nRF9160

Product Specification v2.0

nRF9160 features

Features:

- **Microcontroller:**
- ARM Cortex -M33
	- 243 EEMBC CoreMark score running from flash memory
	- Data watchpoint and trace (DWT), embedded trace macrocell (ETM), and instrumentation trace macrocell (ITM)
	- Serial wire debug (SWD)
	- Trace port
- 1 MB flash
- 256 kB low leakage RAM
- ARM Trustzone
- ARM Cryptocell 310
- Up to 4x SPI master/slave with EasyDMA
- Up to 4x I2C compatible two-wire master/slave with EasyDMA
- Up to 4x UART (CTS/RTS) with EasyDMA
- I2S with EasyDMA
- Digital microphone interface (PDM) with EasyDMA
- 4x pulse width modulator (PWM) unit with EasyDMA
- 12-bit, 200 ksps ADC with EasyDMA eigth configurable channels with programmable gain
- 3x 32-bit timer with counter mode
- 2x real-time counter (RTC)
- Programmable peripheral interconnect (PPI)
- 32 general purpose I/O pins
- Single supply voltage: 3.0 5.5 V
- All necessary clock sources integrated
- Package: 10 × 16 x 1.04 mm LGA

LTE modem:

- Transceiver and baseband
- 3GPP LTE release 13 Cat-M1 and Cat-NB1 compliant
	- 3GPP release 13 coverage enhancement
- 3GPP LTE release 14 Cat-NB2 compliant
- GPS receiver
	- GPS L1 C/A supported
- RF transceiver for global coverage
	- Up to 23 dBm output power
	- -108 dBm sensitivity (LTE-M) for low band, -107 dBm for mid band
	- Single 50 Ω antenna interface
- LTE band support in hardware:
	- Cat-M1: B1, B2, B3, B4, B5, B8, B12, B13, B14, B17, B18, B19, B20, B25, B26, B28, B66
	- Cat-NB1/NB2: B1, B2, B3, B4, B5, B8, B12, B13, B17, B19, B20, B25, B26, B28, B66
- Supports SIM and eSIM with an ETSI TS 102 221 compatible UICC interface
- Power saving features: DRX, eDRX, PSM
- IP v4/v6 stack
- Secure socket (TLS/DTLS) API

Current consumption @ 3.7 V:

- Power saving mode (PSM) floor current: 2.7 µA
- eDRX @ 82.91s: 18 µA in Cat-M1, 37 µA in Cat-NB1 (UICC included)

Applications:

- Sensor networks
- Logistics and asset tracking
- Smart energy
- Smart building automation
- Smart agriculture
- Industrial
- Retail and monitor devices
- Medical devices
- Wearables

Contents

1 Revision history

2 About this document

This document is organized into chapters that are based on the modules and peripherals available in the IC. The relevant Product Specification version for each nRF9160 revision is described by the [nRF9160](https://infocenter.nordicsemi.com/topic/comp_matrix_nrf9160/COMP/nrf9160/nrf9160_doc_ref_design_files_overview.html) [Compatibility Matrix](https://infocenter.nordicsemi.com/topic/comp_matrix_nrf9160/COMP/nrf9160/nrf9160_doc_ref_design_files_overview.html).

2.1 Document status

The document status reflects the level of maturity of the document.

Table 1: Defined document names

2.2 Peripheral chapters

Every peripheral has a unique capitalized name or an abbreviation of its name, e.g. TIMER, used for identification and reference. This name is used in chapter headings and references, and it will appear in the ARM Cortex Microcontroller Software Interface Standard (CMSIS) hardware abstraction layer to identify the peripheral.

The peripheral instance name, which is different from the peripheral name, is constructed using the peripheral name followed by a numbered postfix, starting with 0, for example, TIMER0. A postfix is normally only used if a peripheral can be instantiated more than once. The peripheral instance name is also used in the CMSIS to identify the peripheral instance.

The chapters describing peripherals may include the following information:

- A detailed functional description of the peripheral
- Register configuration for the peripheral
- Electrical specification tables, containing performance data which apply for the operating conditions described in [Peripheral chapters](#page-10-2) on page 11.

2.3 Register tables

Individual registers are described using register tables. These tables are built up of two sections. The first three colored rows describe the position and size of the different fields in the register. The following rows describe the fields in more detail.

2.3.1 Fields and values

The **Id (Field Id)** row specifies the bits that belong to the different fields in the register. If a field has enumerated values, then every value will be identified with a unique value id in the **Value Id** column.

A blank space means that the field is reserved and read as undefined, and it also must be written as 0 to secure forward compatibility. If a register is divided into more than one field, a unique field name is specified for each field in the **Field** column. The **Value Id** may be omitted in the single-bit bit fields when values can be substituted with a Boolean type enumerator range, e.g. true/false, disable(d)/enable(d), on/ off, and so on.

Values are usually provided as decimal or hexadecimal. Hexadecimal values have a $0 \times$ prefix, decimal values have no prefix.

The **Value** column can be populated in the following ways:

- Individual enumerated values, for example 1, 3, 9.
- Range of values, e.g. [0..4], indicating all values from and including 0 and 4.
- Implicit values. If no values are indicated in the **Value** column, all bit combinations are supported, or alternatively the field's translation and limitations are described in the text instead.

If two or more fields are closely related, the **Value Id**, **Value**, and **Description** may be omitted for all but the first field. Subsequent fields will indicate inheritance with '..'.

A feature marked **Deprecated** should not be used for new designs.

2.3.2 Permissions

Different fields in a register might have different access permissions enforced by hardware.

The access permission for each register field is documented in the **Access** column in the following ways:

Table 2: Register field permission schemes

2.4 Registers

Table 3: Register overview

2.4.1 DUMMY

Address offset: 0x514

Example of a register controlling a dummy feature

Product overview

3.1 Introduction

The nRF9160 is a low-power cellular IoT (Internet of Things) solution, integrating an ARM $^{\circledR}$ Cortex $^{\circledR}$ -M33 processor with advanced security features, a range of peripherals, as well as a complete LTE modem compliant with 3GPP LTE release 13 Cat-M1 and Cat-NB1, and 3GPP LTE release 14 Cat-NB1 and Cat-NB2 standards.

The ARM Cortex-M33 processor is exclusively for user application software, and it offers 1 MB of flash and 256 kB of RAM dedicated to this use. The M33 application processor shares the power, clock and peripheral architecture with Nordic Semiconductor nRF51 and nRF52 Series of PAN/LAN SoCs, ensuring minimal porting efforts.

The peripheral set offers a variety of analog and digital functionality enabling single-chip implementation of a wide range of cellular IoT (Internet of Things) applications. ARM TrustZone technology, Cryptocell 310 and supporting blocks for system protection and key management, are embedded to enable advanced security needed for IoT applications.

The LTE modem integrates a very flexible transceiver that in hardware supports frequency range from 700 to 2200 MHz (through a single 50 Ω antenna pin), and a baseband processor handling LTE Cat-M1/ NB1/NB2 protocol layers L1-L3 as well as IP upper layers offering secure socket API for the application. The modem is supported by pre-qualified software builds available for free from Nordic Semiconductor.

On specific nRF9160 device variants, the LTE modem supports A-GPS operation during sleep intervals in the LTE operation (RRC idle and PSM modes).

Note: Cat-NB2 is supported in LTE modem HW, but needs modem firmware support to get enabled. Please refer to *nRF9160 modem firmware release notes* found under nRF91 FW binaries downloads concerning availability of Cat-NB2 feature support".

3.2 Block diagram

This block diagram illustrates the overall system. Arrows with white heads indicate signals that share physical pins with other signals.

Figure 1: Block diagram

3.3 Peripheral interface

Peripherals are controlled by the CPU through configuration registers, as well as task and event registers. Task registers are inputs, enabling the CPU and other peripherals to initiate a functionality. Event registers are outputs, enabling a peripheral to trigger tasks in other peripherals and/or the CPU by tying events to CPU interrupts.

Figure 2: Peripheral interface

The distributed programmable peripheral interconnect (DPPI) feature enables peripherals to connect events to tasks without CPU intervention.

Note: For more information on DPPI and the DPPI channels, see [DPPI - Distributed programmable](#page-85-0) [peripheral interconnect](#page-85-0) on page 86.

3.3.1 Peripheral ID

Every peripheral is assigned a fixed block of 0x1000 bytes of address space, which is equal to 1024 x 32 bit registers.

See [Instantiation](#page-23-0) on page 24 for more information about which peripherals are available and where they are located in the address map.

There is a direct relationship between peripheral ID and base address. For example, a peripheral with base address 0x40000000 is assigned ID=0, a peripheral with base address 0x40001000 is assigned ID=1, and a peripheral with base address 0x4001F000 is assigned ID=31.

Peripherals may share the same ID, which may impose one or more of the following limitations:

- Shared registers or common resources
- Limited availability due to mutually exclusive operation; only one peripheral in use at a time

• Enforced peripheral behavior when switching between peripherals (disable the first peripheral before enabling the second)

3.3.2 Peripherals with shared ID

In general (with the exception of ID 0), peripherals sharing an ID and base address may not be used simultaneously. Only one peripheral can be enabled at a given ID.

When switching between two peripherals sharing an ID, the following should be performed to prevent unwanted behavior:

- **1.** Disable the previously used peripheral.
- **2.** Disable any publish/subscribe connection to the DPPI system for the peripheral that is being disabled.
- **3.** Clear all bits in the INTEN register, i.e. INTENCLR = 0xFFFFFFFF.
- **4.** Explicitly configure the peripheral being enabled. Do not rely on inherited configuration from the disabled peripheral.
- **5.** Enable the now configured peripheral.

For a list of which peripherals that share an ID see [Instantiation](#page-23-0) on page 24.

3.3.3 Peripheral registers

Most peripherals feature an ENABLE register. Unless otherwise specified, the peripheral registers must be configured before enabling the peripheral.

PSEL registers need to be set before a peripheral is enabled or started. Updating PSEL registers while the peripheral is running has no effect. In order to connect a peripheral to a different GPIO, the peripheral must be disabled, the PSEL register updated, and the peripheral re-enabled. It takes four CPU cycles between the PSEL register update and the connection between a peripheral and a GPIO becoming effective.

Note: Note that the peripheral must be enabled before tasks and events can be used.

Most of the register values are lost during System OFF or when a reset is triggered. Some registers will retain their values in System OFF or for some specific reset sources. These registers are marked as retained in the register description for a given peripheral. For more information on their behavior, see chapter [Reset](#page-55-0) on page 56.

3.3.4 Bit set and clear

Registers with multiple single-bit bit fields may implement the set-and-clear pattern. This pattern enables firmware to set and clear individual bits in a register without having to perform a read-modify-write operation on the main register.

This pattern is implemented using three consecutive addresses in the register map, where the main register is followed by dedicated SET and CLR registers (in that exact order).

In the main register, the SET register sets individual bits and the CLR register clears them. Writing '1' to a bit in the SET or CLR register will set or clear the same bit in the main register respectively. Writing '0' to a bit in the SET or CLR register has no effect. Reading the SET or CLR register returns the value of the main register.

Note: The main register may not be visible and therefore not directly accessible in all cases.

3.3.5 Tasks

Tasks are used to trigger actions in a peripheral, such as to start a particular behavior. A peripheral can implement multiple tasks with each task having a separate register in that peripheral's task register group.

A task is triggered when firmware writes '1' to the task register, or when the peripheral itself or another peripheral toggles the corresponding task signal. See the figure [Peripheral interface](#page-15-1) on page 16.

3.3.6 Events

Events are used to notify peripherals and the CPU about events that have happened, for example a state change in a peripheral. A peripheral may generate multiple events, where each event has a separate register in that peripheral's event register group.

An event is generated when the peripheral itself toggles the corresponding event signal, and the event register is updated to reflect that the event has been generated, see figure [Peripheral interface](#page-15-1) on page 16. An event register is cleared when a '0' is written to it by firmware. Events can be generated by the peripheral even when the event register is set to '1'.

3.3.7 Publish and subscribe

Events and tasks from different peripherals can be connected together through the DPPI system using the PUBLISH and SUBSCRIBE registers in each peripheral. See [Peripheral interface](#page-15-1) on page 16. An event can be published onto a DPPI channel by configuring the event's PUBLISH register. Similarly, a task can subscribe to a DPPI channel by configuring the task's SUBSCRIBE register.

