

# μEZ<sup>®</sup> Software Quickstart Guide



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**FDI** *Future Designs, Inc.*  
*Your Development Partner*  
2702 Triana Boulevard SW, Huntsville, AL 35805

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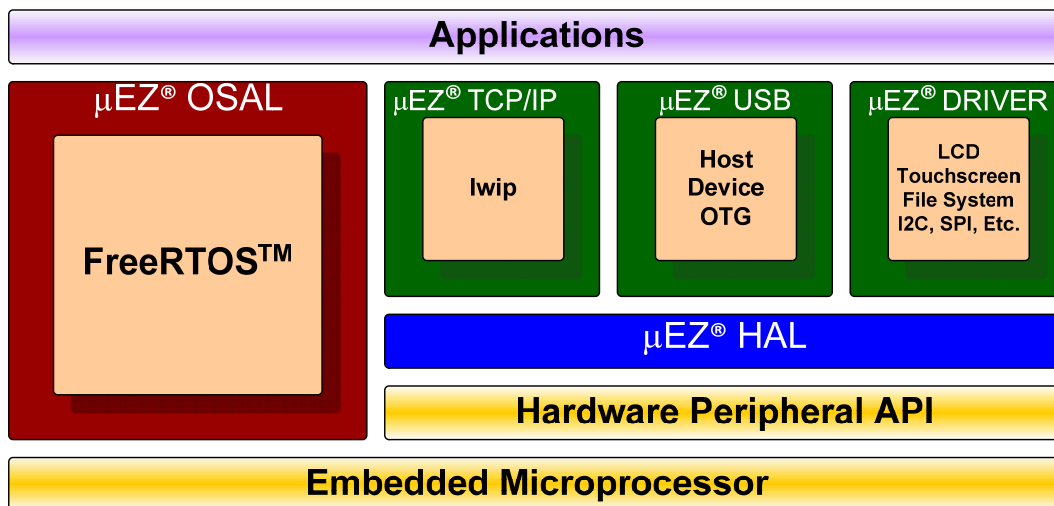
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## 1. Introduction

**μEZ**<sup>®</sup> takes its name from the Muses of Greek mythology. A Muse was a goddess who inspired the creation process for the arts and sciences. Like its ancient Greek namesake, the **μEZ**<sup>®</sup> platform inspires rapid development by supplying customers with an extensive library of open source software, drivers, and processor support - all under a common framework. **μEZ**<sup>®</sup> development works on the premise of "design once, reuse many times". This provides an open source standard for embedded developers to build upon and support. **μEZ**<sup>®</sup> allows companies to focus on innovation and on their own value-added applications while minimizing development time and maximizing software reuse.

The diagram below shows a typical embedded application stack. **μEZ**<sup>®</sup> has three primary categories of components that help simplify embedded application development:

1. **Operating System Abstraction Layer (μEZ<sup>®</sup> OSAL)**
2. **Sub-system drivers (μEZ<sup>®</sup> TCP/IP, μEZ<sup>®</sup> USB, μEZ<sup>®</sup> Driver)**
3. **Hardware Abstraction Layer (μEZ<sup>®</sup> HAL)**



The selection of an RTOS can be one of the most daunting aspects of an embedded system development. With **μEZ**<sup>®</sup> the primary features of common multi-tasking operating systems are abstracted, thus easing the transition to an open source or low-cost RTOS. The **μEZ**<sup>®</sup> OSAL provides applications access to the following features in an OS-independent fashion:

- Pre-emptive multitasking
- Stack overflow detection
- Unlimited number of tasks
- Queues
- Semaphores (binary, counting, mutex)

The **μEZ**<sup>®</sup> sub-system drivers utilize the OSAL functions to provide protected access to the processor peripherals. The sub-system driver API functions are typically protocol layer interfaces (TCP/IP, USB, etc) designed as high-level access routines such as open, close, read, write, etc. where possible.

