



(Universal Asynchronous Receiver Transmitter)

Ultra-Compact UART Macros for Spartan-6, Virtex-6 and 7-Series

with PicoBlaze (KCPSM6) Reference Designs

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Acknowledgments

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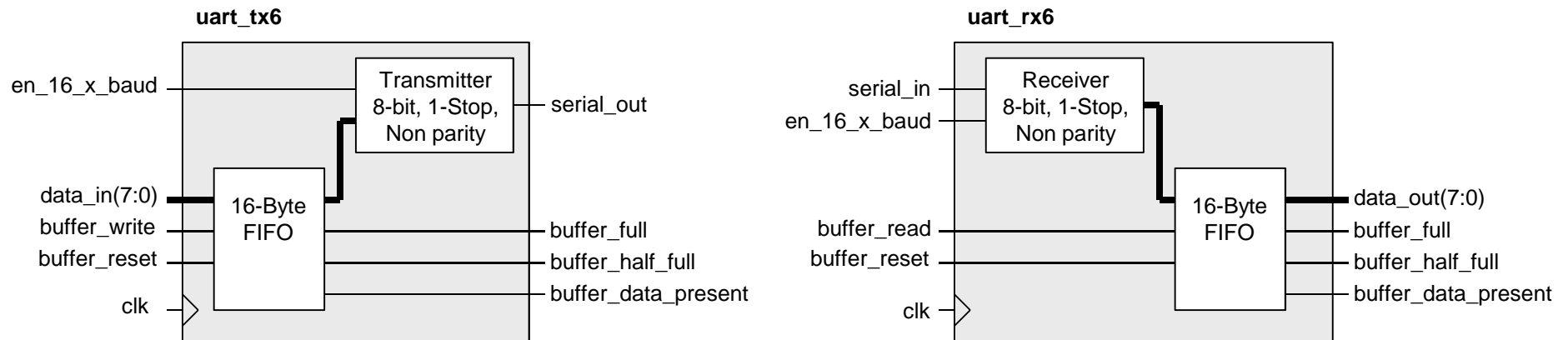
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UART_TX6 and UART_RX6 Features

Unsurprisingly, the 'uart_tx6' macro provides a UART transmitter whilst the 'uart_rx6' provides a UART receiver. More surprising is that each macro includes a 16-byte FIFO buffer and yet each macro occupies only 5-Slices of a Spartan-6 or Virtex-6 device. Their combined size of 10-Slices equates to 1.7% of the smallest (XC6SLX4) Spartan-6 device and a ridiculously small 0.01% of the largest (XC6VLX760) Virtex-6 device so there should never be any problem finding space for them!

Both the transmitter and receiver have pre-defined fixed communication settings of 8-bit data, 1-stop bit and no parity all of which are the most common settings and adequate for the vast majority of applications. The baud rate (bit rate) is defined in your design by the application of enable pulses relative to a system clock frequency. Whilst many applications will require a standard baud rate such as 9600 or 115200 these macros can operate at any baud rate up to your clock frequency divided by 16 which means that baud rates in excess of 10mbps can also be achieved; UART does not have to mean slow! Whilst the macros do not immediately provide a soft or hardware handshake option the FIFO buffer signals facilitate the implementation of handshake schemes.

The UART6 macros can be used standalone in your design but they are ideally matched with the PicoBlaze processor (KCPSM6). Whilst there is nothing particularly special about UART communication, it is highly likely that your application will transmit and receive specific information such as text strings and data values and PicoBlaze (at only 26 Slices) will often make the implementation of your 'protocol' rapid and efficient.



Except for the serial input to the receiver, which by the very nature of UART communication is asynchronous, all inputs and outputs of both macros are synchronous to the supplied clock and should be treated as such in your design. Parallel data is written to or read from the integral 16-byte FIFO buffers that provide a selection of status flags to be used as necessary by your application. The 'en_16_x_baud' input is used to define the baud rate of the serial communication relative to the clock frequency. Any data (characters) written to the transmit buffer will be automatically and continuously transmitted on 'serial_out' until the buffer becomes empty. Likewise, valid data (characters) received from 'serial_in' will be automatically written to the receiver FIFO.

Applications of the UART Macros

For many years UART has been synonymous with RS232 (UART with $\pm 12\text{V}$ signals) and the 9-way connector on the back of a PC often used to connect a serial mouse. Of course that serial port connector has been rapidly disappearing from machines as USB has become more dominant and popular. For a while it looked like UART would fade into history, but whilst it may look that way on most office desk tops it is still very much alive and well in our industry.

USB-UART

The legacy of RS232 is virtually everywhere and much of that equipment will remain in the field for many years to come. Furthermore the software programs associated with those pieces of equipment still require a 'COM' port to be connected. Companies such as FTDIchip (www.ftdichip.com) were quick to recognise that very soon it would be impossible to replace an old PC and developed some apparently simple USB to UART bridging devices. Combined with a 'Virtual COM port' driver these devices immediately saved a lot of people from a big problem. Not only that, these devices are so easy to use that they have given UART a future.

Not everything has to be fast, it just needs to be easy!

Whilst USB has many advantages for modern equipment it has to be said that its complexity is not one of them. When you need high speed connectivity and rapid plug-and-play capability then to some degree it is reasonable to accept the increased complexity in the hardware and software design. However, there are still many applications that only require a relatively low bandwidth communication link. For example, when a terminal is used to display text based status messages and allow commands to be entered on a keyboard for diagnostic purposes. From a hardware perspective the USB-UART devices can be thought of as a replacement for the RS232 level shifter device in the past and the virtual COM port driver avoids the need for special software to be developed.

UART is small

As the 'uart_tx6' and 'uart_rx6' macros prove, a UART can have an extremely small footprint. In contrast, a USB core could easily be expected to be at least 70 times bigger and still require an external PHY device; fine if your application needs a high bandwidth but otherwise a significant overhead.

On board connectivity and Micro-Controllers

At a board level a UART can provide a direct connection between components using LVTTTL or whatever standard is convenient. Many Micro-Controller devices include UART peripherals (at a lower price than their USB equivalents) or implement UART purely in software (see pages 24-25 to see how this technique can be implemented in PicoBlaze) . For PICmicro devices the low pin count (2) requirement of UART is compelling and fuels the desire for this connection to be supported in the Spartan-6 or Virtex-6 device even though it is rich in pins itself. Again, it is unlikely that such applications have any requirement for high bandwidth and in fact the baud rate may be very low in the case of a PICmicro software method being employed. UART really is just a simple and convenient way to pass relatively small amounts of information between devices.

More Potential Applications of the UART Macros

The previous page covered the rather obvious uses of a UART for connections between units either on the same board or with a PC. On this page we can consider how the UART macros in a Spartan-6 or Virtex-6 can be exploited further in your designs.

2 Test Points = Diagnostic Port

Whenever you design a board it is an extremely good idea to provide a general purpose header allowing connection to a few pins on the FPGA. At any time you can modify your FPGA design to bring out some signals of interest to be probed with an oscilloscope etc. Now consider how much information you display on a terminal by inserting a PicoBlaze and a UART in a design as well as the control you could have over that design. Note that a USB-UART device can be part of the cable you attach rather than adding unnecessary cost to your board (e.g. <http://www.ftdichip.com/Products/Cables/USBTTLSerial.htm>).

Higher speed connectivity

The baud rate of these macros can be up to CLK/16 meaning that baud rates of 5mbps in Spartan-6 and 10mbps in Virtex-6 are achievable. Providing you define the same baud rate at both ends of each link in your system then nobody is forcing you to conform to a standard rate. For example, with a 100MHz clock the baud rate of 6.25mbps can be achieved ('en_16_x_baud' input is tied permanently High) supporting a transfer rate of up to 625 k-bytes/second. With each pair of UART macros only occupying 10-Slices, running multiple UART links in parallel is also a cost effective way to increase bandwidth.

Longer distance connectivity made easy

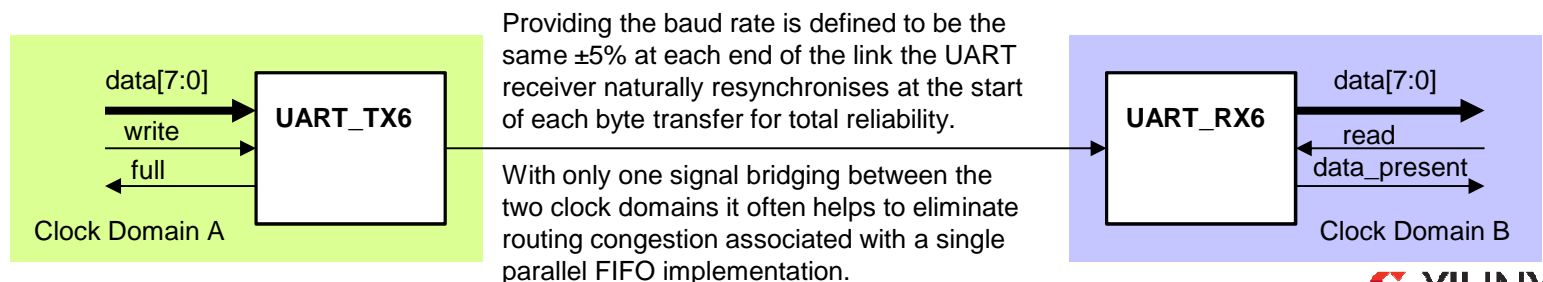
Why not consider using LVDS for longer distance communication over larger boards or twisted pair cables? The differential standard will afford you greater protection from noise etc. Providing the data rate is adequate the naturally asynchronous nature of UART communication also avoids all those tricky requirements for clock forwarding or clock recovery circuits. The simplicity of a UART makes communication reliable and low power.