See [DPPI - Distributed programmable peripheral interconnect](#page-85-0) on page 86 for details.

3.3.8 Shortcuts

A shortcut is a direct connection between an event and a task within the same peripheral. If a shortcut is enabled, the associated task is automatically triggered when its associated event is generated.

Using shortcuts is equivalent to making the connection outside the peripheral and through the DPPI. However, the propagation delay when using shortcuts is usually shorter than the propagation delay through the DPPI.

Shortcuts are predefined, which means that their connections cannot be configured by firmware. Each shortcut can be individually enabled or disabled through the shortcut register, one bit per shortcut, giving a maximum of 32 shortcuts for each peripheral.

3.3.9 Interrupts

All peripherals support interrupts which are generated by events.

A peripheral only occupies one interrupt, and the interrupt number follows the peripheral ID. For example, the peripheral with ID=4 is connected to interrupt number 4 in the nested vectored interrupt controller (NVIC).

Using registers INTEN, INTENSET, and INTENCLR, every event generated by a peripheral can be configured to generate that peripheral's interrupt. Multiple events can be enabled to generate interrupts simultaneously. To resolve the correct interrupt source, the event registers in the event group of peripheral registers will indicate the source.

Some peripherals implement only INTENSET and INTENCLR registers, and the INTEN register is not available on those peripherals. See the individual peripheral chapters for details. In all cases, reading back the INTENSET or INTENCLR register returns the same information as in INTEN.

Each event implemented in the peripheral is associated with a specific bit position in the INTEN, INTENSET, and INTENCLR registers.

The relationship between tasks, events, shortcuts, and interrupts is illustrated in figure [Peripheral interface](#page-15-1) on page 16.

3.3.9.1 Interrupt clearing and disabling

Interrupts should always be cleared by writing '0' to the corresponding EVENT register.

Until cleared, interrupts will immediately be re-triggered and cause software interrupt service routines to be executed repeatedly.

Because the clearing of the EVENT register may take a number of CPU clock cycles, the program should perform a read from the EVENT register that has been cleared before exiting the interrupt service routine. This will ensure that the EVENT clearing has taken place before the interrupt service routine is exited. Care should be taken to ensure that the compiler does not remove the read operation as an optimization.

Similarly, when disabling an interrupt inside an interrupt service routine, the program should perform a read from the INTEN or INTENCLR registers to ensure that the interrupt is disabled before exiting the interrupt service routine.

3.3.10 Secure/non-secure peripherals

For some peripherals, the security configuration can change from secure to non-secure, or vice versa. Care must be taken when changing the security configuration of a peripheral, to prevent security information leakage and ensure correct operation.

The following sequence should be followed, where applicable, when configuring and changing the security settings of a peripheral in the SPU - System protection unit on page 259:

- **1.** Stop peripheral operation
- **2.** Disable the peripheral
- **3.** Remove pin connections
- **4.** Disable DPPI connections
- **5.** Clear sensitive registers (e.g. writing back default values)
- **6.** Change peripheral security setting in the [SPU System protection unit](#page-258-0) on page 259
- **7.** Re-enable the peripheral

Note: Changing security settings on a peripheral during runtime is not advisable.

Application core

4.1 CPU

The ARM Cortex-M33 processor has a 32-bit instruction set (Thumb-2 technology) that implements a superset of 16 and 32-bit instructions to maximize code density and performance.

This processor implements several features that enable energy-efficient arithmetic and high-performance signal processing, including:

- Digital signal processing (DSP) instructions
- Single-cycle multiply and accumulate (MAC) instructions
- Hardware divide
- 8- and 16-bit single instruction, multiple data (SIMD) instructions
- Single-precision floating-point unit (FPU)
- Memory Protection Unit (MPU)
- ARM TrustZone for ARMv8-M

The ARM Cortex Microcontroller Software Interface Standard (CMSIS) hardware abstraction layer for the ARM Cortex processor series is implemented and available for the M33 CPU.

Real-time execution is highly deterministic in thread mode, to and from sleep modes, and when handling events at configurable priority levels via the nested vectored interrupt controller (NVIC).

Executing code from internal or external flash will have a wait state penalty. The instruction cache can be enabled to minimize flash wait states when fetching instructions. For more information on cache, see [Cache](#page-30-0) on page 31. The section [Electrical specification](#page-20-0) on page 21 shows CPU performance parameters including the wait states in different modes, CPU current and efficiency, and processing power and efficiency based on the CoreMark benchmark.

4.1.1 CPU and support module configuration

The ARM Cortex-M33 processor has a number of CPU options and support modules implemented on the device.

4.1.2 Electrical specification

4.1.2.1 CPU performance

The CPU clock speed is 64 MHz. Current and efficiency data is taken when in System ON and the CPU is executing the CoreMark benchmark. It includes power regulator and clock base currents. All other blocks are IDLE.

4.2 Memory

The application microcontroller has embedded 1024 kB flash and 256 kB RAM for application code and data storage.

As illustrated in [Memory layout](#page-21-0) on page 22, both CPU and EasyDMA are able to access RAM via the AHB multilayer interconnect. See [AHB multilayer interconnect](#page-46-0) on page 47 and [EasyDMA](#page-44-0) on page 45 for more information about AHB multilayer interconnect and EasyDMA respectively. The LTE modem can access all application MCU memory, but typically a small portion of RAM is dedicated to data exchange between application MCU and the modem baseband controller.

¹ Using IAR compiler

Figure 3: Memory layout

RAM - Random access memory

RAM can be read and written an unlimited number of times by the CPU and the EasyDMA.

Each RAM AHB slave is connected to one or more RAM sections. See [Memory layout](#page-21-0) on page 22 for more information.

The RAM blocks power states and retention states in System ON and System OFF modes are controlled by the [VMC](#page-26-1).

Flash - Non-volatile memory

Flash can be read an unlimited number of times by the CPU and is accessible via the AHB interface connected to the CPU, see [Memory layout](#page-21-0) on page 22 for more information. There are restrictions on the number of times flash can be written and erased, and also on how it can be written. For more information, see [Absolute maximum ratings](#page-391-1) on page 392. Writing to flash is managed by the nonvolatile memory controller (NVMC).

4.2.1 Memory map

All memory and registers are found in the same address space, as illustrated in the device memory map below.

Figure 4: Memory map

Some of the registers are retained (their values kept). Read more about retained registers in [Retained](#page-56-0) [registers](#page-56-0) on page 57 and [Reset behavior](#page-56-1) on page 57.

4.2.2 Instantiation

Table 4: Instantiation table

4.2.3 Peripheral access control capabilities

Information about the peripheral access control capabilities can be found in the instantiation table.

The instantiation table has two columns containing the information about access control capabilities for a peripheral:

- Secure mapping: This column defines configuration capabilities for TrustZone-M secure attribute.
- DMA security: This column indicates if the peripheral has DMA capabilities, and if DMA transfer can be assigned to a different security attribute than the peripheral itself.

For details on options in secure mapping column and DMA security column, see the following tables respecitvely.

Table 5: Secure mapping column options

Table 6: DMA security column options

4.3 VMC — Volatile memory controller

The volatile memory controller (VMC) provides power control of RAM blocks.

Each of the available RAM blocks, which can contain multiple RAM sections, can be turned on or off independently in System ON mode, using the RAM[n]registers. These registers also control if a RAM block, or some of its sections, is retained in System OFF mode. See [Memory](#page-20-1) chapter for more information about RAM blocks and sections.

Note: Powering up a RAM block takes typically 10 cycles. Thus, it is recommended reading the POWER register before accessing a RAM block that has been recently powered on.

4.3.1 Registers

4.3.1.1 RAM[n].POWER (n=0..7)

Address offset: 0x600 + (n × 0x10)

RAMn power control register

4.3.1.2 RAM[n].POWERSET (n=0..7)

Address offset: $0x604 + (n \times 0x10)$

RAMn power control set register

When read, this register will return the value of the POWER register.

4.3.1.3 RAM[n].POWERCLR (n=0..7)

Address offset: $0x608 + (n \times 0x10)$

RAMn power control clear register

When read, this register will return the value of the POWER register.

4.4 NVMC — Non-volatile memory controller

The non-volatile memory controller (NVMC) is used for writing and erasing of the internal flash memory and the user information configuration register (UICR).

The NVMC is a split security peripheral. This means that when the NVMC is configured as non-secure, only a subset of the registers is available from the non-secure code. See SPU - System protection unit on page 259 and [Registers](#page-31-0) on page 32 for more details.

When the NVMC is configured to be a secure peripheral, only secure code has access.

Before a write can be performed, the NVMC must be enabled for writing in CONFIG.WEN. Similarly, before an erase can be performed, the NVMC must be enabled for erasing in CONFIG.EEN, see [CONFIG](#page-32-0) on page 33. The user must make sure that writing and erasing are not enabled at the same time. Failing to do so may result in unpredictable behavior.

4.4.1 Writing to flash

When writing is enabled, in CONFIG register for secure region, or in CONFIGNS register for non-secure region, flash is written by writing a full 32-bit word to a word-aligned address in flash.

Secure code has access to both secure and non-secure regions, by using the appropriate configuration of CONFIG and CONFIGNS registers. Non-secure code, in constrast, has access to non-secure regions only. Thus, non-secure code only needs CONFIGNS.

The NVMC is only able to write '0' to erased bits in flash, that is bits set to '1'. It cannot write a bit back to '1'.

As illustrated in [Memory](#page-20-1) on page 21, flash is divided into multiple pages. The same address in flash can only be written n_{WRITE} n_{WRITE} n_{WRITE} number of times before a page erase must be performed.

Only full 32-bit words can be written to flash using the NVMC interface. To write less than 32 bits to flash, write the data as a word, and set all the bits that should remain unchanged in the word to '1'. Note that the restriction about the number of writes (see above) still applies in this case.

The time it takes to write a word to flash is specified by t_{WRITE} t_{WRITE} t_{WRITE} . If CPU executes code from flash while the NVMC is writing to flash, the CPU will be stalled.

Only word-aligned writes are allowed. Byte or half-word-aligned writes will result in a bus fault.

4.4.2 Erasing a secure page in flash

When secure region erase is enabled (in CONFIG register), a flash page can be erased by writing 0xFFFFFFFF into the first 32-bit word in a flash page.

Page erase is only applicable to the code area in the flash and does not work with UICR.

After erasing a flash page, all bits in the page are set to '1'. The time it takes to erase a page is specified by t_{[ERASEPAGE](#page-34-2)}. The CPU is stalled if the CPU executes code from the flash while the NVMC performs the erase operation.

See Partial erase of a page in flash for information on splitting the erase time in smaller chunks.

4.4.3 Erasing a non-secure page in flash

When non-secure region erase is enabled, a non-secure flash page can be erased by writing 0xFFFFFFFF into the first 32-bit word of the flash page.

Page erase is only applicable to the code area in the flash and does not work with UICR.

After erasing a flash page, all bits in the page are set to '1'. The time it takes to erase a page is specified by $t_{FRASFBAGE}$. The CPU is stalled if the CPU executes code from the flash while the NVMC performs the erase operation.

4.4.4 Writing to user information configuration registers (UICR)

User information configuration registers (UICR) are written in the same way as flash. After UICR has been written, the new UICR configuration will only take effect after a reset.

UICR is only accessible by secure code. Any write from non-secure code will be faulted.

In order to lock the chip after uploading non-secure code, a simple sequence must be followed:

- **1.** Block access to secure code by setting UICR register [SECUREAPPROTECT](#page-41-0) on page 42 to protected
- **2.** Use the [WRITEUICRNS](#page-34-3) on page 35 register, via non-secure debugger, in order to set APPROTECT (APPROTECT is automatically written to 0x00000000 by the NVMC)

UICR can only be written n_{WRITF} number of times before an erase must be performed using [ERASEALL](#page-32-1).

The time it takes to write a word to the UICR is specified by t_{WRITE} t_{WRITE} t_{WRITE} . The CPU is stalled if the CPU executes code from the flash while the NVMC is writing to the UICR.