The HAL functions provide single-threaded unprotected access to the processor peripherals. Customers can use the  $\mu$ EZ<sup>®</sup> HAL routines provided by FDI or they can write their own. The HAL routines provide for RTOS/ $\mu$ EZ<sup>®</sup> independence and allow portability within a family of processors.

$\mu$ EZ<sup>®</sup> is ideally suited for Embedded Systems with standard features such as:

- Processor and Platform BSPs (Board Support Packages)
- Real Time Operating System (RTOS)
- Memory Management
- NAND/NOR Flash
- SDRAM and DDR Memory
- TCP/IP stack
- USB Device/Host Libraries
- Mass Storage Devices
- LCD Displays with Touch Screen
- Input / Output Devices

## 2. Downloading $\mu$ EZ<sup>®</sup>

Start by downloading the latest version of  $\mu$ EZ<sup>®</sup> from <https://sourceforge.net/projects/uez/>. Unzip to a working folder. In this document we will use a simple directory structure of / $\mu$ EZ but the user is free to modify this as desired.

The  $\mu$ EZ<sup>®</sup> file directory structure should be as follows:

Directory	Description
/Build	Projects/makefiles for different applications/demos
/Include	$\mu$ EZ <sup>®</sup> system files and Config.h
/Include/Device	Device Driver class definitions.
/Include/HAL	Hardware Abstraction Layer (HAL) driver class definitions.
/Include/Types	Common data types used by both HAL and Device Drivers.
/Source	Source code
/Source/App	User application source code and demos shared among multiple builds.
/Source/BSP	BSP generic startup code
/Source/Devices/<category>/<manufacturer>/<device>	Device specific code organized by category (I2C, SSP, etc.), manufacturer, and specific device.
/Source/Library/<category>/<package>	Various support libraries organized by category (graphics, file system, etc.) and package name.
/Source/Platform/<manufacturer>/<platform>	Platforms/boards code organized by manufacturer and specific platform build.
/Source/Processor/<manufacturer>/<processor>	Processor specific code in separate directories organized by manufacturer and specific processor.
/Source/RTOS/<RTOS>/	RTOS source code in separate directories
/Source/ $\mu$ EZSystem	$\mu$ EZ <sup>®</sup> System Core routines

### 3. Project Configuration

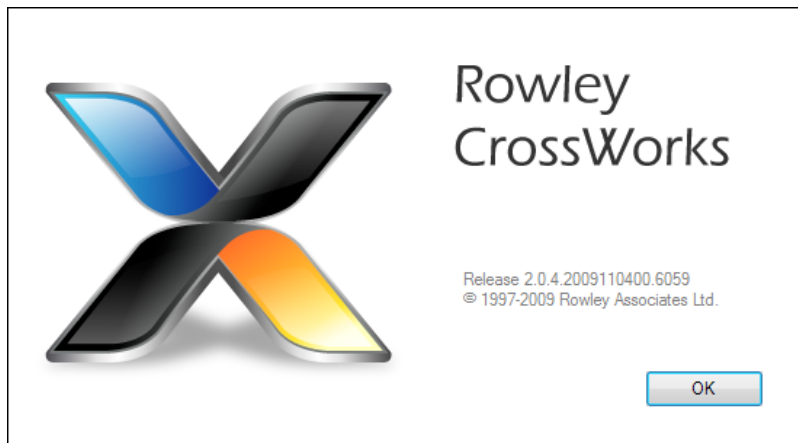
uEZ® uses a simple one project configuration. Depending on the compiler tools, use one of the following subsections.

#### Preparing the uEZ® Source Code

Download the uEZ® v1.11 (or later) source code from <http://www.sourceforge.net/projects/uez>. Unzip the file to where you will be working. It should create a folder called /UEZ\_SRC.

#### Rowley CrossWorks CrossStudio v2.0 Project Configuration Check CrossStudio Version

uEZ® is built using v2.0, or later, of the Rowley CrossWorks CrossStudio for ARM® toolset. To confirm the version number of the tools, go to Help->About in the main menu and the version number should appear in the middle of the dialog.