Crossing Clock Domains and on-chip links

Every time information needs to cross from one clock domain to another there is the potential for unreliable operation. Failure to recognise this can result in intermittent faults that can be very costly over time. Typically the default solution is to insert an asynchronous FIFO although this often comes with the burden of complexity and an undesirable resource cost. So providing the data rate is adequate, the UART6 macros can be a superior alternative.

Each clock domain is presented with a fully synchronous FIFO interface.

Note that the link can buffer up to 32-bytes in total.



Inserting UART Macros into Your Design

Please note that the Verilog equivalent of each macro is also provided.

Each macro is included in your design in exactly the same way as any hardware component.

Hint – This is not supposed to be an exercise in typing so the file called 'uart6_ml605.vhd' can be used as a code template as well as being a working example for the ML605 Evaluation Board. Simply copy and paste the code into the appropriate places in your own design.

Component declarations....

uart_tx6

```
component uart_tx6
  Port (
    data_in : in std_logic_vector(7 downto 0);
    en_16_x_baud : in std_logic;
    serial_out : out std_logic;
    buffer_write : in std_logic;
    buffer_data_present : out std_logic;
    buffer_half_full : out std_logic;
    buffer_full : out std_logic;
    buffer_reset : in std_logic;
    clk : in std_logic);
end component;
```

uart_rx6

```
component uart_rx6
  Port (
    serial_in : in std_logic;
    en_16_x_baud : in std_logic;
    data_out : out std_logic_vector(7 downto 0);
    buffer_read : in std_logic;
    buffer_data_present : out std_logic;
    buffer_half_full : out std_logic;
    buffer_full : out std_logic;
    buffer_reset : in std_logic;
    clk : in std_logic);
end component;
```

Component instantiations.... (Obviously appropriate signals will need to be defined in order that they can be assigned to the ports in the instantiation)

uart_tx6

```
tx: uart_tx6
  port map (
    data_in => uart_tx_data_in,
    en_16_x_baud => en_16_x_baud,
    serial_out => uart_tx,
    buffer_write => write_to_uart_tx,
    buffer_data_present => uart_tx_data_present,
    buffer_half_full => uart_tx_half_full,
    buffer_full => uart_tx_full,
    buffer_reset => uart_tx_reset,
    clk => clk);
```

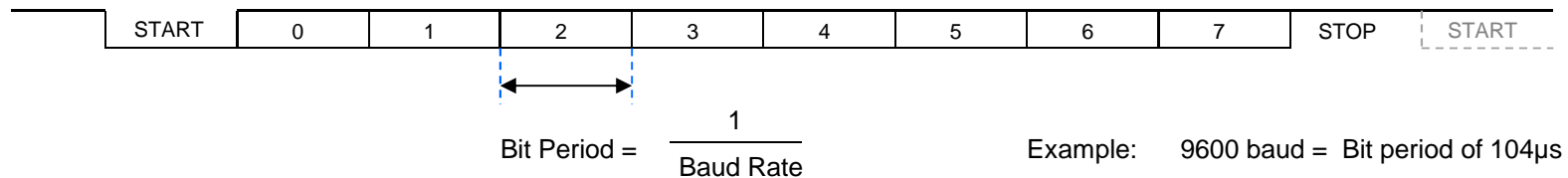
uart_rx6

```
rx: uart_rx6
  port map (
    serial_in => uart_rx,
    en_16_x_baud => en_16_x_baud,
    data_out => uart_rx_data_out,
    buffer_read => read_from_uart_rx,
    buffer_data_present => uart_rx_data_present,
    buffer_half_full => uart_rx_half_full,
    buffer_full => uart_rx_full,
    buffer_reset => uart_rx_reset,
    clk => clk);
```

Hint - If any of the FIFO status signals are not required then these can be left open. For example... `buffer_half_full => open,`

Defining the Baud Rate

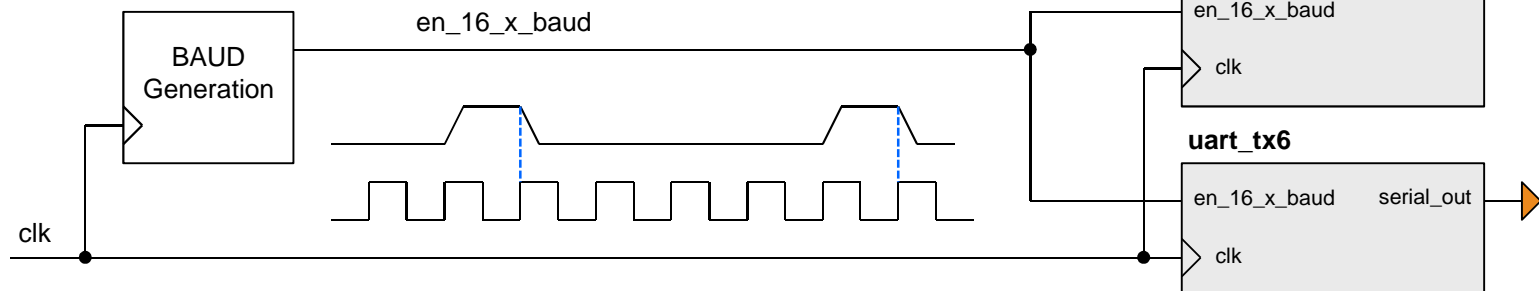
The only requirement that is specific to the serial communication is the definition of the baud rate. The baud rate is the number of bits per second at which information is transmitted and received. It is typically one of the well known standard rates associated with a computer based applications (e.g. 9600 or 115200) but it can be any rate you like provided that it is set to the same rate at both ends of a communication link. Each byte of data (or character) is transmitted and received using 10 bits comprising a start bit ('0'), the 8-bit data (transmitted LSB first) and a stop bit ('1').



Hint – The overhead of start and stop bits means that the maximum data rate is 8/10 of the baud rate. If you have a specific requirements to transfer data then remember to take this into account when defining the baud rate of your communication link. For example, to transfer 1M-byte/second the minimum baud rate must be $1\text{MHz} \times (8\text{-bits of data} + 2) = 10,000,000 \text{ BAUD}$. That's 10MHz rather than 8MHz.

en_16_x_baud

This input to the macros is used to define the desired baud rate by applying a series of enable pulses at a rate that is 16 times greater than the serial bit rate. This in turn is derived from the system clock which is of a known frequency.



IMPORTANT – 'en_16_x_baud' pulses must be synchronous to the clock (synchronous design!).

IMPORTANT – The 'en_16_x_baud' signal should be a series of *single clock cycle pulses* used to enable the UART macros for one rising edge of the clock at a time. Do not make the mistake of applying a square wave 'clock' waveform that is 16 times the frequency of the baud rate!

Defining the Baud Rate

For the majority of applications the baud rate generation takes the form of a simple counter. This scheme is best explained by a real example in which a Spartan-6 device with a 50MHz clock is required to communicate with a PC at a baud rate of 9600.....

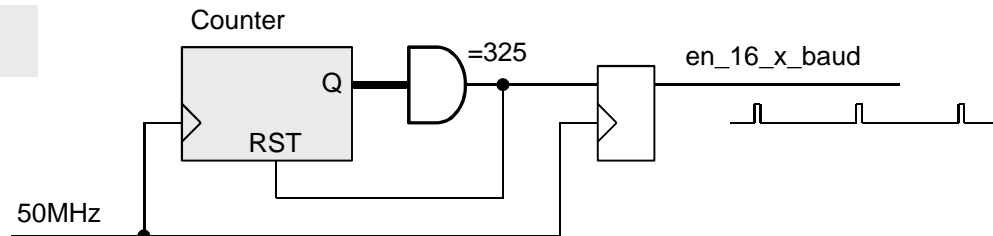
- 1) The 'en_16_x_baud' signal must therefore have a pulse rate of $16 \times 9600 = 153,600$ pulses per second.
- 2) With a 50MHz clock this equates to one enable pulse every $50,000,000 / 153,600 = 325.52$ clock cycles. To be practical we round this to the nearest integer of 326.
- 3) Check the effect of rounding on the baud rate..... $(50,000,000 / 326) / 16 = 9586$ baud which is just 0.15% slower than target (assuming clock is perfect). Providing there is less than 5% difference between the baud rate of the transmitter and receiver forming a communication link then it should work.

Hint – See 'Improving Baud Accuracy' on pages 21-23 if rounding results in an undesirable deviation from the desired rate.

- 4) Implement your baud generation counter circuit. The following example uses a signal defined as an integer to make this really easy....

```
signal      baud_count : integer range 0 to 325 := 0;  
signal      en_16_x_baud : std_logic := '0';
```

```
baud_rate: process(clk)  
begin  
  if clk'event and clk = '1' then  
    if baud_count = 325 then  
      baud_count <= 0;  
      en_16_x_baud <= '1';  
    else  
      baud_count <= baud_count + 1;  
      en_16_x_baud <= '0';  
    end if;  
  end if;  
end process baud_rate;
```



Note that the synchronous reset on the counter means that there are 326 states with values 0 through to 325. It is the total number of states that correctly defines the pulse rate so be careful how you specify the terminal count value in your code.