4.4.5 Erase all

When erase is enabled, the whole flash and UICR can be erased in one operation by using the ERASEALL register. ERASEALL will not erase the factory information configuration registers (FICR).

This functionality can be blocked by some configuration of the UICR protection bits, see the table [NVMC](#page-30-1) [protection \(1 - Enabled, 0 - Disabled, X - Don't care\)](#page-30-1) on page 31.

The time it takes to perform an [ERASEALL](#page-34-2) on page 33 command is specified by t_{ERASEALL}. The CPU is stalled if the CPU executes code from the flash while the NVMC performs the erase operation.

4.4.6 NVMC protection mechanisms

This chapter describes the different protection mechanisms for the non-volatile memory.

4.4.6.1 NVMC blocking

UICR integrity is assured through use of multiple levels of protection. UICR protection bits can be configured to allow or block certain operations.

The table below shows the different status of UICR protection bits, and which operations are allowed or blocked.

UICR protection bit status			NVMC protection	
SECUREAPPROTECT APPROTECT		ERASEPROTECT	CTRL-AP	NVMC
			ERASEALL	ERASEALL
Ω	0	Ω	Available	Available
	X	Ω	Available	Blocked
X	1	Ω	Available	Blocked
X	X		Blocked	Blocked

Table 9: NVMC protection (1 - Enabled, 0 - Disabled, X - Don't care)

Note: Erase can still be performed through CTRL-AP, regardless of the above settings. See [CTRL-AP](#page-371-1) [- Control access port](#page-371-1) on page 372 for more information.

Uploading code with secure debugging blocked

Non-secure code can program non-secure flash regions. In order to perform these operations, the NVMC has the following non-secure registers: CONFIGNS, READY and READYNEXT.

Register [CONFIGNS](#page-33-0) on page 34 works as the CONFIG register but it is used only for non-secure transactions. Both page erase and writing inside the flash require a write transaction (see [Erasing a secure](#page-29-0) [page in flash](#page-29-0) on page 30 or [Erasing a non-secure page in flash](#page-29-1) on page 30). Because of this, the [SPU — System protection unit](#page-258-0) on page 259 will guarantee that the non-secure code cannot write inside a secure page, since the transaction will never reach the NVMC controller.

4.4.6.2 NVMC power failure protection

NVMC power failure protection is possible through use of power-fail comparator that is monitoring power supply.

If the power-fail comparator is enabled, and the power supply voltage is below V_{POF} threshold, the powerfail comparator will prevent the NVMC from performing erase or write operations in non-volatile memory (NVM).

If a power failure warning is present at the start of an NVM write or erase operation, the NVMC will block the operation and a bus error will be signalled. If a power failure warning occurs during an ongoing NVM write operation, the NVMC will try to finish the operation. And if the power failure warning persists, consecutive NVM write operations will be blocked by the NVMC, and a bus error will be signalled. If a power failure warning occurs during an NVM erase operation, the operation is aborted and a bus error is signalled.

4.4.7 Cache

An instruction cache (I-Cache) can be enabled for the ICODE bus in the NVMC.

See [Memory map](#page-22-0) on page 23 for the location of flash.

A cache hit is an instruction fetch from the cache, and it has a 0 wait-state delay. The number of waitstates for a cache miss, where the instruction is not available in the cache and needs to be fetched from flash, depends on the processor frequency, see CPU parameter W_FLASHCACHE.

Enabling the cache can increase the CPU performance, and reduce power consumption by reducing the number of wait cycles and the number of flash accesses. This will depend on the cache hit rate. Cache draws current when enabled. If the reduction in average current due to reduced flash accesses is larger than the cache power requirement, the average current to execute the program code will be reduced.

When disabled, the cache does not draw current and its content is not retained.

It is possible to enable cache profiling to analyze the performance of the cache for your program using the register [ICACHECNF.](#page-32-2) When profiling is enabled, registers [IHIT](#page-33-1) and [IMISS](#page-33-2) are incremented for every instruction cache hit or miss respectively.

4.4.8 Registers

Table 10: Instances

Table 11: Register overview

4.4.8.1 READY

Address offset: 0x400

Ready flag

4.4.8.2 READYNEXT

Address offset: 0x408

Ready flag

4.4.8.3 CONFIG

Address offset: 0x504

Configuration register

Note: This register is one hot

4.4.8.4 ERASEALL

Address offset: 0x50C

Register for erasing all non-volatile user memory

4.4.8.5 ERASEPAGEPARTIALCFG

Address offset: 0x51C

Register for partial erase configuration

complete erase of the flash page

4.4.8.6 ICACHECNF

Address offset: 0x540

I-code cache configuration register

4.4.8.7 IHIT

Address offset: 0x548

I-code cache hit counter

Write zero to clear

4.4.8.8 IMISS

Address offset: 0x54C

I-code cache miss counter

Write zero to clear

4.4.8.9 CONFIGNS

Address offset: 0x584

Note: This register is one hot

4.4.8.10 WRITEUICRNS

Address offset: 0x588

Non-secure APPROTECT enable register

4.4.9 Electrical specification

4.4.9.1 Flash programming

4.4.9.2 Cache size

4.5 FICR — Factory information configuration registers

Factory information configuration registers (FICR) are pre-programmed in factory and cannot be erased by the user. These registers contain chip-specific information and configuration.

4.5.1 Registers

Table 13: Register overview

4.5.1.1 INFO.DEVICEID[n] (n=0..1)

Address offset: 0x204 + (n × 0x4)

Device identifier

DEVICEID[0] contains the least significant bits of the device identifier. DEVICEID[1] contains the most significant bits of the device identifier.

4.5.1.2 INFO.PART

Address offset: 0x20C

Part code

4.5.1.3 INFO.VARIANT

Address offset: 0x210

Part Variant, Hardware version and Production configuration

4.5.1.4 INFO.PACKAGE

Address offset: 0x214

Package option

4.5.1.5 INFO.RAM

Address offset: 0x218

RAM variant

4.5.1.6 INFO.FLASH

Address offset: 0x21C

Flash variant

4.5.1.7 INFO.CODEPAGESIZE

Address offset: 0x220

Code memory page size

4.5.1.8 INFO.CODESIZE

Address offset: 0x224

Code memory size

Total code space is: CODEPAGESIZE * CODESIZE

4.5.1.9 INFO.DEVICETYPE

Address offset: 0x228

Device type

4.5.1.10 TRIMCNF[n].ADDR (n=0..255)

Address offset: 0x300 + (n × 0x8)

Address

4.5.1.11 TRIMCNF[n].DATA (n=0..255)

Address offset: 0x304 + (n × 0x8)

Data

4.5.1.12 TRNG90B.BYTES

Address offset: 0xC00

Amount of bytes for the required entropy bits

A R BYTES **Amount of bytes for the required entropy bits**

4.5.1.13 TRNG90B.RCCUTOFF

Address offset: 0xC04

Repetition counter cutoff

4.5.1.14 TRNG90B.APCUTOFF

Address offset: 0xC08

Adaptive proportion cutoff

4.5.1.15 TRNG90B.STARTUP

Address offset: 0xC0C

Amount of bytes for the startup tests

4.5.1.16 TRNG90B.ROSC1

Address offset: 0xC10

Sample count for ring oscillator 1

4.5.1.17 TRNG90B.ROSC2

Address offset: 0xC14

Sample count for ring oscillator 2

4.5.1.18 TRNG90B.ROSC3

Address offset: 0xC18

Sample count for ring oscillator 3

4.5.1.19 TRNG90B.ROSC4

Address offset: 0xC1C

Sample count for ring oscillator 4

4.6 UICR — User information configuration registers

The user information configuration registers (UICRs) are non-volatile memory (NVM) registers for configuring user specific settings.

For information on writing UICR registers, see the [NVMC — Non-volatile memory controller](#page-28-0) on page 29 and [Memory](#page-20-0) on page 21 chapters.

4.6.1 Registers

Table 14: Instances

Table 15: Register overview

4.6.1.1 APPROTECT

Address offset: 0x000 Access port protection

4.6.1.2 XOSC32M

Address offset: 0x014

Oscillator control

4.6.1.3 HFXOSRC

Address offset: 0x01C

HFXO clock source selection

4.6.1.4 HFXOCNT

Address offset: 0x020

HFXO startup counter

4.6.1.5 SECUREAPPROTECT

Address offset: 0x02C

Secure access port protection

4.6.1.6 ERASEPROTECT

Address offset: 0x030

Erase protection

4.6.1.7 OTP[n] (n=0..189)

Address offset: 0x108 + (n × 0x4)

One time programmable memory

4.6.1.8 KEYSLOT.CONFIG[n].DEST (n=0..127)

Address offset: 0x400 + (n × 0x8)

Destination address where content of the key value registers (KEYSLOT.KEYn.VALUE[0-3]) will be pushed by KMU. Note that this address must match that of a peripherals APB mapped write-only key registers, else the KMU can push this key value into an address range which the CPU can potentially read.

Note: Writing/reading this register requires the KMU SELECTKEYSLOT register to be set to n+1.

4.6.1.9 KEYSLOT.CONFIG[n].PERM (n=0..127)

Address offset: 0x404 + (n × 0x8)

Define permissions for the key slot. Bits 0-15 and 16-31 can only be written when equal to 0xFFFF.

Note: Writing/reading this register requires the KMU SELECTKEYSLOT register to be set to n+1.

4.6.1.10 KEYSLOT.KEY[n].VALUE[o] (n=0..127) (o=0..3)

Address offset: $0x800 + (n \times 0x10) + (o \times 0x4)$

Define bits [31+o*32:0+o*32] of value assigned to KMU key slot.

Note: Writing/reading this register requires the KMU SELECTKEYSLOT register to be set to n+1.

4.7 EasyDMA

EasyDMA is a module implemented by some peripherals to gain direct access to Data RAM.

EasyDMA is an AHB bus master similar to CPU and is connected to the AHB multilayer interconnect for direct access to Data RAM. EasyDMA is not able to access flash.

A peripheral can implement multiple EasyDMA instances to provide dedicated channels. For example, for reading and writing of data between the peripheral and RAM. This concept is illustrated in [EasyDMA](#page-44-0) [example](#page-44-0) on page 45.

Figure 5: EasyDMA example

An EasyDMA channel is implemented in the following way, but some variations may occur:

```
 READERBUFFER_SIZE 5
WRITERBUFFER SIZE 6
uint8 t readerBuffer[READERBUFFER SIZE] __ at __ 0x20000000;
uint8 t writerBuffer[WRITERBUFFER SIZE] ___ at __0x20000005;
 // Configuring the READER channel
MYPERIPHERAL->READER.MAXCNT = READERBUFFER SIZE;
 MYPERIPHERAL->READER.PTR = &readerBuffer;
 // Configure the WRITER channel
 MYPERIPHERAL->WRITER.MAXCNT = WRITEERBUFFER_SIZE;
 MYPERIPHERAL->WRITER.PTR = &writerBuffer;
```
This example shows a peripheral called MYPERIPHERAL that implements two EasyDMA channels - one for reading called READER, and one for writing called WRITER. When the peripheral is started, it is assumed that the peripheral will perform the following tasks:

- Read 5 bytes from the readerBuffer located in RAM at address 0x20000000
- Process the data
- Write no more than 6 bytes back to the writerBuffer located in RAM at address 0x20000005

The memory layout of these buffers is illustrated in [EasyDMA memory layout](#page-45-0) on page 46.

Figure 6: EasyDMA memory layout

The WRITER.MAXCNT register should not be specified larger than the actual size of the buffer (writerBuffer). Otherwise, the channel would overflow the writerBuffer.

Once an EasyDMA transfer is completed, the AMOUNT register can be read by the CPU to see how many bytes were transferred. For example, CPU can read MYPERIPHERAL->WRITER.AMOUNT register to see how many bytes WRITER wrote to RAM.

Note: The PTR register of a READER or WRITER must point to a valid memory region before use. The reset value of a PTR register is not guaranteed to point to valid memory. See [Memory](#page-20-0) on page 21 for more information about the different memory regions and EasyDMA connectivity.

4.7.1 EasyDMA error handling

Some errors may occur during DMA handling.

If READER.PTR or WRITER.PTR is not pointing to a valid memory region, an EasyDMA transfer may result in a HardFault or RAM corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions.

