Groking the Linux SPI Subsystem
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Obligatory geek reference
deobfuscation

grok (/gräk/)

verb
to understand intuitively or by empathy, to establish rapport with.
Overview

- What is SPI?
- SPI Fundamentals
- Linux SPI Concepts
- Linux SPI Use cases
  - Add a device
  - Protocol drivers
  - Controller drivers
  - Userspace drivers
- Linux SPI Performance
- Linux SPI Future
What is SPI?
What is SPI?

- Serial Peripheral Interface
- Motorola
- de facto standard
- master-slave bus
- 4 wire bus
  - except when it’s not
- no maximum clock speed
- “A glorified shift register”

http://wikipedia.org/wiki/Serial_Peripheral_Interface
Common uses of SPI

- Flash memory
- ADCs
- Sensors
  - thermocouples, other high data rate devices
- LCD controllers
- Chromium Embedded Controller
SPI fundamentals
SPI Signals

- MOSI - Master Output Slave Input
  - SIMO, SDI, DI, SDA
- MISO - Master Input Slave Output
  - SOMI, SDO, DO, SDA
- SCLK - Serial Clock (Master output)
  - SCK, CLK, SCL
- SS - Slave Select (Master output)
- CSn, EN, ENB
SPI Master and Slave
Basic SPI Timing Diagram

SPI 8-bit transfers

Write Mode 0
- SCLK
- MOSI: D0, D1, D2, D3, D4, D5, D6, D7
- MISO
- SS

Read Mode 0
- SCLK
- MOSI
- MISO: D0, D1, D2, D3, D4, D5, D6, D7
- SS
SPI Modes

- Modes are composed of two clock characteristics
- **CPOL** - clock polarity
  - 0 = clock idle state low
  - 1 = clock idle state high
- **CPHA** - clock phase
  - 0 = data latched falling, output rising
  - 1 = data latched rising, output falling

<table>
<thead>
<tr>
<th>Mode</th>
<th>CPOL</th>
<th>CPHA</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>1</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>2</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>3</td>
<td>1</td>
<td>1</td>
</tr>
</tbody>
</table>
SPI Mode Timing - CPOL 0

SPI Write Mode 0

Clock idle low, data latched on rising edge

SPI Write Mode 1

Clock idle low, data latched on falling edge
SPI Mode Timing - CPOL 1

SPI Write Mode 2

SCLK

MOSI: D0 D1 D2 D3 D4 D5 D6 D7

SS

Clock idle high, data latched on falling edge

SPI Write Mode 3

SCLK

MOSI: D0 D1 D2 D3 D4 D5 D6 D7

SS

Clock idle high, data latched on rising edge
SPI can be more complicated

- Multiple SPI Slaves
  - One chip select for each slave
- Daisy Chaining
  - Inputs to Outputs
  - Chip Selects
- Dual or Quad SPI (or more lanes)
  - Implemented in high speed SPI Flash devices
  - Instead of one MISO, have N MISOs
  - N times bandwidth of traditional SPI
- 3 Wire (Microwire) SPI
  - Combined MISO/MOSI signal operates in half duplex
Multiple SPI Slaves
SPI Mode Timing - Multiple Slaves
Linux SPI concepts
Linux SPI drivers

- Controller and Protocol drivers only (so far)
  - Controller drivers support the SPI master controller
    - Drive hardware to control clock and chip selects, shift data bits on/off wire and configure basic SPI characteristics like clock frequency and mode.
    - e.g. spi-bcm2835aux.c
  - Protocol drivers support the SPI slave specific functionality
    - Based on messages and transfers
    - Relies on controller driver to program SPI master hardware.
    - e.g. MCP3008 ADC
Linux SPI communication

- Communication is broken up into transfers and messages
- Transfers
  - Defines a single operation between master and slave.
  - tx/rx buffer pointers
  - optional chip select behavior after operation
  - optional delay after operation
- Messages
  - Atomic sequence of transfers
  - Fundamental argument to all SPI subsystem read/write APIs.
SPI Messages and Transfers
Linux SPI use cases
Exploring via use cases

- I want to hook up a SPI device on my board that already has a protocol driver in the kernel.
- I want to write a kernel protocol driver to control my SPI slave.
- I want to write a kernel controller driver to drive my SPI master.
- I want to write a userspace protocol driver to control my SPI slave.
Adding a SPI device to a system