Hint – Similar code in VHDL and Verilog is provided in the two reference designs

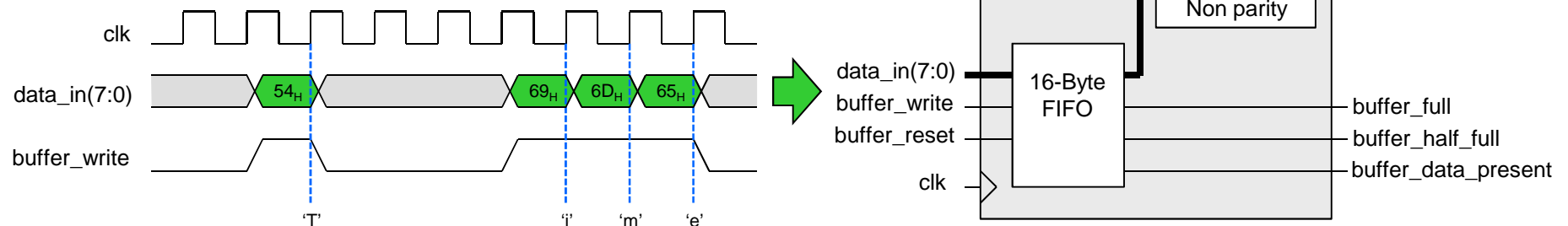
Hint – “**My simulation does not work!**”! Please be aware that many designers have allowed themselves to be confused by an attempt to simulate a design containing the UART6 macros; they simply forget that baud rate is often significantly slower than their clock and fail to simulate for enough cycles. In the above example the transmission of one byte (or character) will take $10 \text{ bits} \times 16 \text{ enable pulses} \times 326 \text{ clock cycles} = 52,160 \text{ clock cycles}$; a long simulation!

Hint – The maximum baud rate is $\text{CLK}/16$ and is achieved by tying the 'en_16_x_baud' input permanently High thereby avoiding any requirement for a baud generation circuit. This is ideal for point to point links whenever the same nominal clock frequency is available at the end of each link. No need for phase locked clocks or clock forwarding. Please also see 'Improving Baud Accuracy' section for high baud rate example.

Transmitting Data with 'uart_tx6'

To transmit data (or characters) you simply need to write 8-bit values into the FIFO buffer; the UART will automatically transmit any characters that are present in the buffer at the baud rate defined by 'en_16_x_baud' (and the clock frequency) until the FIFO buffer is empty. The FIFO is fully synchronous with the clock (clk). 8-bit data or characters presented to the 'data_in' port will be written into the FIFO on the rising edge of the clock when the 'buffer_write' control is active High (1). This obvious scheme facilitates the writing of individual characters or bursts of characters as required by the application.

In this example the text string 'Time' is written to the transmitter FIFO using a combination of a single character write followed by a burst write of 3 characters.



buffer_full - Whilst it is possible to write one character into the FIFO every clock cycle the UART transmitter will always take many more clock cycles to serially transmit each character (e.g. 8,680 clock cycles at 115,200 baud using a 100MHz clock). It is therefore extremely easy to fill the FIFO with 16 bytes of data before the first character has been transmitted. It is *vital* that no attempt is made to write more data into the FIFO if the 'buffer_full' flag is active High (1). The most common technique employed in an application is to first test that 'buffer_full' is Low (0) before writing only one character to the transmitter FIFO. If the full flag is active then the application waits for it to return Low before writing just one more character and testing the 'buffer_full' flag again.

buffer_half_full - The 'buffer_half_full' flag will be active High (1) whenever the FIFO contains 8 or more characters pending transmission. This can be useful to some applications which prefer to write to the transmitter FIFO in small bursts rather than one character at a time. By first testing that the 'buffer_half_full' flag is Low (0) the application will know that up to 8 bytes of information can be written in a burst without needing to check the full flag between each write.

buffer_reset - An active High (1) on the 'buffer_reset' input will synchronously reset the FIFO buffer on the corresponding rising edge of the clock. Any data in the buffer will be lost and all flags will be cleared. This is typically only required when rebooting a system or following a buffer overflow (which is best avoided anyway). Note that if a reset is applied whilst data is being transmitted then the character being transmitted at that time will probably appear corrupted although that should be insignificant compared with the buffer contents being discarded!

Transmitting Data with 'uart_tx6'

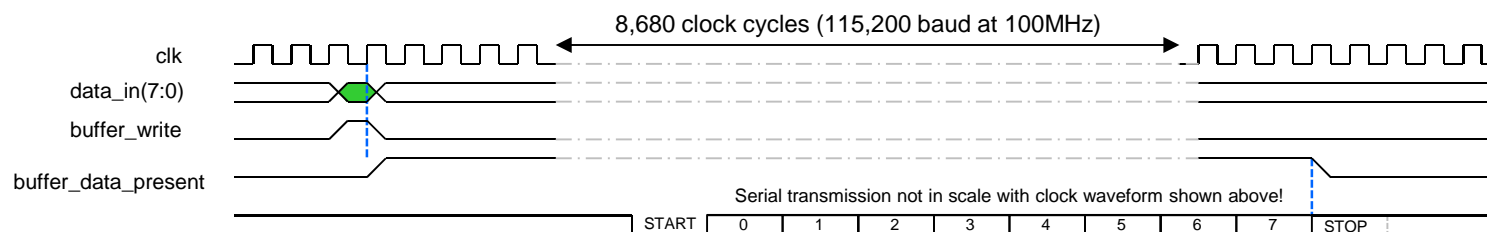
Hint - In some applications it is possible to predict in advance that the FIFO buffer will never become full and all flags can be ignored. This technique can apply if the 'packets' of information written to the transmitter FIFO always contain less than 16 characters and those packets occur at such a rate that it is guaranteed that the UART will have had adequate time to transmit each packet such that the FIFO will be empty before the next one. For example, an application could transmit the time of day using a text string with the format 'hh:mm:ss'. This is a packet containing 8 characters, which if transmitted at one second intervals absolutely guarantees that the buffer will not become full providing the baud rate is more than 80 (which it normally is!).

Hint - It may be undesirable in some applications for everything to 'stall' whilst waiting for the UART to transmit data and free space in the FIFO. However, if the FIFO is full then it is also known that the UART transmitter already has enough information to keep it actively transmitting for another 16 character periods. During this time (e.g. ~1.38ms at 115,200 baud) the application could be gainfully employed to perform other tasks whilst the UART macro continues to transmit. When the application returns to the UART the buffer could, if required, be refilled to capacity and left once again whilst servicing other tasks.

Hint - The effective depth of the FIFO buffer could be increased by inserting an additional FIFO between the application and the UART Transmitter. For example the FIFO mode of a Block Memory (BRAM) could significantly increase the depth of the buffer. The application would observe the status flags of the additional FIFO and write information to it as appropriate. A simple state machine would then automate the process of reading data from this FIFO and writing it into the UART transmitter FIFO providing 'buffer_full' was Low.

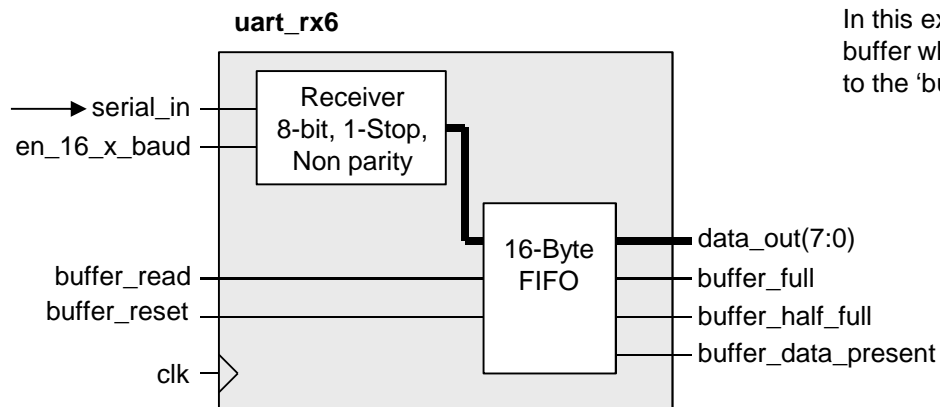
buffer_data_present - The 'buffer_data_present' flag is active High (1) at any time that the FIFO buffer contains one or more characters. Alternatively, it can be said that the buffer is empty when this flag is Low (0). Whilst the majority of applications ignore this flag it can be useful in two principle ways....

- 1) If it is known that the FIFO is empty then it is safe to write a burst of up to 16 characters without needing to test the 'buffer_full' flag between each write.
- 2) The diagram below indicates how the 'buffer_data_present' flag is set High when the first character is written to the buffer. Then, providing no other characters are written, the flag returns Low once the last bit of that character has been transmitted. This can be used by the application to implement either a hardware or soft (XON/XOFF) flow control scheme by only writing one character to the buffer providing the receiver at the other end of the serial line is indicating 'clear to send' (CTS). Although this effectively wastes much of the FIFO capability it ensures that the transmission can be stopped within one character when required to do so.

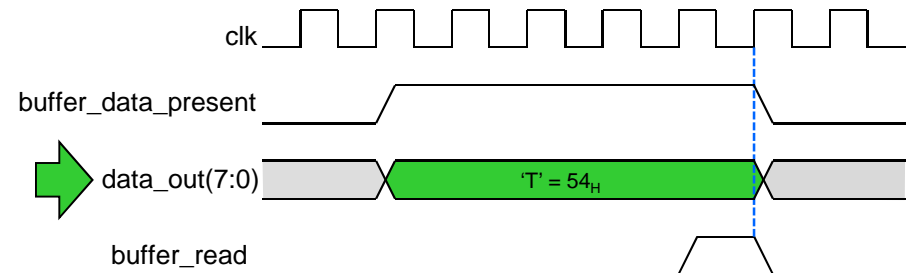


Receiving Data with 'uart_rx6'

Data (or characters) are received automatically at the baud rate defined by 'en_16_x_baud' (and the clock frequency) and then stored in the receiver FIFO buffer. The FIFO is fully synchronous with the clock (clk). When active High (1), the '**buffer_data_present**' flag is used to signify to the application that there is at least one character ready to be read which will be present on the '**data_out**' port. The application should capture this data and then provide an active High (1) level for one rising edge of the clock to the '**buffer_read**' control input. The receiver FIFO will then present the next character to be read on the '**data_out**' or drive the '**buffer_data_present**' flag Low (0) to indicate that the FIFO is now empty. This obvious scheme facilitates the reading of individual characters or bursts of characters (if available).