If several AHB bus masters try to access the same AHB slave at the same time, AHB bus congestion might occur. An EasyDMA channel is an AHB master. Depending on the peripheral, the peripheral may either stall and wait for access to be granted, or lose data.

4.7.2 EasyDMA array list

EasyDMA is able to operate in Array List mode.

The Array List mode is implemented in channels where the LIST register is available.

The array list does not provide a mechanism to explicitly specify where the next item in the list is located. Instead, it assumes that the list is organized as a linear array where items are located one after the other in RAM.

The EasyDMA Array List can be implemented by using the data structure ArrayList_type as illustrated in the code example below using a READER EasyDMA channel as an example:

```
 #define BUFFER_SIZE 4
 typedef struct ArrayList
 {
 uint8 t buffer[BUFFER SIZE];
 } ArrayList_type;
 ArrayList_type ReaderList[3] __at__ 0x20000000;
 MYPERIPHERAL->READER.MAXCNT = BUFFER_SIZE;
 MYPERIPHERAL->READER.PTR = &ReaderList;
MYPERIPHERAL->READER.LIST = MYPERIPHERAL READER LIST ArrayList;
```
The data structure only includes a buffer with size equal to the size of READER.MAXCNT register. EasyDMA uses the READER.MAXCNT register to determine when the buffer is full.

READER.PTR = &ReaderList

 $\ddot{}$

Figure 7: EasyDMA array list

4.8 AHB multilayer interconnect

On the AHB multilayer interconnect, the application CPU and all EasyDMA instances are AHB bus masters while RAM, cache and peripherals are AHB slaves. External MCU subsystems can be seen both as master and slave on the AHB multilayer interconnect.

Multiple AHB masters can access slave resources within the AHB multilayer interconnect as illustrated in [Memory](#page-20-0) on page 21. Access rights to each of the AHB slaves are resolved using the natural priority of the different bus masters in the system.

Power and clock management

5.1 Functional description

The power and clock management system automatically ensures maximum power efficiency.

The nRF9160 provides a total of three power modes; two internal (automatically handled by the device), and one external (driven by the ENABLE pin and overriding internal ones).

The core of the automatic power and clock management is the power management unit (PMU) illustrated in the image below.

Figure 8: Power management unit

When the device is powered and enabled, the PMU automatically tracks the power and clock resources required by the different components in the system. It then starts/stops and chooses operation modes in supply regulators and clock sources, without user interaction, to achieve the lowest power consumption possible.

5.1.1 Power management

The two internal modes are handled by the power management unit (PMU) , whereas the external is handled by the user via the ENABLE pin.

The System Disabled mode provides a way to override the PMU by manipulating voltages presented to the ENABLE pin.

The PMU steers system-wide clock and power in order to provide the power modes - System ON and System OFF. Under the various modes, internal blocks are automatically powered by the PMU as required by the application.

5.1.1.1 System Disabled mode

The entire device can be powered down by presenting the appropriate voltage to the externally available ENABLE pin.

The nRF9160 provides a feature to be able disable power throughout the entire device externally. This can be useful when the device is operating as slave processor where it does not need to be powered on at all times, then it is possible to avoid unnecesary current leaking by driving the ENABLE pin to low. The nRF9160 will not start if is not enabled. Moreover, a change from disable to enable, will result in a poweron-reset behavior inside the device.

Note: VDD GPIO input must be driven low when device is disabled, failing to do so could result in increased leakage. For more information, see VDD GPIO considerations in [Operating conditions](#page-390-0) on page 391.

Note: In case the System Disabled mode is not used, ENABLE must be connected to VDD.

Table 16: ENABLE pin configuration

5.1.1.2 System OFF mode

System OFF is the deepest internal power saving mode the system can enter.

In this mode, the core system functionality is powered down and ongoing tasks terminated, and only the reset and the wakeup functions are available and responsive.

The device is put into System OFF mode using the [REGULATORS](#page-76-0) register interface. When in System OFF mode, one of the following signals/actions will wake up the device:

- **1.** DETECT signal, generated by the GPIO peripheral
- **2.** RESET
- **3.** start of debug session

When the device wakes up from System OFF mode, a system reset is performed.

One or more RAM blocks can be retained in System OFF mode depending on the settings in the RAM[n].POWER registers in [VMC.](#page-26-0) RAM[n].POWER are retained registers, see [Reset behavior](#page-56-0) on page 57. Note that these registers are usually overwritten by the startup code provided with the nRF application examples.

Before entering System OFF mode, the user must make sure that all on-going EasyDMA transactions have completed. This can be accomplished by making sure that EasyDMA enabled peripherals have stopped and END events from them received. The LTE modem also needs to be stopped, by issuing a command through the modem API, before entering System OFF mode. Once the command is issued, one should wait for the modem to respond that it actually has stopped, as there may be a delay until modem is disconnected from the network.

5.1.1.2.1 Emulated System OFF mode

If the device is in debug interface mode, System OFF will be emulated to secure that all required resources needed for debugging are available during System OFF.

See [Overview](#page-368-0) on page 369 chapter for more information. Required resources needed for debugging include the following key components: [Overview](#page-368-0) on page 369, [CLOCK — Clock control](#page-69-0) on page 70, [POWER — Power control](#page-63-0) on page 64, [NVMC — Non-volatile memory controller](#page-28-0) on page 29, [CPU](#page-19-0) on page 20, flash, and RAM. Since the CPU is kept on in emulated System OFF mode, it is required to add an infinite loop directly after entering System OFF, to prevent the CPU from executing code that normally should not be executed.

5.1.1.3 System ON mode

System ON is the power mode entered after a power-on reset.

While in System ON, the system can reside in one of two sub modes:

- Low power
- Constant latency

The low power mode is default after power-on reset.

In low power mode, whenever no application or wireless activity takes place, function blocks like the application CPU, LTE modem and all peripherals are in IDLE state. That particular state is referred to as System ON IDLE. In this state, all function blocks retain their state and configuration, so they are ready to become active once configured by the CPU.

If any application or modem activity occurs, the system leaves the System ON IDLE state. Once a given activity in a function block is completed, the system automatically returns to IDLE, retaining its configuration.

As long as the system resides in low power mode, the PMU ensures that the appropriate regulators and clock sources are started or stopped based on the needs of the function blocks active at any given time.

This automatic power management can be overridden by switching to constant latency mode. In this mode, the CPU wakeup latency and the PPI task response are constant and kept at a minimum. This is secured by keeping a set of base resources that are always enabled. The advantage of having a constant and predictable latency will be at the cost of having significantly increased power consumption compared to the low power mode. The constant latency mode is enabled by triggering the CONSTLAT task [\(TASKS_CONSTLAT](#page-63-1) on page 64).

While the system is in constant latency mode, the low power mode can be enabled by triggering LOWPWR task (TASKS LOWPWR on page 65).

To reduce power consumption while in System ON IDLE, RAM blocks can be turned off in System ON mode while enabling the retention of these RAM blocks in RAM[n].POWER registers in [VMC](#page-26-0). RAM[n].POWER are retained registers, see [Reset behavior](#page-56-0) on page 57. Note that these registers are usually overwritten by the startup code provided with the nRF application examples.

5.1.1.4 Registers

5.1.1.5 Electrical specification

5.1.1.5.1 ENABLE pin voltage requirements

5.1.2 Power supply

The nRF9160 has a single main power supply VDD, and the internal components are powered by integrated voltage regulators. The PMU manages these regulators automatically, no voltage regulator control needs to be included in application firmware.

5.1.2.1 General purpose I/O supply

The input/output (I/O) drivers of P0.00 - P0.31 pins are supplied independently of VDD through VDD_GPIO. This enables easy match to signal voltage levels in the printed circuit board design.

Figure 9: GPIO supply input (VDD_GPIO)

The I/Os are supplied via VDD_GPIO pin as shown in figure above. VDD_GPIO pin supports voltage levels within range given in table [Operating conditions](#page-390-0) on page 391

5.1.3 Power supply monitoring

Power monitor solutions are available in the device, in order to survey the VDD (battery voltage).

5.1.3.1 Power supply supervisor

The power supply supervisor enables monitoring of the connected power supply.

Two functionalities are implemented:

- Power-on reset (POR): Generates a reset when the supply is applied to the device, and ensures that the device starts up in a known state
- Brownout reset (BOR): Generates a reset when the supply drops below the minimum voltage required for safe operations

Two BOR levels are used:

- \bullet V_{BOROFF}, used in System OFF
- V_{BORON}, used in System ON

The power supply supervisor is illustrated in the image below.

Figure 10: Power supply supervisor

5.1.3.2 Battery monitoring on VDD

A battery voltage (VDD) monitoring capability is provided via a modem API

Note: For details regarding the modem API, please refer to *nRF Connect SDK* document and *nRF91 AT Commands, Command Reference Guide* document.

5.1.3.3 Registers

5.1.3.4 Electrical specification

5.1.3.4.1 Device startup times

 2 To decrease the maximum time a device could be held in reset, a strong external pull-up resistor can be used.

5.1.3.4.2 Power supply supervisor

5.1.4 Clock management

The clock control system can source the system clocks from a range of high and low frequency oscillators, and distribute them to modules based upon a module's individual requirements. Clock generation and distribution is handled automatically by PMU to optimize current consumption.

Listed here are the available clock signal sources:

- 64 MHz oscillator (HFINT)
- 64 MHz high accuracy oscillator (HFXO)
- 32.768 kHz RC oscillator (LFRC)
- 32.768 kHz high accuracy oscillator (LFXO)

The clock and oscillator resources are configured and controlled via the CLOCK peripheral as illustrated below.

Figure 11: Clock and oscillator setup

5.1.4.1 HFCLK clock controller

The HFCLK clock controller provides several clocks in the system.

These are as follows:

- HCLK: 64 MHz CPU clock
- PCLK1M: 1 MHz peripheral clock
- PCLK16M: 16 MHz peripheral clock
- PCLK32M: 32 MHz peripheral clock

The HFCLK controller uses the following high frequency clock (HFCLK) sources:

- 64 MHz oscillator (HFINT)
- 64 MHz high accuracy oscillator (HFXO)

For illustration, see [Clock and oscillator setup](#page-53-0) on page 54.

The HFCLK controller will automatically provide the clock(s) requested by the system. If the system does not request any clocks from the HFCLK controller, the controller will switch off all its clock sources and enter a power saving mode.

The HFINT source will be used when HFCLK is requested and HFXO has not been started.

The HFXO is started by triggering the HFCLKSTART task and stopped using the HFCLKSTOP task. A HFCLKSTARTED event will be generated when the HFXO has started and its frequency is stable.

5.1.4.2 LFCLK clock controller

The system supports several low frequency clock sources.

As illustrated in [Clock and oscillator setup](#page-53-0) on page 54, the system supports the following low frequency clock sources:

- LFRC: 32.768 kHz RC oscillator
- LFXO: 32.768 kHz high accuracy oscillator

The LFCLK clock controller and all LFCLK clock sources are always switched off when in System OFF mode.

The LFCLK clock is started by first selecting the preferred clock source in the [LFCLKSRC](#page-76-1) on page 77 register and then triggering the LFCLKSTART task. LFXO is highly recommended as the LFCLK clock source, since the LFRC has a large frequency variation.

Note: The LTE modem requires using LFXO as the LFCLK source.

Switching between LFCLK clock sources can be done without stopping the LFCLK clock. A LFCLK clock source which is running prior to triggering the LFCLKSTART task will continue to run until the selected clock source has been available. After that the clock sources will be switched. Switching between clock sources will never introduce a glitch but it will stretch a clock pulse by 0.5 to 1.0 clock cycle (i.e. will delay rising edge by 0.5 to 1.0 clock cycle).

Note: If the watchdog timer (WDT) is running, the default LFCLK clock source (LFRC - see [LFCLKSRC](#page-76-1) on page 77) is started automatically (LFCLKSTART task doesn't have to be triggered).

A LFCLKSTARTED event will be generated when the selected LFCLK clock source has started.

Note: When selecting LFXO as clock source for the first time, LFRC quality is provided until LFXO is stable.