- Know the characteristics of your slave device!
  - Learn to read datasheets

- Three methods
  - Device Tree
    - Ubiquitous
  - Board File
    - Deprecated
  - ACPI
    - Mostly x86
8.2 Serial interface characteristics (3-line serial)

<table>
<thead>
<tr>
<th>Signal</th>
<th>Symbol</th>
<th>Parameter</th>
<th>Min</th>
<th>Max</th>
<th>Unit</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>CSX</td>
<td>TCSS</td>
<td>Chip select setup time (write)</td>
<td>15</td>
<td></td>
<td>ns</td>
<td></td>
</tr>
<tr>
<td></td>
<td>TCSH</td>
<td>Chip select hold time (write)</td>
<td>15</td>
<td></td>
<td>ns</td>
<td></td>
</tr>
<tr>
<td></td>
<td>TCSS</td>
<td>Chip select setup time (read)</td>
<td>60</td>
<td></td>
<td>ns</td>
<td></td>
</tr>
<tr>
<td></td>
<td>TSCC</td>
<td>Chip select hold time (read)</td>
<td>65</td>
<td></td>
<td>ns</td>
<td></td>
</tr>
<tr>
<td></td>
<td>TCHW</td>
<td>Chip select “H” pulse width</td>
<td>40</td>
<td></td>
<td>ns</td>
<td></td>
</tr>
</tbody>
</table>
Reading datasheets for SPI details - ST7735

<table>
<thead>
<tr>
<th>SCL</th>
<th>Description</th>
<th>Value</th>
<th>Unit</th>
</tr>
</thead>
<tbody>
<tr>
<td>TSCYCW</td>
<td>Serial clock cycle (Write)</td>
<td>66</td>
<td>ns</td>
</tr>
<tr>
<td>TSHW</td>
<td>SCL “H” pulse width (Write)</td>
<td>30</td>
<td>ns</td>
</tr>
<tr>
<td>TSLW</td>
<td>SCL “L” pulse width (Write)</td>
<td>30</td>
<td>ns</td>
</tr>
<tr>
<td>TSCYCR</td>
<td>Serial clock cycle (Read)</td>
<td>150</td>
<td>ns</td>
</tr>
<tr>
<td>TSHR</td>
<td>SCL “H” pulse width (Read)</td>
<td>60</td>
<td>ns</td>
</tr>
<tr>
<td>TSLR</td>
<td>SCL “L” pulse width (Read)</td>
<td>60</td>
<td>ns</td>
</tr>
</tbody>
</table>
On-chip sample and hold
- SPI serial interface (modes 0.0 and 1.1)
- Single supply operation: 2.7V - 5.5V
- 200 ksp/s max. sampling rate at $V_{DD} = 5V$
- 75 ksp/s max. sampling rate at $V_{DD} = 2.7V$

Single-ended inputs. Differential Nonlinearity (DNL) and Integral Nonlinearity (INL) are specified at ±1 LSB. Communication with the devices is accomplished using a simple serial interface compatible with the SPI protocol. The devices are capable of conversion rates of up to 200 ksp/s. The MCP3004/3008 devices operate

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**FIGURE 1-1: Serial Interface Timing.**

<table>
<thead>
<tr>
<th></th>
<th>$t_{HI}$</th>
<th>125</th>
<th>—</th>
<th>—</th>
<th>ns</th>
</tr>
</thead>
<tbody>
<tr>
<td>Clock High Time</td>
<td>$t_{HI}$</td>
<td>125</td>
<td>—</td>
<td>—</td>
<td>ns</td>
</tr>
<tr>
<td>Clock Low Time</td>
<td>$t_{LO}$</td>
<td>125</td>
<td>—</td>
<td>—</td>
<td>ns</td>
</tr>
<tr>
<td>CS Fall To First Rising CLK Edge</td>
<td>$t_{SUCS}$</td>
<td>100</td>
<td>—</td>
<td>—</td>
<td>ns</td>
</tr>
<tr>
<td>CS Fall To Falling CLK Edge</td>
<td>$t_{CSD}$</td>
<td>—</td>
<td>—</td>
<td>0</td>
<td>ns</td>
</tr>
</tbody>
</table>
Reading datasheets for SPI details - MCP3008

* After completing the data transfer, if further clocks are applied with \( \overline{CS} \) low, the A/D converter will output LSB first data, then followed with zeros indefinitely. See Figure 5-2 below.