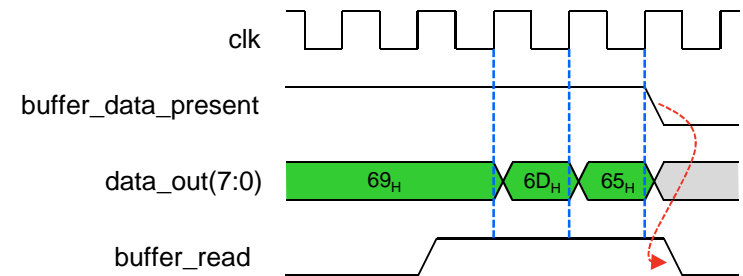


In this example the character 'T' is received and automatically stored in the FIFO buffer which was previously empty. After a few clock cycles the application responds to the 'buffer_data_present' flag and reads the FIFO so that it is empty once again.



Hint – The 'buffer_read' control is more accurately described as being an "I have read you" control. Unlike the 'buffer_write' control that is an instruction to write data into the transmitter FIFO on the corresponding rising clock edge, the data presented on the 'data_out' port of the receiver FIFO can be read at any time that it is valid (e.g. 'T' shown in the diagram above could have been read anywhere in the green zone) and the 'buffer_read' is purely the indication that the FIFO can now discard that data and move on to the next character and/or update the status flags.

Hint – The 'buffer_read' control should only be asserted when 'buffer_data_present' is High indicating that there was valid data to be read from the buffer. The diagram on the right shows a burst read of characters 'i', 'm' and 'e' resulting in the buffer becoming empty. Note how 'buffer_data_present' is used to drive 'buffer_read' Low to prevent a further illegal read. Asserting 'buffer_read' when 'buffer_data_present' is Low does not itself result in incorrect operation of the FIFO but it does imply that the application may have read 'data_out' when it was not valid to do so. There is also a risk that that the 'buffer_read' occurs at exactly the same time that a character received from the serial input is being written into the FIFO buffer with the net effect being that the received character is missed by the application.



Receiving Data with 'uart_rx6'

buffer_full - The receiver FIFO buffer can hold up to 16 characters. Obviously this means that up to 16 characters can be received from the serial input before the application needs to read any of them from the buffer. The 'buffer_full' flag will be driven active High (1) as soon as the 16th character is received since design start or the when the last read occurred. If this situation be allowed to develop in a application then it should be treated as a matter of some urgency to read at least one character from the buffer before a 17th character is received and results in a buffer overflow. Remember that it can appear to take a relatively long time (e.g. 8,680 clock cycles at 115,200 baud using a 100MHz clock) for the next character to be received so a rapid response to 'buffer_full' should avoid any loss of data. If however, the application is unable to determine the moment at which the 'buffer_full' flag was asserted then it will almost certainly need to assume that an overflow has occurred and take suitable recovery steps.

Hint – If the FIFO is full then the application can burst read up to 16 characters without needing to check the state of the 'buffer_data_present' flag.

buffer_reset - An active High (1) on the 'buffer_reset' input will synchronously reset the FIFO buffer on the corresponding rising edge of the clock. Any data in the buffer will be lost and all flags will be reset. This is typically only required when rebooting a system or following a buffer overflow (which is best avoided anyway). Note that if a reset is applied whilst data is being received then the character being received at that time will still be written into the receiver buffer providing the 'buffer_reset' is Low when the stop bit of that character is received (assuming it is a valid).

buffer_half_full - The 'buffer_half_full' flag will be active High (1) whenever the receiver FIFO contains 8 or more characters waiting to be read by the application. This can be very useful in several ways:-

- 1) If the 'buffer_half_full' flag is used to alert the application to the requirement to start reading from the buffer then the remaining half of the buffer (enough to receive another 8 characters) would generally provide adequate time for the application to schedule the buffer reading task in the near future rather than interrupting its current task. This ability to be more 'relaxed' is often very welcome. Using this scheme the 'buffer_full' flag should never be seen to go High and therefore be assigned the status of 'overflow' or 'communication error' should it ever occur.
- 2) The 'buffer_half_full' flag is ideally suited for the implementation of either a hardware or soft (XON/XOFF) flow control scheme. When the flag is asserted the receiving application can indicate to the transmitter at the other end of the link that it should cease transmission. By the very nature of the UART arrangement it is almost impossible to stop the transmission immediately but since there is enough remaining space in the receiver FIFO buffer to store another 8 characters before an overflow can occur then this provides a high margin of safety.
- 3) Some application have more important and compelling tasks to perform than checking to see if there is anything waiting to be read from the receiver FIFO. Likewise, handling one character at a time when each character is received relatively slowly can be a distraction from other tasks. In these situations the 'buffer_half_full' flag can be used as the trigger to tell the application that there are at least 8 characters waiting to be read. Not only may this be considered enough information to be worthy of processing but it also means the application can burst read up to 8 characters without needing to check the state of the 'buffer_data_present' flag between each read operation.

Debugging a UART Connection

If your UART communication is not working then fortunately there is nearly always a simple reason and an easy solution. As with most successful debugging, it is often solved by breaking the design down into smaller pieces and checking what does and what does not work. So here are the steps recommended to debug a UART connection that should solve 90% of cases. The next 9% of cases will be solved by going over them again more carefully! ☺

- 1) Read the documentation again!
 - If you are simulating a design rather than using hardware then especially read the “My simulation does not work” Hint on page 8.
- 2) Check your communication settings at your terminal. Do they match your baud rate? Check 8-bit, 1-stop, no parity and no handshake.
- 3) Check your design again.
 - The way you have connected the UART macros in your design.
 - The way you have defined the baud rate (you are generating synchronous enable pulses aren't you?).
 - Your UCF file defines the correct pins on your FPGA; it's easy to swap serial input and serial output pins!
 - Cables are plugged in correctly etc.
 - The FPGA is configured isn't it?
- 4) If nothing seems to make it work then create a dummy design in which you define a 'wire' directly between your serial input and serial output.
 - This is a 'loop-back' connection and completely eliminates the UART macros and the rest of your design.
 - Typing on your keyboard should result in the same characters being displayed as they go down and back up the cable.
 - Likewise an embedded design should be able to see characters echo back.
 - If this doesn't work then you have a problem with your cable or your loop-back design.
 - Check your UCF pin assignments again.
 - Are they the correct pins for your hardware and have you got them assigned the right way round?
 - Check your cable
 - Ideally disconnect it and physically short the connections at the end of the cable.
 - Note that serial cables either come as straight-through (pin3 to pin3) or swap-over (pin3 to pin4) so be sure which you need and use.
- 5) If the loop-back worked then focus only on the 'uart_tx6' macro first and continuously transmit a known ASCII character (e.g. 'A' = 41hex).
 - If you do not receive characters then....
 - Check your baud rate definition again along with 8-bit, 1-stop, no parity and no handshake.
 - Check how you write to the 'uart_tx6' macro and check to see if the transmitter buffer flags are changing as expected.
 - If you do receive characters then....
 - Implementing a loop-back of data received from 'uart_rx6' to resolve your receive path.
 - Check status of flags on 'uart_rx6'.

PicoBlaze Reference Designs with UART6 Macros

Hint – README.txt includes UART device pin constraints for other popular boards

Two *simple* reference designs are provided with KCPSM6 and the UART6 macros. As provided, the source files target the ML605 Virtex-6 Evaluation Kit and the ATLYS Spartan-6 Design Platform but both can be used as reference for your own designs and are easy to port to other hardware. The primary objective of the designs is to illustrate the typical hardware design and PSM assembler code required when using the UART6 macros with KCPSM6 and for this reason the two designs are almost identical in this area. However, the designs do have some subtle differences as well as unique features, all of which are intended to provide educational examples as well as reusable code for your own designs. Please do take the time to look at *both* designs; even if you plan to work immediately with one of the target boards there are lessons to be learnt from both designs and different PSM code for you see and reuse.

Common to both designs...

- The KCPSM6 processor interfaces to the UART6 receiver and transmitter macros using the same input and output ports.
- The baud rate is set to 115200 (This is also the default baud rate for the PicoTerm terminal).
- Programs (PSM code) illustrate UART macro interaction and communication with terminal (keyboard and display) .
- Source files only; you must assemble the PSM file to generate the program definition file and then implement the design to configure the device.

Differences...

An overview of the differences in each design is given below and the following pages provide further details (each source file also contains descriptions).