A LFCLKSTOP task will stop global requesting of the LFCLK clock. However, if any system component (e.g. WDT, modem) requires the LFCLK, the clock won't be stopped. The LFCLKSTOP task should only be triggered after the STATE field in the LFCLKSTAT register indicates a LFCLK running-state.

5.1.4.2.1 32.768 kHz RC oscillator (LFRC)

The default source of the low frequency clock (LFCLK) is the 32.768 kHz RC oscillator (LFRC).

The LFRC frequency will be affected by variation in temperature.

5.1.4.3 Registers

5.1.4.4 Electrical specification

5.1.4.4.1 64 MHz internal oscillator (HFINT)

5.1.4.4.2 64 MHz high accuracy oscillator (HFXO)

5.1.4.4.3 32.768 kHz high accuracy oscillator (LFXO)

5.1.4.4.4 32.768 kHz RC oscillator (LFRC)

5.1.5 Reset

There are multiple reset sources that may trigger a reset of the system. After a reset the CPU can query the RESETREAS (reset reason register) to find out which source generated the reset.

5.1.5.1 Power-on reset

The power-on reset generator initializes the system at power-on. The system is held in reset state until the supply has reached the minimum operating voltage and the internal voltage regulators have started.

5.1.5.2 Pin reset

A pin reset is generated when the physical reset pin (nRESET) on the device is pulled low.

To ensure that reset is issued correctly, the reset pin should be held low for time given in [Pin reset](#page-57-0) on page 58 .

nRESET pin has an always-on internal pull-up resistor connected to nRF9160 internal voltage typically of 2.2 V level. This is illustrated in the figure below. The value of the pull-up resistor is given in [Pin reset](#page-57-0) on page 58.

Note: Driving nRESET high with a voltage lower than 2.2V will result in additional leakage.

Figure 12: Pin reset internal generation

5.1.5.3 Wakeup from System OFF mode reset

The device is reset when it wakes up from System OFF mode.

The Debug access port is not reset following a wake up from System OFF mode if the device is in debug interface mode, see [Overview](#page-368-0) on page 369 chapter for more information.

5.1.5.4 Soft reset

A soft reset is generated when the SYSRESETREQ bit of the application interrupt and reset control register (AIRCR register) in the ARM core is set.

5.1.5.5 Watchdog reset

A watchdog reset is generated when the watchdog timer (WDT) times out.

See [WDT — Watchdog timer](#page-353-0) on page 354 chapter for more information.

5.1.5.6 Brownout reset

The brownout reset generator puts the system in reset state if the supply voltage drops below the brownout reset threshold.

5.1.5.7 Retained registers

A retained register is a register that will retain its value in System OFF mode, and through a reset depending on reset source. See individual peripheral chapters for information of which registers are retained for the different peripherals.

5.1.5.8 Reset behavior

Reset behavior depends on the reset source.

The reset behavior is summarized in the table below.

Table 17: Reset behavior for the main components

Note: The RAM is never reset but its content may be corrupted after reset in the cases given in the table above.

³ All debug components excluding SWJ-DP. See [Overview](#page-368-0) on page 369 chapter for more information about the different debug components in the system.

⁴ RAM can be configured to be retained using registers in [VMC — Volatile memory controller](#page-26-0) on page 27

⁵ Reset from CPU lockup is disabled if the device is in debug interface mode. CPU lockup is not possible in System OFF.

 6 The debug components will not be reset if the device is in debug interface mode.

⁷ Watchdog reset is not available in System OFF.

Table 18: Reset behavior for the retained registers

5.1.5.9 Registers

5.1.5.10 Electrical specification

5.1.5.10.1 Pin reset

5.2 Current consumption

As the system is being constantly tuned by the PMU described in [Functional description](#page-47-0) on page 48, estimating the current consumption of an application can be challenging if the designer is not able to perform measurements directly on the hardware. To facilitate the estimation process, a set of current consumption scenarios are provided to show the typical current drawn from the VDD supply.

Each scenario specifies a set of operations and conditions applying to the given scenario. [Current](#page-58-0) [consumption scenarios, common conditions](#page-58-0) on page 59 shows a set of common conditions used in all scenarios, unless otherwise is stated in the description of a given scenario. Similarly, [Current consumption](#page-58-1) [scenarios, common conditions for LTE modem](#page-58-1) on page 59 describes the conditions used for the modem current consumption specifications. All scenarios are listed in [Electrical specification](#page-58-2) on page 59

Peripherals typically share one or more power sources. This results in a current consumption that does not scale linearly with the number of peripherals enabled. For example, the current consumption for an application with two peripherals enabled, is not the sum of the currents reported by their individual peripherals.

Table 19: Current consumption scenarios, common conditions

All LTE modem current consumption numbers include application core idle mode consumption

Table 20: Current consumption scenarios, common conditions for LTE modem

5.2.1 Electrical specification

5.2.1.1 Current consumption during System Disabled

 8 Except for currents reported for a given peripheral. Peripheral's currents are estimated during momentary transmission.

¹¹ Minimum UICC supply shut down interval and clock stop mode current consumption must be obtained from the UICC supplier.

⁹ Required UICC restart current consumption is included.

 10 If the used UICC does not support supply shut down, then UICC will remain in clock stop mode. Depending on the used UICC a clock stop current of typ. 20-60uA@3.7V needs to be added to get the total average consumption.

5.2.1.2 Sleep

5.2.1.3 Application CPU active current consumption

5.2.1.4 I2S

5.2.1.5 PDM

5.2.1.6 PWM

5.2.1.7 SAADC

5.2.1.8 TIMER

5.2.1.9 SPIM

5.2.1.10 SPIS

5.2.1.11 TWIM

5.2.1.12 TWIS

5.2.1.13 UARTE

5.2.1.14 WDT

5.2.1.15 Modem current consumption

For estimating particular use cases, see [nRF9160 Online Power Profiler for LTE](https://devzone.nordicsemi.com/nordic/power/w/opp/3/online-power-profiler-for-lte)

5.2.1.16 GPS current consumption

5.3 Register description

5.3.1 POWER — Power control

The POWER module provides an interface to tasks, events, interrupt and reset related configuration settings of the power management unit.

Note: Registers [INTEN](#page-66-0) on page 67, [INTENSET](#page-66-1) on page 67, and [INTENCLR](#page-67-0) on page 68 are the same registers (at the same address) as corresponding registers in [CLOCK — Clock control](#page-69-0) on page 70.

5.3.1.1 Registers

Table 21: Instances

Table 22: Register overview

5.3.1.1.1 TASKS_CONSTLAT

Address offset: 0x78

Enable constant latency mode.

5.3.1.1.2 TASKS_LOWPWR

Address offset: 0x7C

Enable low power mode (variable latency)

5.3.1.1.3 SUBSCRIBE_CONSTLAT

Address offset: 0xF8

Subscribe configuration for task [CONSTLAT](#page-63-1)

5.3.1.1.4 SUBSCRIBE_LOWPWR

Address offset: 0xFC

Subscribe configuration for task [LOWPWR](#page-64-0)

5.3.1.1.5 EVENTS_POFWARN

Address offset: 0x108

Power failure warning

5.3.1.1.6 EVENTS_SLEEPENTER

Address offset: 0x114

CPU entered WFI/WFE sleep

5.3.1.1.7 EVENTS_SLEEPEXIT

Address offset: 0x118

CPU exited WFI/WFE sleep

5.3.1.1.8 PUBLISH_POFWARN

Address offset: 0x188

Publish configuration for event [POFWARN](#page-64-3)

5.3.1.1.9 PUBLISH_SLEEPENTER

Address offset: 0x194

Publish configuration for event [SLEEPENTER](#page-65-0)

5.3.1.1.10 PUBLISH_SLEEPEXIT

Address offset: 0x198

Publish configuration for event [SLEEPEXIT](#page-65-1)

5.3.1.1.11 INTEN

Address offset: 0x300

Enable or disable interrupt

5.3.1.1.12 INTENSET

Address offset: 0x304

Enable interrupt

5.3.1.1.13 INTENCLR

Address offset: 0x308

Disable interrupt

5.3.1.1.14 RESETREAS

Address offset: 0x400

Reset reason

Note: Unless cleared, the RESETREAS register will be cumulative. A field is cleared by writing '1' to it. If none of the reset sources are flagged, this indicates that the chip was reset from the on-chip reset generator, which will indicate a power-on reset or a brownout reset.

5.3.1.1.15 POWERSTATUS

Address offset: 0x440

Modem domain power status

5.3.1.1.16 GPREGRET[n] (n=0..1)

Address offset: 0x51C + (n × 0x4)

General purpose retention register

This register is a retained register

5.3.2 CLOCK — Clock control

The CLOCK module provides one of the interfaces to power and clock management configuration settings.

Through CLOCK module it is able to configure the following:

- LFCLK clock source setup
- LFCLK and HFCLK status
- Tasks and events
- Interrupts
- Reset

Note: Registers [INTEN](#page-73-0) on page 74, [INTENSET](#page-73-1) on page 74, and [INTENCLR](#page-73-2) on page 74 are the same registers (at the same address) as corresponding registers in [POWER — Power control](#page-63-0) on page 64.

5.3.2.1 Registers

Table 23: Instances

Table 24: Register overview

5.3.2.1.1 TASKS_HFCLKSTART

Address offset: 0x000

Start HFCLK source

5.3.2.1.2 TASKS_HFCLKSTOP

Address offset: 0x004

Stop HFCLK source

5.3.2.1.3 TASKS_LFCLKSTART

Address offset: 0x008

Start LFCLK source

5.3.2.1.4 TASKS_LFCLKSTOP

Address offset: 0x00C

Stop LFCLK source

5.3.2.1.5 SUBSCRIBE_HFCLKSTART

Address offset: 0x080

Subscribe configuration for task [HFCLKSTART](#page-70-0)

5.3.2.1.6 SUBSCRIBE_HFCLKSTOP

Address offset: 0x084

Subscribe configuration for task [HFCLKSTOP](#page-70-1)

5.3.2.1.7 SUBSCRIBE_LFCLKSTART

Address offset: 0x088

Subscribe configuration for task [LFCLKSTART](#page-70-2)

5.3.2.1.8 SUBSCRIBE_LFCLKSTOP

Address offset: 0x08C

Subscribe configuration for task [LFCLKSTOP](#page-70-3)

5.3.2.1.9 EVENTS_HFCLKSTARTED

Address offset: 0x100

HFCLK oscillator started

5.3.2.1.10 EVENTS_LFCLKSTARTED

Address offset: 0x104

LFCLK started

5.3.2.1.11 PUBLISH_HFCLKSTARTED

Address offset: 0x180

Publish configuration for event [HFCLKSTARTED](#page-72-0)

5.3.2.1.12 PUBLISH_LFCLKSTARTED

Address offset: 0x184

Publish configuration for event [LFCLKSTARTED](#page-72-1)

5.3.2.1.13 INTEN

Address offset: 0x300

Enable or disable interrupt

5.3.2.1.14 INTENSET

Address offset: 0x304

Enable interrupt

5.3.2.1.15 INTENCLR

Address offset: 0x308

Disable interrupt

5.3.2.1.16 INTPEND

Address offset: 0x30C

Pending interrupts

5.3.2.1.17 HFCLKRUN

Address offset: 0x408

Status indicating that HFCLKSTART task has been triggered

5.3.2.1.18 HFCLKSTAT

Address offset: 0x40C

The register shows if HFXO has been requested by triggering HFCLKSTART task and if it has been started (STATE)

5.3.2.1.19 LFCLKRUN

Address offset: 0x414

Status indicating that LFCLKSTART task has been triggered

5.3.2.1.20 LFCLKSTAT

Address offset: 0x418

The register shows which LFCLK source has been requested (SRC) when triggering LFCLKSTART task and if the source has been started (STATE)

5.3.2.1.21 LFCLKSRCCOPY

Address offset: 0x41C

Copy of LFCLKSRC register, set after LFCLKSTART task has been triggered

5.3.2.1.22 LFCLKSRC

Address offset: 0x518

Clock source for the LFCLK. LFCLKSTART task starts starts a clock source selected with this register.

5.3.3 REGULATORS — Voltage regulators control

The REGULATORS module provides an interface to certain configuration settings of on-chip voltage regulators.