Build versions of 2.0.x are acceptable.

#### Check Installed Packages

In addition, packages for your target processor(s) should be installed. Go to **Tools->Show Installed Packages** and see which packages have been installed. For example,

## Installed Packages

The following support packages have been installed, click on the links to get more information on each package and its contents:

Package	Version	Status
<a href="#">Generic ARM CPU Support Package</a>	1.3	Installed
<a href="#">NXP LPC1000 CPU Support Package</a>	1.7	Installed
<a href="#">NXP LPC2000 CPU Support Package</a>	1.30	Installed

If doing development for the DK-TS-KIT with the SOMDIMM-LPC2478, the following packages should be installed:

- Generic ARM® CPU Support Package
- NXP LPC2000 CPU Support Package

If doing development for the DK-TS-KIT with the SOMDIMM-LPC1788, the following packages should be installed:

- Generic ARM® CPU Support Package

## NXP LPC1000 CPU Support Package

If the packages are not installed, go to **Tools->Download Packages from Web**, download the missing packages, and then use **Tools->Install Package...** to install them.

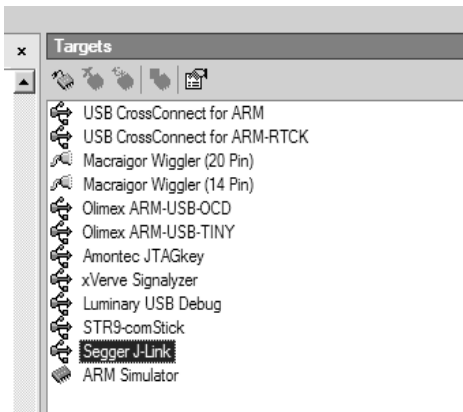
### Opening and Compiling uEZ®

Open the one project build files in the /uEZ/Build directories. For example, when working on the DK-57TS-LPC2478, open /uEZ/Build/DK-TS-KIT/DK-TS-LPC2478/FDIDemo/CrossWorks 2.0/DK-TS-LPC2478 uEZDemo.hzp. The Project Explorer should appear at the right showing all the files in the project. The uEZ distribution comes with the uEZ Demonstration Application in the /uEZ/App/UEZDemo directory and is configured for the DK-57TS-LPC2478 kit. If you need to change the LCD configuration, open the file Config\_Build.h to change which LCD to use.

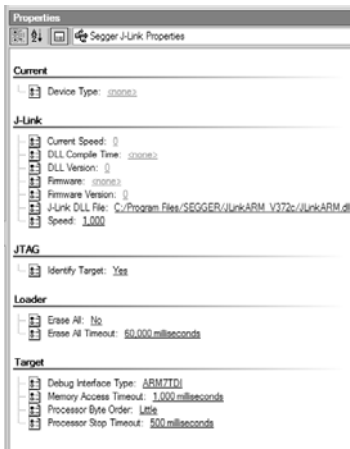
To compile the code for the first time, select **Build->Rebuild** uEZ from the main menu. When complete, the output should report “Build up to date” when done.

### Downloading and Debugging uEZ® on the Target

- 1) Plug the J-Link device into the PC and install any drivers as directed. The Segger J-Link drivers can be found at <http://www.segger.com/cms/jlink-software.html> with additional information at <http://www.segger.com/cms/development-tools.html>.
- 2) Plug the J-Link's JTAG cable into the target (e.g., SOMDIMM-LPC2478's J3 connector).
- 3) Power on the target board.
- 4) Select **Target** menu and choose **Targets**. The following list will appear to the right.