** \( t_{\text{DATA}} \): during this time, the bias current and the comparator powers down while the reference input becomes a high-impedance node.

**FIGURE 5-1:** Communication with the MCP3004 or MCP3008.
* Microchip Analog to Digital Converter (ADC)

The node for this driver must be a child node of a SPI controller, hence all mandatory properties described in

```
Documentation/devicetree/bindings/spi/spi-bus.txt
```

must be specified.

Required properties:
- compatible: Must be one of the following, depending on the model:

```
... "microchip,mcp3008" ...
```

Examples:
```
spi_controller {
    mcp3x0x@0 {
        compatible = "mcp3002";
        reg = <0>;
        spi-max-frequency = <1000000>;
    };
};
```
static const struct of_device_id mcp320x_dt_ids[] = {
    /* NOTE: The use of compatibles with no vendor prefix is deprecated. */
    {
        ...,
        { .compatible = "mcp3008",
        .data = &mcp320x_chip_infos[mcp3008],
        },
    },
    ...
};
MODULE_DEVICE_TABLE(of, mcp320x_dt_ids);

... static struct spi_driver mcp320x_driver = {
    .driver = {
        .name = "mcp320x",
        .of_match_table = of_match_ptr(mcp320x_dt_ids),
    },
    .probe = mcp320x_probe,
    .remove = mcp320x_remove,
    .id_table = mcp320x_id,
};
module_spi_driver(mcp320x_driver);
MCP3008 via DT - DTS overlay fragment

```plaintext
fragment@1 {
    target = <&spi0>;
    __overlay__ {
        /* needed to avoid dtc warning */
        #address-cells = <1>;
        #size-cells = <0>;
        mcp3x0x@0 {
            compatible = "mcp3008";
            reg = <0>;
            spi-max-frequency = <1000000>;
        }
    }
};
```
MCP3008 via board file - C fragment

```c
static struct spi_board_info my_board_info[] __initdata = {
    {
        .modalias       = "mcp320x",
        .max_speed_hz   = 4000000,
        .bus_num        = 0,
        .chip_select    = 0,
    },
};

spi_register_board_info(spi_board_info, ARRAY_SIZE(my_board_info));
```
MCP3008 via ACPI

Scope (\_SB.SPI1)
{
    Device (MCP3008)
    {
        Name (_HID, "PRP0001")
        Method (_CRS, 0, Serialized) {
            Name (UBUF, ResourceTemplate () {
                SpiSerialBus (0x0000, PolarityLow, FourWireMode, 0x08,
                ControllerInitiated, 0x003D0900, ClockPolarityLow,
                ClockPhaseFirst, "\_SB.SPI1", 0x00, ResourceConsumer)
            })
            Return (UBUF)
        }
        Method (_STA, 0, NotSerialized)
        {
            Return (0xF)
        }
    }
}
Protocol Driver

- Standard Linux driver model
- Instantiate a struct spi_driver
  - .driver =
    - .name = “my_protocol”,
    - .pm = &my_protocol_pm_ops,
  - .probe = my_protocol_probe
  - .remove = my_protocol_remove
- Once it probes, SPI I/O may take place using kernel APIs
Kernel APIs

- **spi_async()**
  - asynchronous message request
  - callback executed upon message complete
  - can be issued in any context

- **spi_sync()**
  - synchronous message request
  - may only be issued in a context that can sleep (i.e. not in IRQ context)
  - wrapper around spi_async()

- **spi_write()/spi_read()**
  - helper functions wrapping spi_sync()
Kernel APIs

- `spi_read_flash()`
  - Optimized call for SPI flash commands
  - Supports controllers that translate MMIO accesses into standard SPI flash commands
- `spi_message_init()`
  - Initialize empty message
- `spi_message_add_tail()`
  - Add transfers to the message’s transfer list
Controller Driver