5.3.3.1 Registers

Table 25: Instances

Table 26: Register overview

5.3.3.1.1 SYSTEMOFF

Address offset: 0x500

System OFF register

5.3.3.1.2 DCDCEN

Address offset: 0x578

Enable DC/DC mode of the main voltage regulator.

Note: DCDCEN must be set to 1 (enabled) before the LTE modem is started.

6.1 CRYPTOCELL — ARM TrustZone CryptoCell 310

ARM TrustZone CryptoCell 310 (CRYPTOCELL) is a security subsystem which provides root of trust (RoT) and cryptographic services for a device.

Figure 13: Block diagram for CRYPTOCELL

The following cryptographic features are provided:

- True random number generator (TRNG) compliant with NIST 800-90B, AIS-31, and FIPS 140-2
- Pseudorandom number generator (PRNG) using underlying AES engine compliant with NIST 800-90A
- RSA public key cryptography
	- Up to 2048-bit key size
	- PKCS#1 v2.1/v1.5
	- Optional CRT support
- Elliptic curve cryptography (ECC)
	- NIST FIPS 186-4 recommended curves using pseudorandom parameters, up to 521 bits:
		- Prime field: P-192, P-224, P-256, P-384, P-521
	- SEC 2 recommended curves using pseudorandom parameters, up to 521 bits:
		- Prime field: secp160r1, secp192r1, secp224r1, secp256r1, secp384r1, secp521r1
	- Koblitz curves using fixed parameters, up to 256 bits:

- Prime field: secp160k1, secp192k1, secp224k1, secp256k1
- Edwards/Montgomery curves:
	- Ed25519, Curve25519
- ECDH/ECDSA support
- Secure remote password protocol (SRP)
	- Up to 3072-bit operations
- Hashing functions
	- SHA-1, SHA-2 up to 256 bits
	- Keyed-hash message authentication code (HMAC)
- AES symmetric encryption
	- General purpose AES engine (encrypt/decrypt, sign/verify)
	- 128-bit key size
	- Supported encryption modes: ECB, CBC, CMAC/CBC-MAC, CTR, CCM/CCM* (CCM* is a minor variation of CCM)
- ChaCha20/Poly1305 symmetric encryption
	- Supported key size: 128 and 256 bits
	- Authenticated encryption with associated data (AEAD) mode

6.1.1 Usage

The CRYPTOCELL state is controlled via a register interface. The cryptographic functions of CRYPTOCELL are accessible by using a software library provided in the device SDK, not directly via a register interface.

To enable CRYPTOCELL, use register [ENABLE](#page-81-0) on page 82.

Note: Keeping the CRYPTOCELL subsystem enabled will prevent the device from reaching the System ON, All Idle state.

6.1.2 Always-on (AO) power domain

The CRYPTOCELL subsystem has an internal always-on (AO) power domain for retaining device secrets when CRYPTOCELL is disabled.

The following information is retained by the AO power domain:

- 4 bits indicating the configured CRYPTOCELL lifecycle state (LCS)
- 1 bit indicating if the hard-coded RTL key, K_{PRTL} (see [RTL key](#page-80-0) on page 81), is available for use
- 128-bit device root key, K_{DR} (see [Device root key](#page-80-1) on page 81)

A reset from any reset source will erase the content in the AO power domain.

6.1.3 Lifecycle state (LCS)

Lifecycle refers to multiple states a device goes through during its lifetime. Two valid lifecycle states are offered for the device - debug and secure.

The CRYPTOCELL subsystem lifecycle state (LCS) is controlled through register [HOST_IOT_LCS](#page-84-0) on page 85. A valid LCS is configured by writing either value Debug or Secure into the LCS field of this register. A correctly configured LCS can be validated by reading back the read-only field LCS IS VALID from the abovementioned register. The LCS IS VALID field value will change from Invalid to Valid once a valid LCS value has been written.

Table 27: Lifecycle states

6.1.4 Cryptographic key selection

The CRYPTOCELL subsystem can be instructed to operate on different cryptographic keys.

Through register [HOST_CRYPTOKEY_SEL](#page-82-0) on page 83, the following key types can be selected for cryptographic operations:

- \bullet RTL key K_{PRTL}
- Device root key K_{DR}
- Session key

 K_{PRTL} and K_{DR} are configured as part of the CRYPTOCELL initialization process, while session keys are provided by the application through the software library API.

6.1.4.1 RTL key

The ARM TrustZone CryptoCell 310 contains one hard-coded RTL key referred to as K_{PRTL} . This key is set to the same value for all devices with the same part code in the hardware design and cannot be changed.

The K_{PRTL} key can be requested for use in cryptographic operations by the CRYPTOCELL, without revealing the key value itself. Access to use of K_{PRT} in cryptographic operations can be disabled until next reset by writing to register [HOST_IOT_KPRTL_LOCK](#page-83-1) on page 84. If a locked K_{PRTL} key is requested for use, a zero vector key will be routed to the AES engine instead.

6.1.4.2 Device root key

The device root key K_{DR} is a 128-bit AES key programmed into the CRYPTOCELL subsystem using firmware. It is retained in the AO power domain until the next reset.

Once configured, it is possible to perform cryptographic operations using the the CRYPTOCELL subsystem where K_{DR} is selected as key input without having access to the key value itself. The K_{DR} key value must be written to registers [HOST_IOT_KDR\[0..3\].](#page-83-0) These 4 registers are write-only if LCS is set to debug mode, and write-once if LCS is set to secure mode. The K_{DR} key value is successfully retained when the read-back value of register [HOST_IOT_KDR0](#page-83-0) on page 84 changes to 1.

6.1.5 Direct memory access (DMA)

The CRYPTOCELL subsystem implements direct memory access (DMA) for accessing memory without CPU intervention.

Any data stored in memory type(s) not accessible by the DMA engine must be copied to SRAM before it can be processed by the CRYPTOCELL subsystem. Maximum DMA transaction size is limited to 2^{16} -1 bytes.

6.1.6 Standards

ARM TrustZone CryptoCell 310 (CRYPTOCELL) supports a number of cryptography standards.

Table 28: CRYPTOCELL cryptography standards

6.1.7 Registers

6.1.7.1 ENABLE

Address offset: 0x500

Enable CRYPTOCELL subsystem

6.1.8 Host interface

This chapter describes host registers used to control the CRYPTOCELL subsystem behavior.

6.1.8.1 HOST_RGF block

The HOST_RGF block contains registers for configuring LCS and device root key K_{DR}, in addition to selecting which cryptographic key is connected to the AES engine.

6.1.8.1.1 Registers

Table 31: Instances

Table 32: Register overview

6.1.8.1.1.1 HOST_CRYPTOKEY_SEL

Address offset: 0x1A38

AES hardware key select

Note: If the HOST_IOT_KPRTL_LOCK register is set, and the HOST_CRYPTOKEY_SEL register set to 1, then the HW key that is connected to the AES engine is zero

6.1.8.1.1.2 HOST_IOT_KPRTL_LOCK

Address offset: 0x1A4C

This write-once register is the K_PRTL lock register. When this register is set, K_PRTL cannot be used and a zeroed key will be used instead. The value of this register is saved in the CRYPTOCELL AO power domain.

6.1.8.1.1.3 HOST_IOT_KDR0

Address offset: 0x1A50

This register holds bits 31:0 of K_DR. The value of this register is saved in the CRYPTOCELL AO power domain. Reading from this address returns the K_DR valid status indicating if K_DR is successfully retained.

6.1.8.1.1.4 HOST_IOT_KDR1

Address offset: 0x1A54

This register holds bits 63:32 of K_DR. The value of this register is saved in the CRYPTOCELL AO power domain.

6.1.8.1.1.5 HOST_IOT_KDR2

Address offset: 0x1A58

This register holds bits 95:64 of K_DR. The value of this register is saved in the CRYPTOCELL AO power domain.

6.1.8.1.1.6 HOST_IOT_KDR3

Address offset: 0x1A5C

This register holds bits 127:96 of K_DR. The value of this register is saved in the CRYPTOCELL AO power domain.

6.1.8.1.1.7 HOST_IOT_LCS

Address offset: 0x1A60

Controls lifecycle state (LCS) for CRYPTOCELL subsystem

6.2 DPPI - Distributed programmable peripheral interconnect

The distributed programmable peripheral interconnect (DPPI) enables peripherals to interact autonomously with each other by using tasks and events, without any intervention from the CPU. DPPI allows precise synchronization between peripherals when real-time application constraints exist, and eliminates the need for CPU involvement to implement behavior which can be predefined using the DPPI.

Note: For more information on tasks, events, publish/subscribe, interrupts, and other concepts, see [Peripheral interface](#page-14-0) on page 15.

The DPPI has the following features:

- Peripheral tasks can subscribe to channels
- Peripheral events can be published on channels
- Publish/subscribe pattern enabling multiple connection options that include the following:
	- One-to-one
	- One-to-many
	- Many-to-one
	- Many-to-many

The DPPI consists of several PPIBus modules, which are connected to a fixed number of DPPI channels and a DPPI configuration (DPPIC).

Figure 14: DPPI overview

6.2.1 Subscribing to and publishing on channels

The PPIBus can route peripheral events onto the channels (publishing), or route events from the channels into peripheral tasks (subscribing).

All peripherals include the following:

- One subscribe register per task
- One publish register per event

Publish and subscribe registers use a channel index field to determine the channel to which the event is published or tasks subscribed. In addition, there is an enable bit for the subscribe and publish registers that needs to be enabled before the subscription or publishing takes effect.

Writing non-existing channel index (CHIDX) numbers into a peripheral's publish or subscribe registers will yield unexpected results.

One event can trigger multiple tasks by subscribing different tasks to the same channel. Similarly, one task can be triggered by multiple events by publishing different events to the same channel. For advanced use cases, multiple events and multiple tasks can connect to the same channel forming a many-to-many connection. If multiple events are published on the same channel at the same time, the events are merged and only one event is routed through the DPPI.

How peripheral events are routed onto different channels based on publish registers is illustrated in the following figure.

Figure 15: DPPI events flow

The following figure illustrates how peripheral tasks are triggered from different channels based on subscribe registers.

Figure 16: DPPI tasks flow

6.2.2 DPPI configuration (DPPIC)

Enabling and disabling of channels globally is handled through the DPPI configuration (DPPIC). Connection (connect/disconnect) between a channel and a peripheral is handled locally by the PPIBus.

There are two ways of enabling and disabling global channels using the DPPI configuration:

- Enable or disable channels individually using registers CHEN, CHENSET, and CHENCLR.
- Enable or disable channels in channel groups using the groups' tasks ENABLE and DISABLE. It needs to be defined which channels belong to which channel groups before these tasks are triggered.

Note: ENABLE tasks are prioritized over DISABLE tasks. When a channel belongs to two or more groups, for example group m and n, and the tasks CHG[m].EN and CHG[n].DIS occur simultaneously (m and n can be equal or different), the CHG[m].EN task on that channel is prioritized.

The DPPI configuration tasks (for example CHG[0].EN) can be triggered through DPPI like any other task, which means they can be linked to a DPPI channel through the subscribe registers.

In order to write to CHG[x], the corresponding CHG[x]. EN and CHG[x]. DIS subscribe registers must be disabled. Writes to CHG[x] are ignored if any of the two subscribe registers are enabled.

6.2.3 Connection examples

DPPI offers several connection options. Examples are given for how to create one-to-one and many-tomany connections.

One-to-one connection

This example shows how to create a one-to-one connection between TIMER compare register and SAADC start task.

The channel configuration is set up first. TIMER0 will publish its COMPARE0 event on channel 0, and SAADC will subscribe its START task to events on the same channel. After that, the channel is enabled through the DPPIC.

```
NRF_TIMER0->PUBLISH_COMPARE0 = (DPPI_PUB_CHIDX_Ch0) | 
                              (DPPI_PUB_EN_Msk);
NRF_SAADC->SUBSCRIBE_START = (DPPI_SUB_CHIDX_Ch0) |
                               (DPPI_SUB_EN_Msk);
NRF_DPPIC->CHENSET = (DPPI_CHENSET_CH0_Set << DPPI_CHENSET_CH0_Pos);
```
Many-to-many connection

The example shows how to create a many-to-many connection, showcasing the DPPIC's channel group functionality.