uart6_ml605

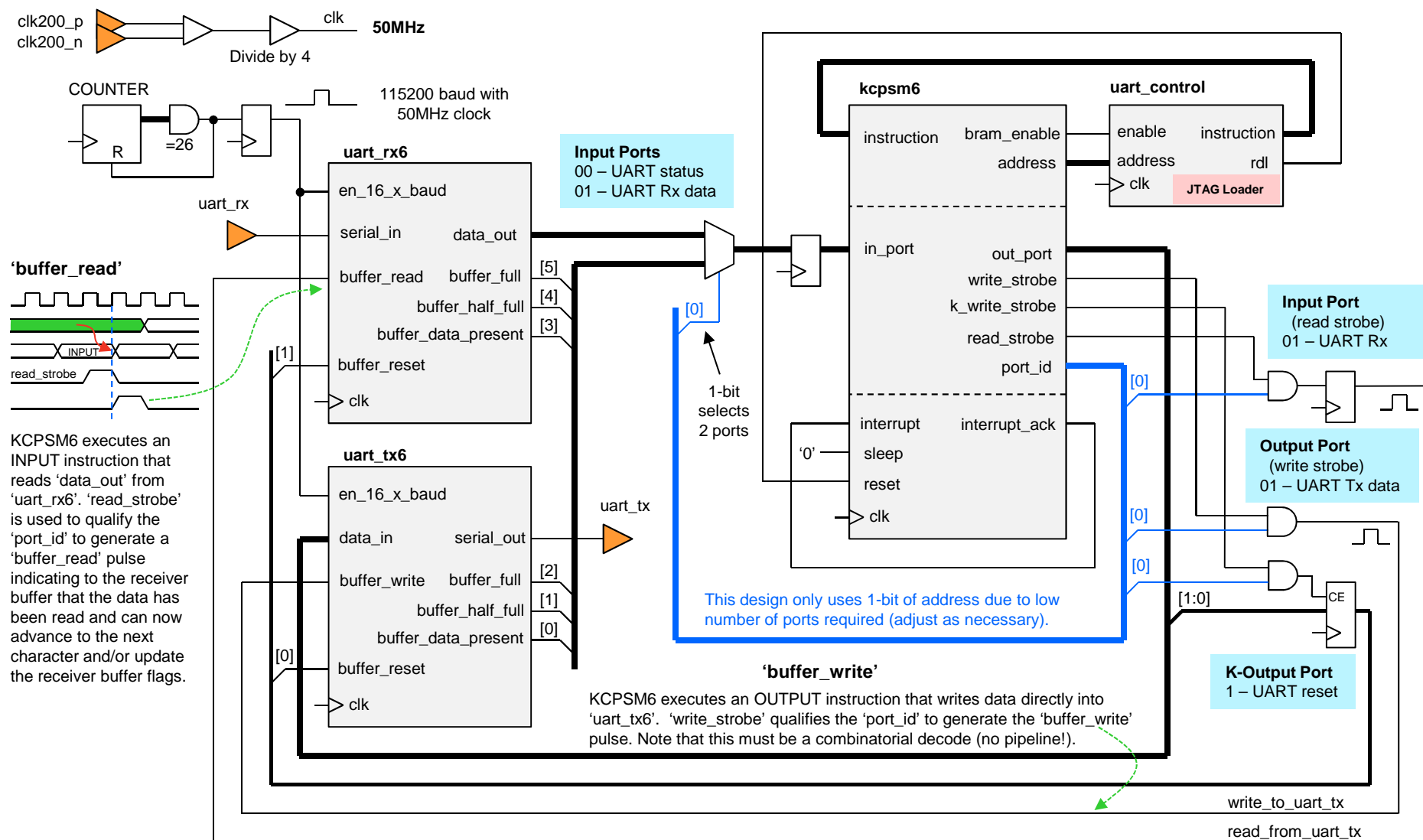
- Hardware design defined by..... [‘uart6_ml605.vhd’](#) (verilog version also provided) and [‘uart6_ml605.ucf’](#).
- ML605 provides a 200MHz differential clock which is divided by 4 using a ‘BUFR’ to form a 50MHz clock.
Note how the baud rate is defined relative to the 50MHz clock and that software delays in PSM code also relate to 50MHz.
- Program memory is set to ‘V6’ due to target being a Virtex-6 device. The initial program size is set to 2K instructions (1 BRAM in a Virtex-6).
- KCPSM6 code defined by.... [‘uart_control.psm’](#) and [‘uart_interface_routines.psm’](#).
- Program illustrates interaction with the user of a terminal allowing keyboard entry of characters and performing ASCII, hex and decimal conversions.
- Can be used with any appropriately configured terminal (e.g. HyperTerminal) but PicoTerm should make setting up easy.

uart6_atlys

- Hardware design defined by..... [‘uart6_atlys.vhd’](#) (verilog version also provided) and [‘uart6_atlys.ucf’](#).
- ATLYS provides a 100MHz clock which is used directly. Note that the baud rate and software delays in PSM code are defined relative to 100MHz.
- Program memory is set to ‘S6’ due to target being a Spartan-6 device. The initial program size is set to 1K instructions (1 BRAM in a Spartan-6).
- Additional ports interface with the 8 switches and 8 LEDs on the ATLYS board, an interrupt is generated at one second intervals and a reset button.
- KCPSM6 code defined by.... [‘atlys_real_time_clock.psm’](#), [‘PicoTerm_routines.psm’](#) and [‘soft_delays_100mhz.psm’](#).
- The program exploits and illustrates several of the unique features that PicoTerm provides and therefore PicoTerm must be used to see everything.
- Although simple, the program provides examples of interrupt handing and hardware interaction in addition to various UART communications.

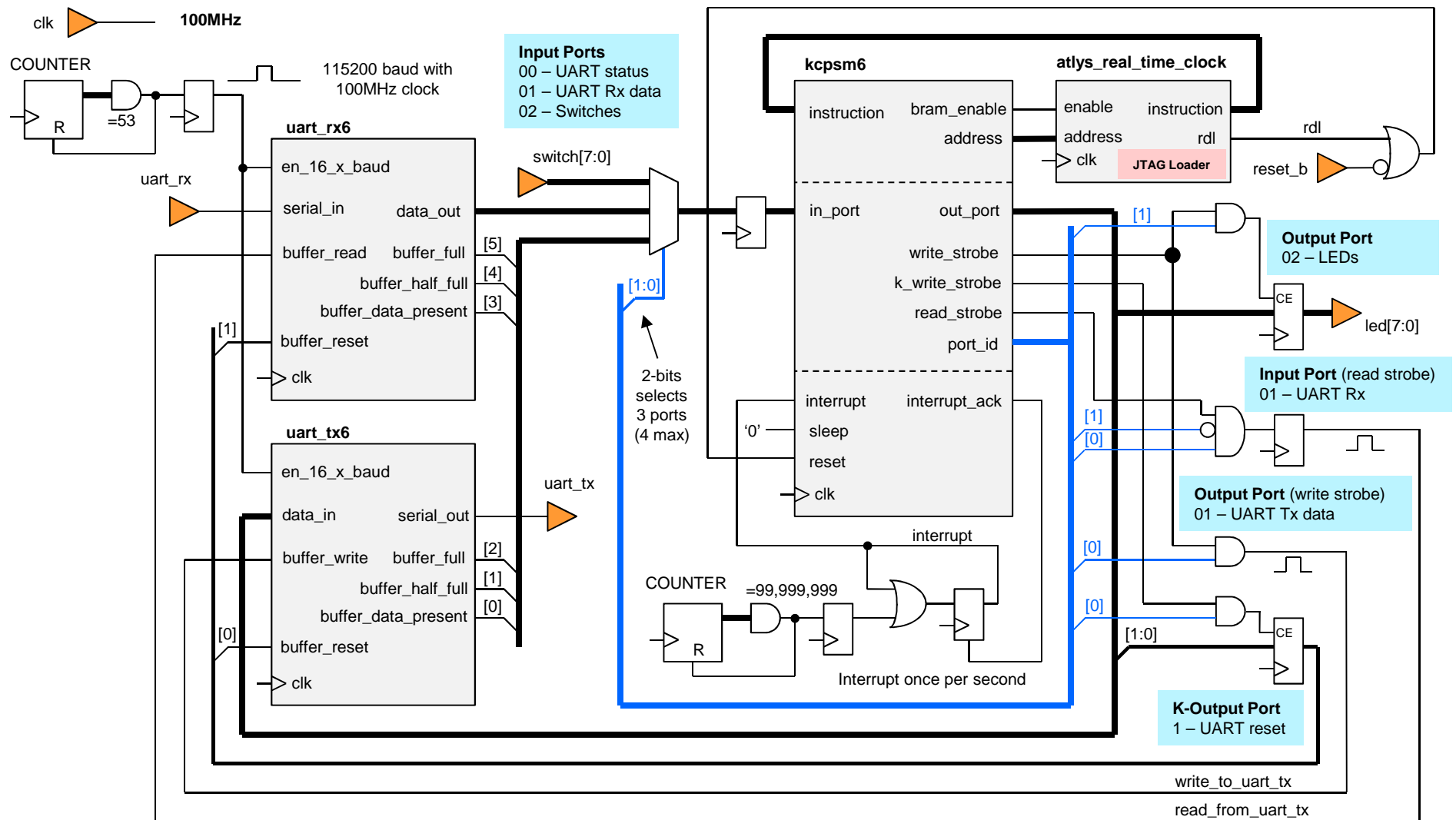
uart6_ml605

This diagram represents the circuit provided in 'uart6_ml605.vhd' (or '.v') but the same ports are assigned to the UART macros in 'uart6_atlys.vhd'.



uart6_atlys

This diagram represents the circuit provided in 'uart6_atlys.vhd' (or '.v'). Note that the UART interface is the same as in 'uart6_ml605.vhd'.



KCPSM6 Interface with UART6 Macros

All code shown below is provided in 'uart6_ml605.vhd' (or '.v') and 'uart_interface_routines.psm' (or 'PicoTerm_routines.psm').

'uart6_atlys.vhd' (or '.v') is slightly different due to having additional ports to read switches and drive LEDs but the UART port assignments remain the same.

```
input_ports: process(clk)
begin
    if clk'event and clk = '1' then
        case port_id(0) is

            -- Read UART status at port address 00 hex
            when '0' =>
                in_port(0) <= uart_tx_data_present;
                in_port(1) <= uart_tx_half_full;
                in_port(2) <= uart_tx_full;
                in_port(3) <= uart_rx_data_present;
                in_port(4) <= uart_rx_half_full;
                in_port(5) <= uart_rx_full;

            -- Read UART_RX6 data at port address 01 hex
            when '1' =>
                in_port <= uart_rx_data_out;

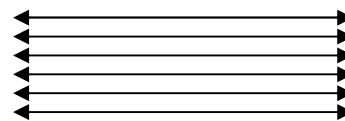
            when others =>
                in_port <= "XXXXXXXX";
        end case;

        if (read_strobe = '1') and (port_id(0) = '1') then
            read_from_uart_rx <= '1';
        else
            read_from_uart_rx <= '0';
        end if;
    end if;
end process input_ports;
```

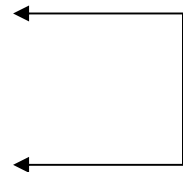
```
write_to_uart_tx <= '1' when (write_strobe = '1') and (port_id(0) = '1')
else '0';
```

```
constant_output_ports: process(clk)
begin
    if clk'event and clk = '1' then
        if k_write_strobe = '1' then
            if port_id(0) = '1' then
                uart_tx_reset <= out_port(0);
                uart_rx_reset <= out_port(1);
            end if;
        end if;
    end if;
end process constant_output_ports;
```

The extracts of VHDL shown on the left hand side (from 'uart6_ml605.vhd') define the three ports forming the interface with the UART macros. Below are a set of CONSTANT declarations in the PSM code that correspond with the hardware port allocations and enable the PSM code routines to be more portable as well as easier to write and understand.

