be powered up before the USB HSIC device

For i.MX 6SoloLite, there is only one HSIC port, so only H2_xxx signals are used.

10.2 USB Overview for i.MX 6SoloLite

There are up to three USB ports on i.MX 6 SoloLite serial application processors:

- USB OTG1 port
- USB OTG2 port
- USB HSIC1 port

The following power supplies must be provided:

- 5V power supply for USB OTG1 VBUS
- 5V power supply for USB OTG2 VBUS
- 3.3V power supply for HSIC1 port
- 3.15 +/- 5%V power supply for USB OTG1/OTG2 PHY. Since this power can be routed from USB OTG1/OTG2 VBUS, it indicates that if either of the power supplies is powered up, the USB PHY is powered as well. However, if neither can be powered up, an external power supply is needed.

For the USB OTG1 port, the following signals are used:

- USB_OTG1_CHD_B
- USB_OTG1_VBUS
- USB_OTG1_DN
- USB_OTG1_DP
- USBOTG1_ID
- USBOTG1_OC_B
- one pin is used to control USB_OTG1_VBUS signal

The following signals, needed to set with proper IOMUX, are multiplexed with other pins.

NOTE

For the USBOTG_ID pin, a pin which has an alternate USBOTG_ID function must be used.

- USBOTG_ID
- USBOTG_OC_B
- one pin used to control USB_OTG_VBUS signal

For USB OTG2 port, the following signals are used:

- USB_OTG2_VBUS
- USB_OTG2_DN

- USB_OTG2_DP
- USBOTG2_OC_B

The following signals are multiplexed with other pins, and need to set with proper IOMUX:

- USBOTG2_OC_B

For USB HSIC 1 port, the following signals are used:

- H2_STROBE
- H2_DATA

The following signals are multiplexed with other pins, and need to set with proper IOMUX:

- H2_STROBE
- H2_DATA

To secure HSIC connection, the USB HSIC port must be powered up before the USB HSIC device

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