A channel group that includes only channel 0 is set up first. Then the GPIOTE and TIMER0 configure their IN0 and COMPARE0 events respectively to be published on channel 0, while the SAADC configures its START task to subscribe to events on channel 0. Through DPPIC, the CHG0 DISABLE task is configured to subscribe to events on channel 0. After an event is received on channel 0 it will be disabled. Finally, channel 0 is enabled using the DPPIC task to enable a channel group.

```
NRF_DPPIC->CHG[0] = (DPPI_CHG_CHO_Included << PPI_CHG_CHO_Pos);
NRF GPIOTE->PUBLISH INO = (DPPI_PUB_CHIDX_Ch0) |
                                (DPPI_PUB_EN_Msk);
NRF_TIMER0->PUBLISH_COMPARE0 = (DPPI_PUB_CHIDX_Ch0) | 
                                (DPPI_PUB_EN_Msk);
NRF_SAADC->SUBSCRIBE_START = (DPPI_SUB_CHIDX_Ch0) |
                                 (DPPI_SUB_EN_Msk);
NRF_DPPIC->SUBSCRIBE_CHG[0].DIS = (DPPI_SUB_CHIDX_Ch0) |
                                 (DPPI_SUB_EN_Msk);
NRF DPPIC->TASK CHG[0].EN = 1;
```
6.2.4 Special considerations for a system implementing TrustZone for Cortex-M processors

DPPI is implemented with split security, meaning it handles both secure and non-secure accesses. In a system implementing the TrustZone for Cortex-M technology, DPPI channels can be defined as secure or non-secure using the SPU.

A peripheral configured as non-secure will only be able to subscribe to or publish on non-secure DPPI channels. A peripheral configured as secure will be able to access all DPPI channels. DPPI handles both secure and non-secure accesses, but behaves differently depending on the access type:

• A non-secure peripheral access can only configure and control the DPPI channels defined as non-secure in the SPU.DPPI.PERM[] register(s)

• A secure peripheral access can control all the DPPI channels, independently of the SPU.DPPI.PERM[] register(s)

A group of channels can be created, making it possible to simultaneously enable or disable all channels within the group. The security attribute of a group of channels (secure or non-secure) is defined as follows:

- If all channels (enabled or not) within a group are non-secure, then the group is considered non-secure
- If at least one of the channels (enabled or not) within the group is secure, then the group is considered secure

A non-secure access to a DPPI register, or a bit field, controlling a channel marked as secure in SPU.DPPI[].PERM register(s) will be ignored. Write accesses will have no effect, and read accesses will always return a zero value.

No exceptions are triggered when non-secure accesses target a register or a bit field controlling a secure channel. For example, if the bit \pm is set in the SPU.DPPI[0].PERM register (declaring DPPI channel i as secure), then:

- Non-secure write accesses to registers CHEN, CHENSET, and CHENCLR cannot write bit i of these registers
- Non-secure write accesses to TASK CHG[j].EN and TASK CHG[j].DIS registers are ignored if the channel group j contains at least one channel defined as secure (it can be the channel i itself or any channel declared as secure)
- Non-secure read accesses to registers CHEN, CHENSET, and CHENCLR always read 0 for the bit at position i

For the channel configuration registers (CHG[]), access from non-secure code is only possible if the included channels are all non-secure, whether the channels are enabled or not. If a CHG[g] register included one or more secure channel(s), then the group q is considered as secure, and only secure transfers can read to or write from CHG[g]. A non-secure write access is ignored, and a non-secure read access returns 0.

The DPPI can subscribe to secure and non-secure channels through the SUBSCRIBE_CHG[] registers, in order to trigger the task for enabling or disabling groups of channels. An event from a secure channel will be ignored if the group subscribing to this channel is non-secure. A secure group can subscribe to a nonsecure channel or a secure channel.

6.2.5 Registers

Table 33: Instances

Table 34: Register overview

6.2.5.1 TASKS_CHG[n].EN (n=0..5)

Address offset: 0x000 + (n × 0x8)

Enable channel group n

6.2.5.2 TASKS_CHG[n].DIS (n=0..5)

Address offset: 0x004 + (n × 0x8)

Disable channel group n

6.2.5.3 SUBSCRIBE_CHG[n].EN (n=0..5)

Address offset: 0x080 + (n × 0x8)

Subscribe configuration for task [CHG\[n\].EN](#page-91-0)

6.2.5.4 SUBSCRIBE_CHG[n].DIS (n=0..5)

Address offset: 0x084 + (n × 0x8)

Subscribe configuration for task [CHG\[n\].DIS](#page-91-1)

6.2.5.5 CHEN

Address offset: 0x500

Channel enable register

6.2.5.6 CHENSET

Address offset: 0x504

Channel enable set register

Note: Read: Reads value of CH{i} field in CHEN register

6.2.5.7 CHENCLR

Address offset: 0x508

Channel enable clear register

Note: Read: Reads value of CH{i} field in CHEN register

6.2.5.8 CHG[n] (n=0..5)

Address offset: 0x800 + (n × 0x4)

Channel group n

Note: Writes to this register are ignored if either SUBSCRIBE_CHG[n].EN or SUBSCRIBE_CHG[n].DIS is enabled

6.3 EGU — Event generator unit

Event generator unit (EGU) provides support for interlayer signaling. This means providing support for atomic triggering of both CPU execution and hardware tasks, from both firmware (by CPU) and hardware (by PPI). This feature can, for instance, be used for triggering CPU execution at a lower priority execution from a higher priority execution, or to handle a peripheral's interrupt service routine (ISR) execution at a lower priority for some of its events. However, triggering any priority from any priority is possible.

Listed here are the main EGU features:

- Software-enabled interrupt triggering
- Separate interrupt vectors for every EGU instance
- Up to 16 separate event flags per interrupt for multiplexing

Each instance of EGU implements a set of tasks which can individually be triggered to generate the corresponding event, for example, the corresponding event for TASKS TRIGGER[n] is EVENTS_TRIGGERED[n]. See [Instances](#page-94-0) on page 95 for a list of EGU instances.

6.3.1 Registers

Table 35: Instances

Table 36: Register overview

6.3.1.1 TASKS_TRIGGER[n] (n=0..15)

Address offset: 0x000 + (n × 0x4)

Trigger n for triggering the corresponding TRIGGERED[n] event

6.3.1.2 SUBSCRIBE_TRIGGER[n] (n=0..15)

Address offset: 0x080 + (n × 0x4)

Subscribe configuration for task [TRIGGER\[n\]](#page-94-1)

6.3.1.3 EVENTS_TRIGGERED[n] (n=0..15)

Address offset: 0x100 + (n × 0x4)

Event number n generated by triggering the corresponding TRIGGER[n] task

6.3.1.4 PUBLISH_TRIGGERED[n] (n=0..15)

Address offset: 0x180 + (n × 0x4)

Publish configuration for event [TRIGGERED\[n\]](#page-95-0)

6.3.1.5 INTEN

Address offset: 0x300

Enable or disable interrupt

6.3.1.6 INTENSET

Address offset: 0x304

Enable interrupt

6.3.1.7 INTENCLR

Address offset: 0x308

Disable interrupt

6.3.2 Electrical specification

6.3.2.1 EGU Electrical Specification

6.4 GPIO — General purpose input/output

The general purpose input/output pins (GPIOs) are grouped as one or more ports with each port having up to 32 GPIOs.

The number of ports and GPIOs per port may vary with product variant and package. Refer to [Registers](#page-100-0) on page 101 and [Pin assignments](#page-384-0) on page 385 for more information about the number of GPIOs that are supported.

GPIO has the following user-configurable features:

- Up to 32 GPIO pins per GPIO port
- Configurable output drive strength
- Internal pull-up and pull-down resistors
- Wake-up from high or low level triggers on all pins

- Trigger interrupt on state changes on any pin
- All pins can be used by the PPI task/event system
- One or more GPIO outputs can be controlled through PPI and GPIOTE channels
- All pins can be individually mapped to interface blocks for layout flexibility
- GPIO state changes captured on SENSE signal can be stored by LATCH register
- Support for secure and non-secure attributes for pins in conjunction with the system protection unit [\(SPU — System protection unit](#page-258-0) on page 259)

[GPIO port and the GPIO pin details](#page-97-0) on page 98 illustrates the GPIO port containing 32 individual pins, where PIN0 is illustrated in more detail as a reference. All signals on the left side in the illustration are used by other peripherals in the system and therefore not directly available to the CPU.

Figure 17: GPIO port and the GPIO pin details

6.4.1 Pin configuration

The GPIO port peripheral implements up to 32 pins, PIN0 through PIN31. Each of these pins can be individually configured in the PIN CNF[n] registers (n=0..31).

The following parameters can be configured through these registers:

- **Direction**
- Drive strength
- Enabling of pull-up and pull-down resistors
- Pin sensing
- Input buffer disconnect
- Analog input (for selected pins)

Note: All write-capable registers are retained registers, see [POWER — Power control](#page-63-0) on page 64 for more information.

The input buffer of a GPIO pin can be disconnected from the pin to enable power savings when the pin is not used as an input, see [GPIO port and the GPIO pin details](#page-97-0) on page 98. Inputs must be connected to get a valid input value in the [IN](#page-102-0) register, and for the sense mechanism to get access to the pin.

Other peripherals in the system can connect to GPIO pins and override their output value and configuration, or read their analog or digital input value. See [GPIO port and the GPIO pin details](#page-97-0) on page 98.

Selected pins also support analog input signals, see ANAIN in [GPIO port and the GPIO pin details](#page-97-0) on page 98. The assignment of the analog pins can be found in [Pin assignments](#page-384-0) on page 385.

The following delays should be taken into considerations:

There is a delay of 2 CPU clock cycles from the GPIO pad to the [IN](#page-102-0) register.

• The GPIO pad must be low (or high depending on the SENSE polarity) for 3 CPU clock cycles after DETECT has gone high to generate a new DETECT signal.

Note: When a pin is configured as digital input, care has been taken to minimize increased current consumption when the input voltage is between V_{II} and V_{III} . However, it is a good practice to ensure that the external circuitry does not drive that pin to levels between V_{II} and V_{IH} for a long period of time.

6.4.2 Pin sense mechanism

Pins sensitivity can be individually configured, through the SENSE field in the PIN CNF[n] register, to detect either a high level or a low level on their input.

When the correct level is detected on any such configured pin, the sense mechanism will set the DETECT signal high. Each pin has a separate DETECT signal. Default behavior, defined by the DETECTMODE register, is that the DETECT signals from all pins in the GPIO port are combined into one common DETECT signal that is routed throughout the system, which then can be utilized by other peripherals. This mechanism is functional in both System ON and System OFF modes.

DETECTMODE and DETECTMODE_SEC are provided to handle secure and non-secure pins. DETECTMODE_SEC register is available to control the behavior associated to pin marked as secure, while the DETECTMODE register is restricted to pin marked as non-secure. Please refer to [GPIO security](#page-99-0) on page 100 for more details.

Make sure that a pin is in a level that cannot trigger the sense mechanism before enabling it. The DETECT signal will go high immediately if the SENSE condition configured in the PIN CNF registers is met when the sense mechanism is enabled. This will trigger a PORT event if the DETECT signal was low before enabling the sense mechanism.

The DETECT signal is also used by power and clock management system to exit from System OFF mode, and by GPIOTE to generate the PORT event. In addition GPIOTE_SEC is used for PORT event related to secure pins). See [POWER — Power control](#page-63-0) on page 64 and [GPIOTE — GPIO tasks and events](#page-105-0) on page 106 for more information about how the DETECT signal is used.

When a pin's PINx.DETECT signal goes high, a flag will be set in the [LATCH](#page-103-0) register. For example, when the PIN0.DETECT signal goes high, bit 0 in the [LATCH](#page-103-0) register will be set to '1'. If the CPU performs a clear operation on a bit in the [LATCH](#page-103-0) register when the associated PINx.DETECT signal is high, the bit in the [LATCH](#page-103-0) register will not be cleared. The [LATCH](#page-103-0) register will only be cleared if the CPU explicitly clears it by writing a '1' to the bit that shall be cleared, i.e. the [LATCH](#page-103-0) register will not be affected by a PINx.DETECT signal being set low.