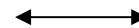


```
CONSTANT UART_status_port, 00
CONSTANT UART_Tx_data_present, 00000001'b
CONSTANT UART_Tx_half_full, 00000010'b
CONSTANT UART_Tx_full, 00000100'b
CONSTANT UART_Rx_data_present, 00001000'b
CONSTANT UART_Rx_half_full, 00010000'b
CONSTANT UART_Rx_full, 00100000'b
```



```
CONSTANT UART_RX6_input_port, 01
```

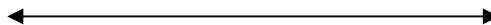
Reading 'uart_rx6' buffer captures the data and generates the 'buffer_read' pulse from the 'read-strobe'.



```
CONSTANT UART_TX6_output_port, 01
```

Hint - When decoding more bits of 'port_id' then your code would take the form....

```
and (port_id(2 downto 0) = "001")
```



```
CONSTANT reset_UART_port, 01
CONSTANT UART_tx_reset, 00000001'b
CONSTANT UART_rx_reset, 00000010'b
CONSTANT UART_reset, 00000011'b ;reset Tx and Rx
CONSTANT UART_operate, 00000000'b ; Tx and Rx free to operate
```

KCPSM6 Interface with UART6 Macros

All code shown below is provided in 'uart_interface_routines.psm'.

'PicoTerm_routines.psm' has the same 'UART_TX' code but contains an enhanced 'UART_RX' routine (plus additional routines) to exploit PicoTerm features.

```
;------  
; Routine to send one character to the UART Transmitter (UART_TX6)  
;------  
;  
; This routine will transmit the character provided in register 's5'.  
;
```

```
UART_TX: INPUT s0, UART_status_port      ;Check if buffer is full  
TEST s0, UART_Tx_full  
JUMP NZ, UART_TX  
OUTPUT s5, UART_TX6_output_port ;write character to buffer  
RETURN
```

```
;------  
; Routine to attempt to receive one character from the UART Receiver (UART_RX6)  
;------  
;  
; This routine will attempt to receive one character from the 'UART_RX6' macro, and if  
; successful, will return that character in register 's5' and the Zero flag will be  
; reset (Z=0).  
;
```

```
UART_RX: LOAD s1, 167'd                ;Timeout = 167 x (6 instructions x 2 clock cycles)  
rx_timeout: INPUT s0, UART_status_port  
TEST s0, UART_Rx_data_present        ;Z=0 when data present  
JUMP NZ, read_Rx  
SUB s1, 1'd  
RETURN Z                               ;Timeout returns with Z=1  
JUMP rx_timeout  
;  
read_Rx: INPUT s5, UART_RX6_input_port ;read character from buffer  
RETURN
```

```
;------  
; Routine to reset UART Buffers inside 'UART_TX6' and 'UART_RX6'  
;------
```

```
reset_UART_macros: OUTPUTK UART_reset, reset_UART_port  
OUTPUTK UART_operate, reset_UART_port
```

These simple PSM subroutines enable characters to be transmitted and received using the UART macros.

Transmit

It is vital that no characters are written to the transmitter FIFO buffer if it is full. This routine tests the 'buffer_full' flag and unless it is Low (0) it will wait until it is before executing the OUTPUT instruction to write data to the transmitter FIFO.

Receive

The key requirement is that a read only occurs when there is a character waiting to be read from the receiver FIFO buffer. So this routine tests the 'buffer_data_present' flag to ensure that it is High (1) before executing the INPUT instruction to read a character.

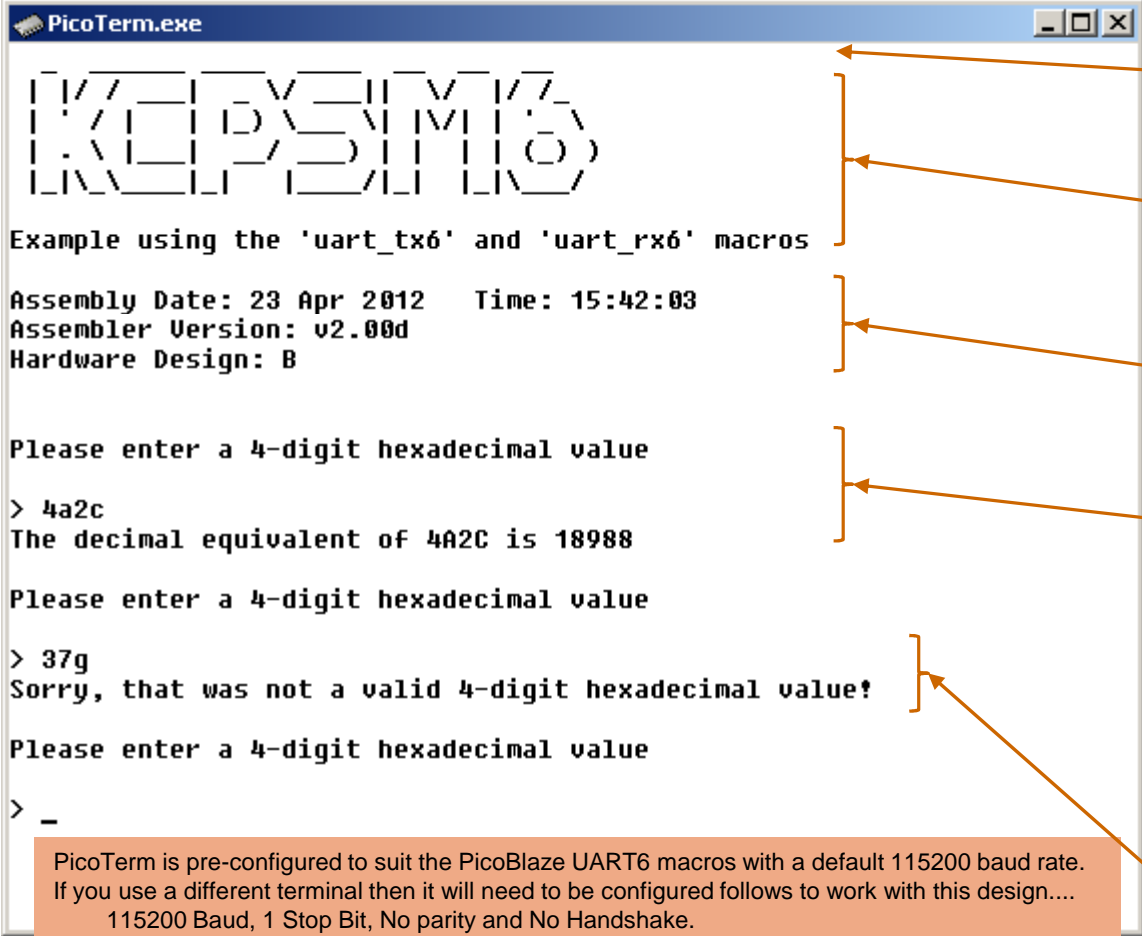
This routine also includes a timeout to prevent KCPSM6 waiting indefinitely for 'uart_rx6' to receive a valid character. This could be used to detect a break in communications or allow KCPSM6 to perform some other tasks.

Hint – The 'timeout' feature can be removed for many applications.

Reset – Generates active High reset pulses with a duration of 2 clock cycles to both 'uart_tx6' and 'uart_rx6'.

Example Program: uart_control.psm

The 'uart_control.psm' program includes several routines that demonstrate typical uses of the UART macros when communicating with a simple terminal such as PicoTerm (provided with PicoBlaze and the UART macros) or HyperTerminal. The screen capture below shows PicoTerm when connected to the ML605 Evaluation Board running the reference design. Note that the ML605 has a USB-UART bridge with a corresponding virtual COM port on the PC.



The display is cleared by KCP605 sending **ANSI Escape Sequences** using 'uart_tx6'.

Printing or displaying **text strings** is a very common application. The STRING directive combined with the LOAD&RETURN instruction makes sending text strings to 'uart_tx6' straightforward.

These text strings pick up on the **version information** provided by the KCP605 assembler and the 'hwbuild' generic in the VHDL design. A very simple way to track the build state and date/time stamp any design.

This reference code implements a **hexadecimal to decimal converter**. In so doing it receives characters entered by the user on their keyboard via the 'uart_rx6' and performs the following...

- Accepts upper or lower case characters.
- Converts lower to upper case.
- ASCII Hex to binary conversion
- Including trap for non-hex characters.
- Display of binary value in ASCII Hex.
- 16-bit binary to 5-digit BCD (Binary Coded Decimal)
- Display of BCD with leading zero blanking.

Error checking and reporting.

PicoTerm is pre-configured to suit the PicoBlaze UART6 macros with a default 115200 baud rate. If you use a different terminal then it will need to be configured follows to work with this design....
115200 Baud, 1 Stop Bit, No parity and No Handshake.
ASCII setup to perform a line feed when receiving a carriage return.