- 5) Right click on “Segger J-Link” and select Properties,

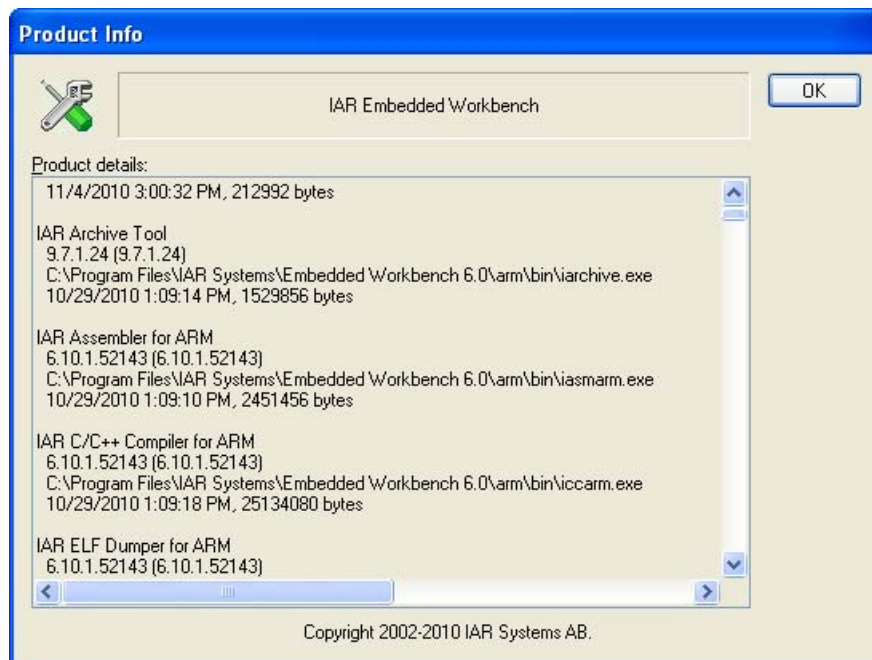


- 6) If this is the first time you are programming with the J-Link on the Rowley Platform, select J-Link DLL File, press the “...” button and find the file JLinkARM.dll (usually installed in C:/Program Files/SEGGER/”)
- 7) If programming a blank LPC2478 part, select a Speed of 100. If the LPC2478 has already been programmed, select a Speed of 1000. All LPC2478’s that come with the DK-xTS-LPC2478 are pre-programmed.
- 8) Go back to menu **Target** and select “Connect Segger J-Link”
- 9) Press F5 to download the application to the target and start debugging. When the application starts, it will pause. Press F5 again to start executing the code.
- 10) To stop at any line of code, right click the line and select Toggle Breakpoint. Execution will stop automatically at the breakpoint. Press F5 again to continue debugging.
- 11) When done debugging, select **Debug->Stop**. The debugger will return to standard editor mode.
- 12) From this point on, the process is simply a matter of editing code, compiling the code (**Build->Build uEZ** or pressing F7), and then running the debugger.

## IAR Systems Embedded Workbench v6.10 Project Configuration

### Check IAR Version

uEZ® is built using 6.10, or later, of the IAR Embedded Workbench Toolset. To confirm the version number of the tools, go to Help->About->Product Info in the main menu and the version number should appear in the middle of the dialog.



IAR C/C++ Compiler for ARM 6.10.1 and greater are acceptable.