- Standard Linux driver model
- Allocate a controller
  - spi_alloc_master()
- Set controller fields and methods (just the basics)
  - mode_bits - flags e.g. SPI_CPOL, SPI_CPHA, SPI_NO_CS, SPI_CS_HIGH, SPI_RX_QUAD, SPI_LOOP
  - setup() - configure SPI parameters
  - cleanup() - prepare for driver removal
  - transfer_one_message()/transfer_one() - dispatch one msg/transfer (mutually exclusive)
- Register a controller
  - spi_register_master()
Userspace Driver - spidev

- Primarily for development and test
- DT binding requires use of a supported compatible string or add a new one if no kernel driver exists for the device
  - rohm,dh2228fv
  - lineartecnology,ltc2488
  - ge,achc
- ACPI binding requires use of a dummy device ID
  - SPT0001
  - SPT0002
  - SPT0003
Userspace Driver - spidev

- Slave devices bound to the spidev driver yield:
  - /sys/class/spidev/spidev[bus].[cs]
  - /dev/spidev[bus].[cs]

- Character device
  - open()/close()
  - read()/write() are half duplex
  - ioctl()
    - SPI_IOC_MESSAGE - raw messages, full duplex and chip select control
    - SPI_IOC_[RD|WR]_* - set SPI parameters
Userspace Help

- Docs
  - Documentation/spi/spidev
- Examples
  - tools/spi/spidev_fdx.c
  - tools/spi/spidev_test.c
- Helper libraries
  - https://github.com/jackmitch/libsoc
  - https://github.com/doceme/py-spidev
Linux SPI Performance
Performance considerations

- Be aware of underlying DMA engine or SPI controller driver behavior.
  - e.g. OMAP McSPI hardcoded to PIO up to 160 byte transfer
- sync versus async API behavior
  - async may be suitable for higher bandwidth where latency is not a concern (some network drivers)
  - sync will attempt to execute in caller context (as of 4.x kernel) avoiding sleep and reducing latency
Performance considerations

- Use cs_change wisely. Note the details from include/linux/spi/spi.h:

  * All SPI transfers start with the relevant chipselect active. Normally it stays selected until after the last transfer in a message. Drivers can affect the chipselect signal using cs_change.

  * (i) If the transfer isn't the last one in the message, this flag is used to make the chipselect briefly go inactive in the middle of the message. Toggling chipselect in this way may be needed to terminate a chip command, letting a single spi_message perform all of group of chip transactions together.

  * (ii) When the transfer is the last one in the message, the chip may stay selected until the next transfer. On multi-device SPI busses with nothing blocking messages going to other devices, this is just a performance hint; starting a message to another device deselects this one. But in other cases, this can be used to ensure correctness. Some devices need protocol transactions to be built from a series of spi_message submissions, where the content of one message is determined by the results of previous messages and where the whole transaction ends when the chipselect goes inactive.
Performance tools

● Debug/visibility tools critical to any hardware focused work
● Logic analyzer
  ○ [http://elinux.org/Logic_Analyzers](http://elinux.org/Logic_Analyzers)
  ○ [https://sigrok.org/wiki/Supported_hardware#Logic_analyzers](https://sigrok.org/wiki/Supported_hardware#Logic_analyzers)
● `drivers/spi/spi-loopback-test`
● SPI subsystem statistics
  ○ `/sys/class/spi_master/spiB/spiB.C/statistics`
    ■ messages, transfers, errors, timedout
    ■ `spi_sync`, `spi_sync_immediate`, `spi_async`
    ■ `transfer_bytes histo_*`
Linux SPI Future
Slave Support

- Hard real time issues on Linux due to full duplex nature of SPI.
- Useful if considering limited use cases
  - Pre-existing responses
  - Commands sent to slave
- RFC v2 patch series
  - https://lkml.org/lkml/2016/9/12/1065
- Registering a controller works just like a master
  - spi_alloc_slave()
Slave Support

- `/sys/class/spi_slave/spiB/slave` for each slave controller
- slave protocol drivers can be bound via sysfs
  - `echo slave-foo > /sys/class/spi_slave/spi3/slave`
- Two slave protocol drivers provided as an example
  - `spi-slave-time` (provides latest uptime to master)
  - `spi-slave-system-control` (power off, reboot, halt system)
Questions?