Example Program: atlys_real_time_clock.psm

The 'atlys_real_time_clock.psm' program also displays text and interacts with user keyboard entries in a similar way to the 'uart6_ml605.psm' program (see previous page). However, this program specifically exploits and demonstrates some of the special features of PicoTerm so PicoTerm must be used. The hardware design includes additional ports which interface with 8 switches and 8 LEDs on the ATLYS board and the program passes information between those switches, LEDs and PicoTerm. The design also generates interrupts at one second intervals which the program uses to maintain a real time clock. Note that ATLYS also provides a USB-UART bridge with a corresponding virtual COM port on the PC.

```
PicoTerm.exe

ATLYS

Reference Design: UART macros and PicoTerm Features
Real Time Clock includes interrupt handling

Assembly Date: 06 Sep 2012   Time: 13:46:25
Assembler Version: v2.31
Hardware Design: A

PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!
PicoTerm can display text in 8 colours!

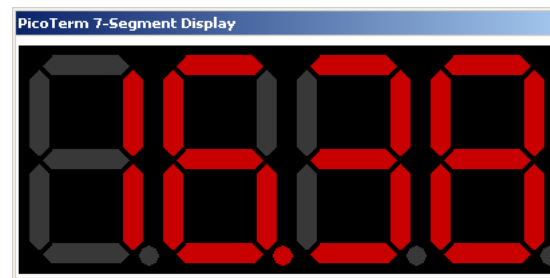
Please select an LED to toggle (0 to 7)

> 5
> 3
> -
```

Keyboard ASCII characters entered at the keyboard are checked and when valid used to toggle the *physical* LEDs on the ATLYS board.

Hint - 'PicoTerm_README.txt' includes descriptions of the PicoTerm features as well as basic usage. "PicoTerm_routines.psm" contains routines to work with each of the features with full descriptions.

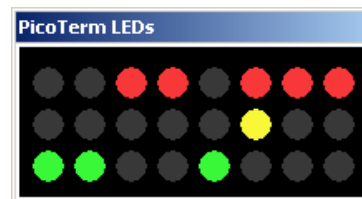
Main terminal window control includes ability to change text colour and printing of **text strings** using the STRING directive combined with the LOAD&RETURN instruction.



Interrupts trigger a Interrupt Service Routine (ISR) which implements a real time clock (hours, minutes and seconds). The time is displayed on the PicoTerm *virtual* 7-Segment Display window via the transmission of Device Control Strings (DCS).

```
PicoTerm DCS Transactions
Ping!
Request Time Value -> 0F 08 07
```

The program will also transmit a DCS to confirm that PicoTerm is connected and another DCS to request the time from your PC. These are all examples of UART communication but specific to the special features available with PicoTerm.



The setting of the *physical* switches on the ATLYS board are displayed on the PicoTerm *virtual* LED window via the transmission of Device Control Strings (DCS).
Red = Switch ON Green = Switch OFF,
Amber identifies last switch that was changed.

Improving BAUD Accuracy

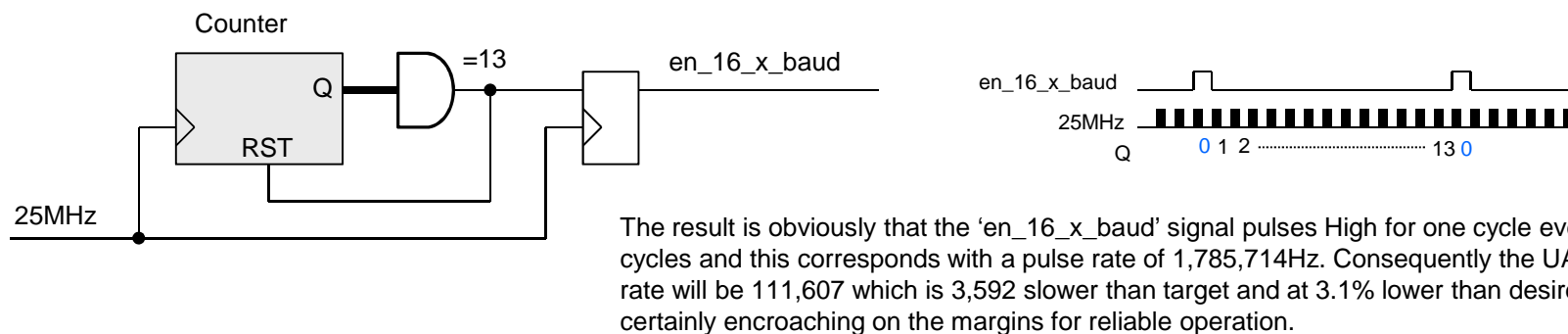
As described on pages 7 and 8 the baud rate is defined by the rate at which enable pulses are applied to the 'en_16_x_baud' input of each macro. In the vast majority of cases the desired baud rate will be achieved by a simple division of the system clock. Generally speaking an accuracy of $\pm 5\%$ is adequate but it should be remembered that this figure must account for the *total* potential difference between the baud rate of the transmitter and the baud rate of the receiver forming the link. As such, it would be unwise to consume all of the $\pm 5\%$ budget for your end of a link with the assumption that the other end is perfect.

Except in situations where the desired baud rate is an exact integer division of the system clock frequency then the potential for greater baud rate inaccuracy increases the higher the desired baud rate is relative to the clock. This is best covered by an example....

Desired baud rate = 115,200 \Rightarrow Hence the target 'en_16_x_baud' pulse rate = 1,843,200 Hz

Reference clock = 25MHz

This implies that the 'en_16_x_baud' pulses should be derived by dividing the 25MHz clock by 13.56 which does not appear to be possible so we select the nearest integer value of 14 and see what happens.....



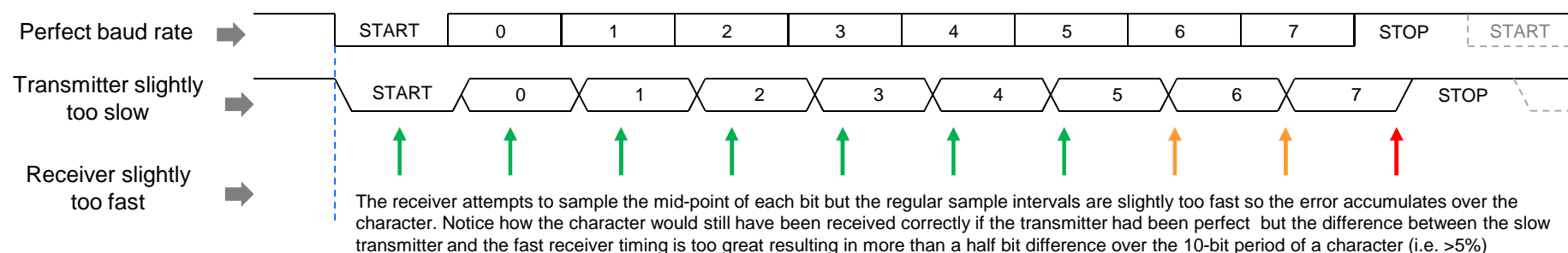
One solution is to lower the baud rate or increase the clock rate but in most cases we have been 'dealt the playing cards' and rarely have the luxury to change either. In situations where you really want to exploit a higher baud rate it is also undesirable to lower the baud rate and a higher frequency clock may be impossible to work with. So we need to achieve the equivalent of a non-integer division and fortunately that is easier to implement than you may first think it to be....

Improving BAUD Accuracy

The period of each serial bit is defined by the application of 16 pulses to the 'en_16_x_baud' input. To be more correct, a bit period is defined by 16 rising edges of the clock enabled by 'en_16_x_baud' because in some situations the enable input may be permanently High or driven with a less obvious waveform as we will go on to consider on the next page.

The 'uart_tx6' transmitter macro uses each 16 enable pulses to generate the serial waveform with the desired baud rate timing. Whilst a 5% deviation from the ideal timing of a bit period may seem trivial the problem is that the error accumulates over the transmission of a complete character formed of 10-bit periods (start bit, 8-data bits and a stop bit). This means that the receiver at the other end of the line may have difficulty correctly receiving the stop bit or even the MSB's of the data byte. Of course if the receiver timing deviates from the ideal baud rate in the same direction as the transmitter then they cancel each other out and can be considered a 'matching pair'. However, unless you have full control over both ends of a communication link then the opposite could be true and failure would be almost certain.

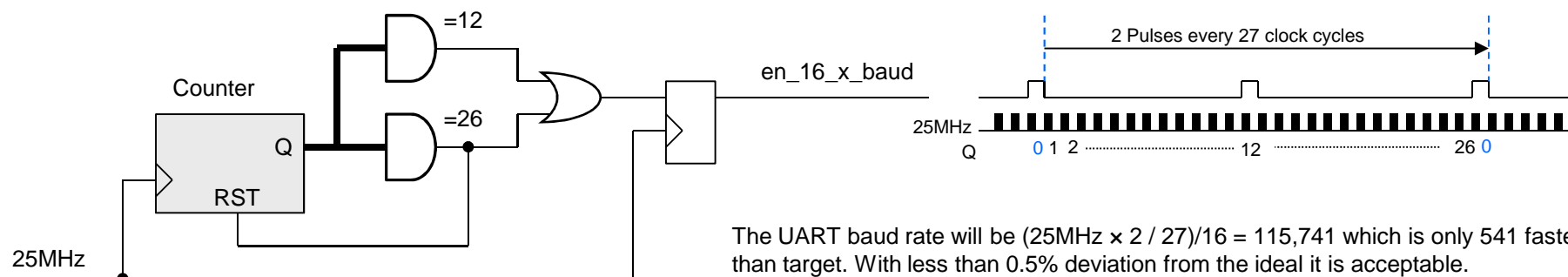
In a similar way the 'uart_tx6' receiver macro also uses each 16 enable pulses to determine the bit period of the serial waveform but uses this reference in a particular way. Initially the receiver only looks at the serial line waiting for the High to Low transition associated with the beginning of a start bit. The point at which this occurs is the reference point in time for the character that follows over 10 bit periods (start bit, 8-data bits and a stop bit). The robust communications qualities of the UART can be attributed to this resynchronisation at the beginning of each character combined with each bit of the character being sampled clear of any switching transitions. In other words, the receiver will attempt to sample each bit in the middle where it is stable and 'uart_tx6' achieves this by counting the enable pulses following the beginning of the start bit. After 8 enable pulses it should be the middle of the start bit which it checks is still Low to help reject glitches. Then every 16 enable pulses should correspond with the middle of the next bit. As with the transmitter, a 5% deviation from the ideal timing of a bit period may seem trivial but the error accumulates. The sampling of the stop bit is defined by the $(8+(9 \times 16))=152$ enable pulses that are applied to the macro since the beginning of the start bit and for reliable operation the stop bit really needs to be sampled whilst the stop bit is stable. Sample too early and the MSB data may still be present or the serial line may still be switching. Sample too late and the serial line could be switching, or have switched, to the start bit of the next character.