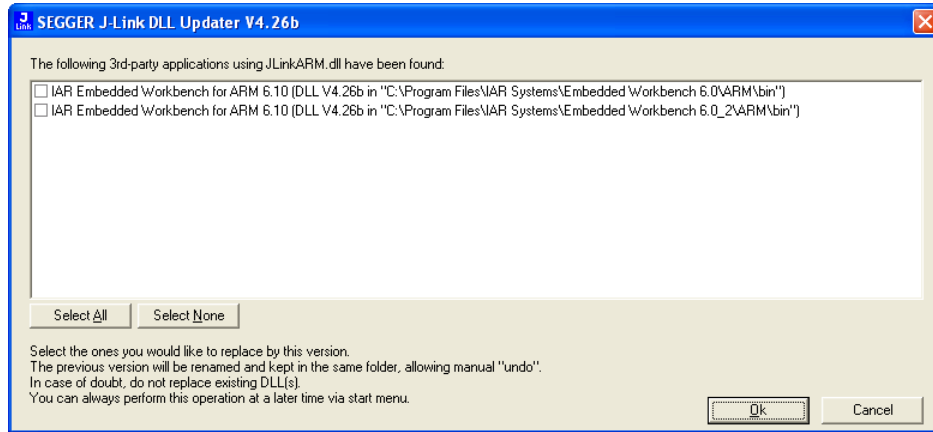
### Opening and Compiling uEZ®

Open the one project build files in the /uEZ/Build directories. For example, when working on the DK-57TS-LPC2478, open uEZ\Build\DK-TS-KIT\DK-57TS-LPC2478\IAR6.10\ DK-57TS-LPC2478.eww. The Project Explorer should appear at the left showing all the files in the project. The uEZ distribution comes with the uEZ Demonstration Application in the /uEZ/App/ DK-TS-Demo directory and is configured for the DK-XXXTS-LPC2478 kit, in this case DK-57TS-LPC2478.

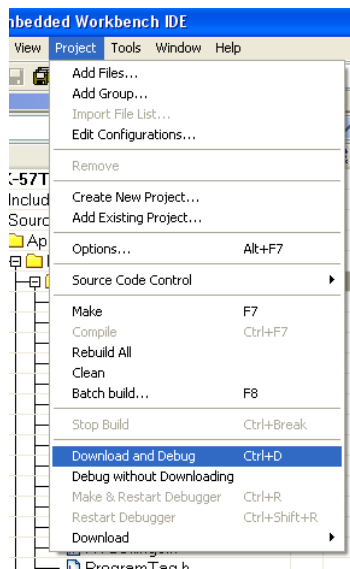
To compile the code for the first time, select **Project->Make** from the main menu or press F7. When complete, the output should report “Total number of errors: 0” when done.

### Downloading and Debugging uEZ® on the Target

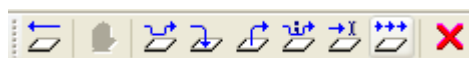
- 1) Plug the J-Link device into the PC and install any drivers as directed. The Segger J-Link drivers can be found at <http://www.segger.com/cms/jlink-software.html> with additional information at <http://www.segger.com/cms/development-tools.html>.
- 2) Plug the J-Link’s JTAG cable into the target (e.g., SOMDIMM-LPC2478’s J3 connector).
- 3) Power on the target board.
- 4) The project is preconfigured for the Segger J-Link. If the J-link software is installed after IAR the dll will automatically be updated. Otherwise run the SEGGER J-Link Updater from SEGGER/J-Link ARM vx.xx in the start menu.



- 5) Select Project->Download and Debug from the main menu or Ctrl + D to start debugging.



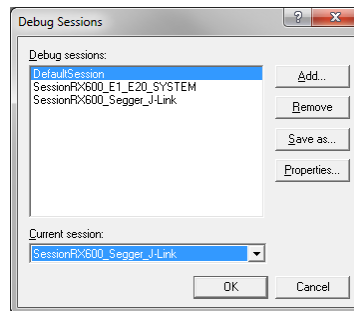
- 6) Debugging control can be operated from debug toolbar.



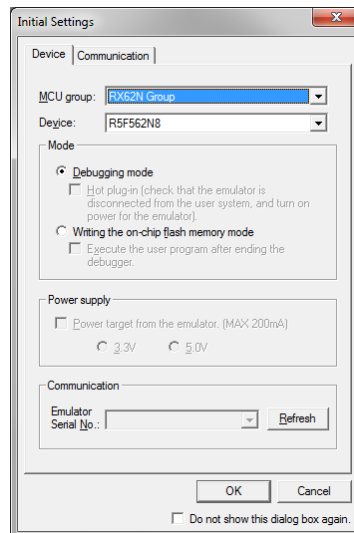
7) When finished debugging press the red X in the debug toolbar.

## Configuring Renesas HEW for J-Link Flashing

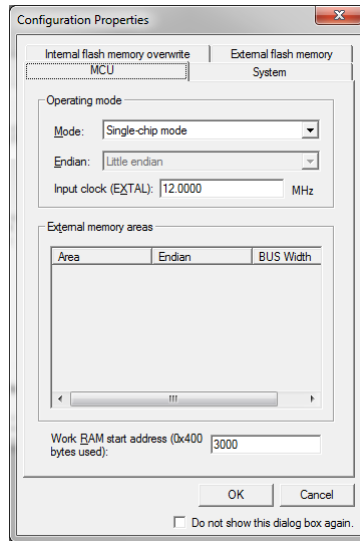
- 1) See the document “uEZ® Software Quick start Guide” for details on how to download the uEZ® source code
- 2) Plug in the J-Link device into the PC and install any drivers as directed. If necessary, download the drivers from [http://www.segger.com/cms/jlink-software.html?step=1&file=JLink\\_426a](http://www.segger.com/cms/jlink-software.html?step=1&file=JLink_426a)
- 3) Plug in the J-Link’s JTAG 10-pin connector (J2) to the SOMDIMM board connector (CN1) with the JTAG adapter.
- 4) If a workspace has not been opened, go to /uEZ\_SRC/Build/DK-TS-KIT/DK-57TS-RX62N/RenesasRX and open file “DKTSKITDemo\_RX62N.hws” or any other existing workspace.
- 5) Build the code if not already using **Build->Build** or by pressing **F7**.
- 6) Open Debug->Debug Sessions. Under Current Session, select “SessionRX600\_Segger\_J-Link” and click **OK**. Some older compiler configurations do not have this option. If this is the case, use “SessionRX600\_E1\_E20\_SYSTEM”. If asked to save the previous session, click **No**.



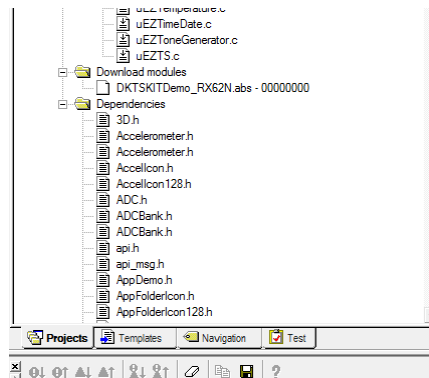
- 7) The following dialog will appear. Make sure the MCU group is “RX62N Group” and Device is “R5F562N8”. On the Communication tab, the JTAG Clock is 16.5 MHz. Press **OK**.



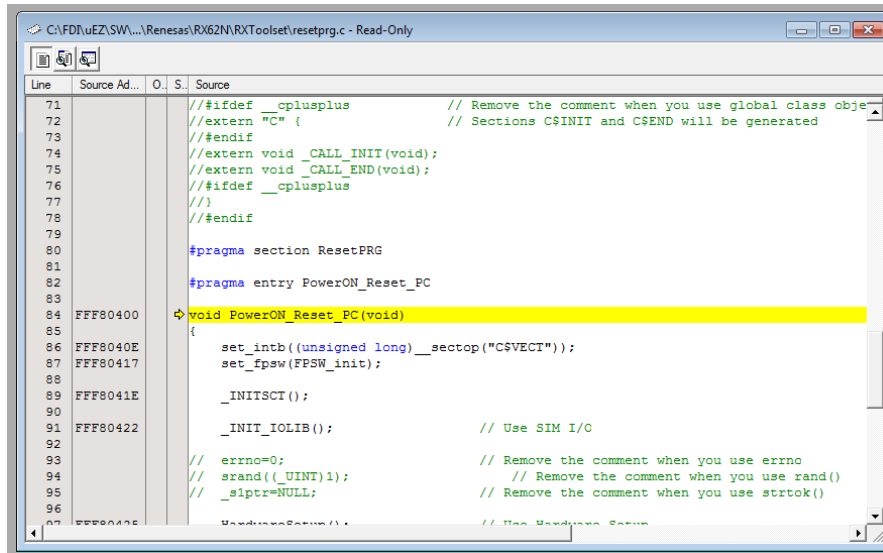
- 8) The Configuration Properties will appear. Confirm the Operating Mode has a Mode of “Single-chip mode” and Input clock (EXTAL) is “12.0000” MHz. The other tabs (Internal flash memory, External Flash memory, and System) use the default values. Then press **OK** to connect to the unit.