The key observations that each bit period defined by 16 enable pulses *and* that a complete character is defined by 160 enable pulses. Therefore the focus for improved baud accuracy is to consider a scheme in which it is the time taken to generate 16 enable pulses that is important rather than the regular precise timing of every individual pulse.

Improving BAUD Accuracy

Returning to the example in which we desire a 115,200 baud rate but only have a 25MHz reference we know that in an ideal world we would need to generate an 'en_16_x_baud' pulse every 13.56 clock cycles. However we also know that we only need to *average* this rate and therefore we don't have to settle for a fixed integer division. In this example an average of 13.5 clock cycles per enable pulse can be achieved by alternating clock division between 13 and 14 clock cycles. That's two pulses every 27 clock cycles resulting in an almost perfect average both within a bit period and across a whole character.



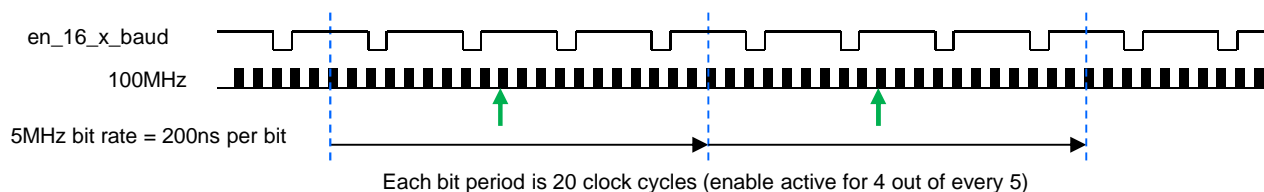
The combination of target baud rate and clock frequency used in the example above may look as if it was chosen to be convenient but it is actually a real case study. Remember that the initial inaccuracy of 3.1% was due to the inconvenience of the ideal division factor of 13.56 falling almost mid-way between two integer values (13 and 14). This means that using a scheme similar to above is the solution to the worst case error associated with simple rounding with ideal division factors now only being rounded by up to a maximum of 0.25 (e.g. 12.5 is the rounding of values 12.26 through to 12.74).

Accuracy at Higher Baud Rates

Obtaining relatively high baud rates with accuracy can be the greatest challenge but whilst the general appearance of the 'en_16_x_baud' waveform is different the same principles apply.

Example

Desired baud rate = 5Mbps
Reference clock = 100MHz



The required 'en_16_x_baud' pulse rate is $16 \times 5\text{MHz} = 80\text{MHz}$ implying a clock division factor of 1.2. In other words the input needs to be High most of the time but can not be permanently High as that would equate to 6.25MHz (25% too fast). The solution is to drive the enable with a waveform that is High for 4 clock cycles and Low for 1 clock cycle. In this way the macro is enabled for 4/5 of the clock cycles which means that the baud rate is perfect $(100\text{MHz} \times 4 / 5) / 16 = 5\text{Mbps}$. Transmission is perfect and the receiver will sample each bit close to the mid-point (average 20 clock cycles per bit period).

An Alternative: 100% Soft PicoBlaze UART

The 'uart_tx6' and 'uart_rx6' are each only 5 Slices, and combined with their integrated FIFO buffers, do represent a compelling and easy way to implement reliable UART communication schemes. However, many applications could implement a UART purely in KCPSM6 PSM code as these examples show.

```
CONSTANT UART_input_port, 04      ; Receive serial data
CONSTANT UART_output_port, 10     ; Transmit serial data
CONSTANT serial_data, 00000001'b  ; bit0 - serial data
LOAD s0, serial_data
OUTPUT s0, UART_output_port      ; initialise serial output
```

Simple I/O ports are assigned enabling the serial output to be driven directly and the serial input to be monitored. The serial output needs to be High (1) in the idle state.

Transmitter – Every KCPSM6 instruction executes in 2 clock cycles so it is possible to generate the correct UART waveform with reasonable accuracy for most typical baud rates (baud rate is slow relative to the clock frequency).

```
; Software implemented UART Transmitter  This example if for 115200 baud using a 50MHz clock
;
; Transmits one character provided in 's5' at 115200 baud with 1 start bit, 1 stop bit
; and no parity. All timing is based on a 50MHz clock where each bit period is equivalent
; to 217 instructions.
;
; Registers used s0, s1, s2 (and s5 for the data which is preserved)
;
UART_TX: LOAD s0, 00                      ;start bit (Low)
CALL UART_TX_bit
LOAD s2, 8'd                             ;8 bits to transmit
TX_loop: RR s5                           ;transmit LSB first
SLA s0                                    ;move each data bit into bit0 of s0 (via C flag)
CALL UART_TX_bit                          ;transmit data bit
SUB s2, 1'd                               ;count bits transmitted
JUMP NZ, TX_loop                         ;After 8 bits 's5' is back to original value
LOAD s0, 01                              ;stop bit
CALL UART_TX_bit
RETURN
;
; Each bit (contained in bit0 of 's0') is transmitted for a period of approximately 217
; instructions. The delay implemented below is slightly less to account for the
; 5 instructions taken to prepare each bit to be transmitted in the code above.
;
UART_TX_bit: OUTPUT s0, UART_output_port
LOAD s1, 106'd                           ;106 x 2 = 212
TX_bit_loop: SUB s1, 1'd
JUMP NZ, TX_bit_loop
RETURN
```

The transmitter is the most practical to implement in software because your PicoBlaze program knows when it wants to transmit information.

When it transmits, KCPSM6 is totally dedicated to the task and therefore it will be unavailable to perform other tasks. This could be a relatively long time at lower baud rates (e.g. ~1ms per character at 9600 baud) but if that is all the application needs to do then putting KCPSM6 to good use during this time saves 5 Slices. If there are other tasks to perform then it is far better to use the 'uart_tx6' macro.

When KCPSM6 has no information to transmit the serial output is left parked in the High (1) state and KCPSM6 is totally free to perform other tasks.

An Alternative: 100% Soft PicoBlaze UART

```
; Software implemented UART Receiver This example if for 115200 baud using a 50MHz clock
;
; Receives one character into 's5' at 115200 baud with 1 start bit, 1 stop bit and no
; parity. All timing is based on a 50MHz clock where each bit period is equivalent to 217
; instructions. A valid character is signified by Z=0 and C=0. A timeout (~51us with no
; serial activity) is signified by Z=1 and C=0. When serial activity is detected but
; character is invalid then Z=0 and C=1.
;
; Registers used s0, s1, s2 and s5.
;
UART_RX: LOAD s1, 255'd                ;Detect beginning of start bit (0) or timeout
rx_timeout: INPUT s0, UART_input_port  ; 255 x 5 = 1275 instructions or ~51us.
TEST s0, serial_data                 ;test serial input for change to '0'
JUMP Z, start_bit
SUB s1, 1'd
JUMP NZ, rx_timeout
RETURN                                ;Timeout returns with Z=1 and C=0
;
start_bit: LOAD s1, 51'd               ;Wait until middle of start bit
mid_start_delay: SUB s1, 1'd           ;51 x 2 = 102 instruction delay
JUMP NZ, mid_start_delay
INPUT s0, UART_input_port
SR1 s0
RETURN C
;
LOAD s2, 08                          ;8 bits to receive
RX_loop: LOAD s1, 105'd               ;Loop delay is (105 x 2) + 6 = 216 instructions
rx_bit_delay: SUB s1, 1'd
JUMP NZ, rx_bit_delay
INPUT s0, UART_input_port            ;sample data bit at mid-point
SR0 s0                               ;move data bit into carry flag
SRA s5                               ;Shift data bit into 's5' LSB first
SUB s2, 1'd                          ;count 8 bits
JUMP NZ, RX_loop
;
; Finally wait one more bit period and sample the stop bit which should be High.
; If it is Low then set carry flag to indicate error. But if it is High the
; character is good and the return must be made with Z=0.
;
stop_bit: LOAD s1, 106'd              ;Wait until middle of stop bit
stop_bit_delay: SUB s1, 1'd           ;(106 x 2) + 5 = 217 instructions
JUMP NZ, stop_bit_delay
INPUT s0, UART_input_port
XOR s0, serial_data
SR1 s0
RETURN                                ;test for stop bit = '1'
;                                     ;invert bit so that correct value for carry flag
;                                     ;shift inverted bit into carry flag force Z=0
;                                     ;For good character return with Z=0 and C=0
```

Receiver – Every KCPSM6 instruction executes in 2 clock cycles so it is possible to analyse the activity on the serial input with reasonable accuracy for most typical baud rates (baud rate is slow relative to the clock frequency). However, it is immediately obvious from this example that receiving is more of a challenge than transmitting!

The single biggest issue with adopting a software UART receiver is that KCPSM6 must detect the beginning of the start bit otherwise a character will appear corrupted or missed altogether. This means that your program really needs to be able to anticipate when a character is about to be received and then dedicate itself to the task of receiving. This is practical in some applications; for example; when there is nothing else to do except wait for a user input in response to a prompt just issued.

However, the naturally asynchronous nature of UART really does make the 'uart_rx6' macro the more natural choice especially with its internal FIFO buffer.