- 9) No errors should appear. The unit is now connected. The next step is to download the code. If the code has been compiled, scroll down in the project explorer and find the image file under “Download modules”. For the DKTSKitDemo code, the file “DKTSKITDemo\_RX62N.abs” should be listed. Right click on this file and select **Download**.



10) The following window should appear. Select Debug->Run (F5) to start execution.



```
CA\FDI\ueZ\SW\...Renesas\RX62N\RXToolset\resetprg.c - Read-Only
Line Source Ad... O. S. Source
71 //ifndef __cplusplus // Remove the comment when you use global class objects
72 //extern "C" { // Sections C$INIT and C$END will be generated
73 //endif
74 //extern void _CALL_INIT(void);
75 //extern void _CALL_END(void);
76 //ifndef __cplusplus
77 //}
78 //endif
79
80 #pragma section ResetPRG
81
82 #pragma entry PowerON_Reset_PC
83
84 FFF80400 void PowerON_Reset_PC(void
85 {
86 FFF8040E set_intb((unsigned long)__sectop("C$VECT"));
87 FFF80417 set_fpsw(FPSW_init);
88
89 FFF8041E _INITISCT();
90
91 FFF80422 _INIT_IOLIB(); // Use SIM I/O
92
93 // errno=0; // Remove the comment when you use errno
94 // srand((UINT)1); // Remove the comment when you use rand()
95 // _supt=NULL; // Remove the comment when you use strtok()
96
97 FFF8042E HardwareSetup(); // Use Hardware Setup
```

#### 4. Questions and Support

For all questions, bug reports and general technical support, go to <https://sourceforge.net/projects/uez/> and use the Sourceforge.net tools or email FDI directly at [support@teamfdi.com](mailto:support@teamfdi.com). A support forum is also provided at <http://www.teamfdi.com/forum/>.

Marketing updates and details on technical support are available at [www.teamfdi.com/uez](http://www.teamfdi.com/uez).

#### Can we use another RTOS?

All  $\mu$ EZ<sup>®</sup> components are made to connect through the  $\mu$ EZ<sup>®</sup> OSAL (Operating System Abstraction Layer) to the RTOS ensuring compatibility with many different RTOS's. Currently all  $\mu$ EZ<sup>®</sup> development by FDI is being focused on the FreeRTOS<sup>™</sup> platform since it satisfies the low cost tool requirement because it is "free". RTOS products from other vendors can also be used with  $\mu$ EZ<sup>®</sup>.

#### Which compiler suites do you support?

Currently, most  $\mu$ EZ<sup>®</sup> development by FDI has been focused on the low cost Rowley CrossWorks compiler, but we also support the IAR EWARM tool suite. In addition, Keil, ARM<sup>®</sup> RealView, GNU and other compilers can be used with  $\mu$ EZ<sup>®</sup>.

#### What debug tools are available?

Since  $\mu$ EZ<sup>®</sup> uses the debug tools that are provided in the customers compiler suite, it can be used with any of the tools listed above.

#### Which processors are supported?

Even though  $\mu$ EZ<sup>®</sup> is processor independent, all of our initial development has been focused on various members of the ARM Family. We currently support the NXP LPC24xx family, the NXP LPC17xx, and processors like Cortex<sup>™</sup>-M3, and other variations of ARM7<sup>®</sup> are being added.