The LDETECT signal will be set high when one or more bits in the [LATCH](#page-103-0) register are '1'. The LDETECT signal will be set low when all bits in the [LATCH](#page-103-0) register are successfully cleared to '0'.

If one or more bits in the [LATCH](#page-103-0) register are '1' after the CPU has performed a clear operation on the [LATCH](#page-103-0) registers, a rising edge will be generated on the LDETECT signal. This is illustrated in [DETECT signal](#page-99-1) [behavior](#page-99-1) on page 100.

Note: The CPU can read the [LATCH](#page-103-0) register at any time to check if a SENSE condition has been met on one or more of the the GPIO pins, even if that condition is no longer met at the time the CPU queries the [LATCH](#page-103-0) register. This mechanism will work even if the LDETECT signal is not used as the DETECT signal.

The LDETECT signal is by default not connected to the GPIO port's DETECT signal, but via the DETECTMODE register it is possible to change from default behavior to DETECT signal being derived directly from the LDETECT signal instead. See [GPIO port and the GPIO pin details](#page-97-0) on page 98. [DETECT signal behavior](#page-99-1) on page 100 illustrates the DETECT signal behavior for these two alternatives.

Figure 18: DETECT signal behavior

6.4.3 GPIO security

The general purpose input/output (GPIO) peripheral is implemented as a *split-security* peripheral. If marked as non-secure, it can be accessed by both secure and non-secure accesses but will behave differently depending on the access type.

A non-secure peripheral access will only be able to configure and control pins defined as non-secure in the system protection unit (SPU) GPIOPORT.PERM[] register(s).

A non-secure access to a register or a bitfield controlling a pin marked as secure in GPIO.PERM[] register(s) will be ignored:

- write accesses will have no effect
- read accesses will always return a zero value

No exception is triggered when a non-secure access targets a register or bitfield controlling a secure pin.

For example, if the bit *i* is set in the SPU.GPIO.PERM[0] register (declaring Pin P0.*i* as secure), then

- non-secure write accesses to OUT, OUTSET, OUTCLR, DIR, DIRSET, DIRCLR and LATCH registers will not be able to write to bit *i* of those registers
- non-secure write accesses to registers PIN[*i*].OUT and PIN_CNF[*i*] will be ignored
- non-secure read accesses to registers OUT, OUTSET, OUTCLR, IN, DIR, DIRSET, DIRCLR and LATCH will always read a 0 for the bit at position *i*
- non-secure read accesses to registers PIN[*i*].OUT, PIN[*i*].OUT and PIN_CNF[*i*] will always return 0

The GPIO.DETECTMODE and GPIO.DETECTMODE SEC registers are handled differently than the other registers mentioned before. When accessed by a secure access, the DETECTMODE_SEC register control the source for the DETECT SEC signal for the pins marked as secure. When accessed by a non-secure access, the DETECTMODE SEC is read as zero and write accesses are ignored. The GPIO.DETECTMODE register controls the source for the DETECT_NSEC signal for the pins defined as non-secure.

The DETECT_NSEC signal is routed to the GPIOTE peripheral, allowing generation of events and interrupts from pins marked as non-secure. The DETECT SEC signal is routed to the GPIOTESEC peripheral, allowing generation of events and interrupts from pins marked as secure. [Principle of direct pin access](#page-100-1) on

page 101 illustrates how the DETECT_NSEC and DETECT_SEC signals are generated from the GPIO PIN[].DETECT signals.

Figure 19: Principle of direct pin access

6.4.4 Registers

Table 37: Instances

Table 38: Register overview

6.4.4.1 OUT (Retained)

Address offset: 0x004

Write GPIO port

This register is retained.

6.4.4.2 OUTSET

Address offset: 0x008

Set individual bits in GPIO port

Note: Read: reads value of OUT register.

6.4.4.3 OUTCLR

Address offset: 0x00C

Clear individual bits in GPIO port

Note: Read: reads value of OUT register.

6.4.4.4 IN

Address offset: 0x010

Read GPIO port

6.4.4.5 DIR (Retained)

Address offset: 0x014

Direction of GPIO pins

This register is retained.

6.4.4.6 DIRSET

Address offset: 0x018

DIR set register

Note: Read: reads value of DIR register.

6.4.4.7 DIRCLR

Address offset: 0x01C

DIR clear register

Note: Read: reads value of DIR register.

6.4.4.8 LATCH (Retained)

Address offset: 0x020

Latch register indicating what GPIO pins that have met the criteria set in the PIN_CNF[n].SENSE registers This register is retained.

6.4.4.9 DETECTMODE (Retained)

Address offset: 0x024

Select between default DETECT signal behavior and LDETECT mode (For non-secure pin only)

This register is retained.

6.4.4.10 DETECTMODE_SEC (Retained)

Address offset: 0x028

Select between default DETECT signal behavior and LDETECT mode (For secure pin only)

This register is retained.

6.4.4.11 PIN_CNF[n] (n=0..31) (Retained)

Configuration of GPIO pins

This register is retained.

6.4.5 Electrical specification

6.4.5.1 GPIO Electrical Specification

6.5 GPIOTE — GPIO tasks and events

The GPIO tasks and events (GPIOTE) module provides functionality for accessing GPIO pins using tasks and events. Each GPIOTE channel can be assigned to one pin.

A GPIOTE block enables GPIOs to generate events on pin state change which can be used to carry out tasks through the PPI system. A GPIO can also be driven to change state on system events using the PPI system. Tasks and events are briefly introduced in [Peripheral interface](#page-14-0) on page 15, and GPIO is described in more detail in [GPIO — General purpose input/output](#page-96-2) on page 97.

Low power detection of pin state changes is possible when in System ON or System OFF.

Table 39: GPIOTE properties

Up to three tasks can be used in each GPIOTE channel for performing write operations to a pin. Two tasks are fixed (SET and CLR), and one (OUT) is configurable to perform following operations:

- Set
- Clear
- Toggle

 1 Rise and fall times based on simulations

An event can be generated in each GPIOTE channel from one of the following input conditions:

- Rising edge
- Falling edge
- Any change

6.5.1 Pin events and tasks

The GPIOTE module has a number of tasks and events that can be configured to operate on individual GPIO pins.

The tasks SET[n], CLR[n], and OUT[n] can write to individual pins, and events IN[n] can be generated from input changes of individual pins.

The SET task will set the pin selected in [GPIOTE.CONFIG\[n\]](#page-111-0).PSEL to high. The CLR task will set the pin low.

The effect of the OUT task on the pin is configurable in CONFIG[n].POLARITY. It can set the pin high, set it low, or toggle it.

Tasks and events are configured using the CONFIG[n] registers. One CONFIG[n] register is associated with a set of SET[n], CLR[n], and OUT[n] tasks and IN[n] events.

As long as a SET[n], CLR[n], and OUT[n] task or an IN[n] event is configured to control pin **n**, the pin's output value will only be updated by the GPIOTE module. The pin's output value, as specified in the GPIO, will be ignored as long as the pin is controlled by GPIOTE. Attempting to write to the pin as a normal GPIO pin will have no effect. When the GPIOTE is disconnected from a pin, the associated pin gets the output and configuration values specified in the GPIO module, see MODE field in CONFIG[n] register.

When conflicting tasks are triggered simultaneously (i.e. during the same clock cycle) in one channel, the priority of the tasks is as described in the following table.

Table 40: Task priorities

When setting the CONFIG[n] registers, MODE=Disabled does not have the same effect as MODE=Task and POLARITY=None. In the latter case, a CLR or SET task occurring at the exact same time as OUT will end up with no change on the pin, based on the priorities described in the table above.

When a GPIOTE channel is configured to operate on a pin as a task, the initial value of that pin is configured in the OUTINIT field of CONFIG[n].

6.5.2 Port event

PORT is an event that can be generated from multiple input pins using the GPIO DETECT signal.

The event will be generated on the rising edge of the DETECT signal. See [GPIO — General purpose input/](#page-96-2) [output](#page-96-2) on page 97 for more information about the DETECT signal.

The GPIO DETECT signal will not wake the system up again if the system is put into System ON IDLE while the DETECT signal is high. Clear all DETECT sources before entering sleep. If the LATCH register is used as a source, a new rising edge will be generated on DETECT if any bit in LATCH is still high after clearing all or part of the register. This could occur if one of the PINx.DETECT signals is still high, for example. See [Pin](#page-98-0) [sense mechanism](#page-98-0) on page 99 for more information.

Setting the system to System OFF while DETECT is high will cause a wakeup from System OFF reset.

This feature can be used to wake up the CPU from a WFI or WFE type sleep in System ON when all peripherals and the CPU are idle, meaning the lowest power consumption in System ON mode.

To prevent spurious interrupts from the PORT event while configuring the sources, the following steps must be performed:

- **1.** Disable interrupts on the PORT event (through INTENCLR.PORT).
- **2.** Configure the sources (PIN_CNF[n].SENSE).
- **3.** Clear any potential event that could have occurred during configuration (write 0 to EVENTS PORT).
- **4.** Enable interrupts (through INTENSET.PORT).

6.5.3 Tasks and events pin configuration

Each GPIOTE channel is associated with one physical GPIO pin through the CONFIG.PSEL field.

When Event mode is selected in CONFIG.MODE, the pin specified by CONFIG.PSEL will be configured as an input, overriding the DIR setting in GPIO. Similarly, when Task mode is selected in CONFIG.MODE, the pin specified by CONFIG.PSEL will be configured as an output overriding the DIR setting and OUT value in GPIO. When Disabled is selected in CONFIG.MODE, the pin specified by CONFIG.PSEL will use its configuration from the PIN[n].CNF registers in GPIO. CONFIG.MODE must be disabled in order to be able to change the value of the PSEL field.

Note: A pin can only be assigned to one GPIOTE channel at a time. Failing to do so may result in unpredictable behavior.

6.5.4 Registers

Table 41: Instances

Table 42: Register overview

6.5.4.1 TASKS_OUT[n] (n=0..7)

Address offset: 0x000 + (n × 0x4)

Task for writing to pin specified in CONFIG[n].PSEL. Action on pin is configured in CONFIG[n].POLARITY.

6.5.4.2 TASKS_SET[n] (n=0..7)

Address offset: 0x030 + (n × 0x4)

Task for writing to pin specified in CONFIG[n].PSEL. Action on pin is to set it high.

6.5.4.3 TASKS_CLR[n] (n=0..7)

Address offset: 0x060 + (n × 0x4)

Task for writing to pin specified in CONFIG[n].PSEL. Action on pin is to set it low.

6.5.4.4 SUBSCRIBE_OUT[n] (n=0..7)

Address offset: 0x080 + (n × 0x4)

Subscribe configuration for task [OUT\[n\]](#page-107-0)

6.5.4.5 SUBSCRIBE_SET[n] (n=0..7)

Address offset: 0x0B0 + (n × 0x4)

Subscribe configuration for task [SET\[n\]](#page-108-0)

6.5.4.6 SUBSCRIBE_CLR[n] (n=0..7)

Address offset: 0x0E0 + (n × 0x4)

Subscribe configuration for task [CLR\[n\]](#page-108-1)

6.5.4.7 EVENTS_IN[n] (n=0..7)

Address offset: 0x100 + (n × 0x4)

Event generated from pin specified in CONFIG[n].PSEL

6.5.4.8 EVENTS_PORT

Address offset: 0x17C

Event generated from multiple input GPIO pins with SENSE mechanism enabled

6.5.4.9 PUBLISH_IN[n] (n=0..7)

Address offset: 0x180 + (n × 0x4)

Publish configuration for event [IN\[n\]](#page-109-0)

6.5.4.10 PUBLISH_PORT

Address offset: 0x1FC

Publish configuration for event [PORT](#page-109-1)

6.5.4.11 INTENSET

Address offset: 0x304

Enable interrupt

6.5.4.12 INTENCLR

Address offset: 0x308

Disable interrupt

6.5.4.13 CONFIG[n] (n=0..7)

Address offset: 0x510 + (n × 0x4)

Configuration for OUT[n], SET[n], and CLR[n] tasks and IN[n] event

e generated if operation specified in POLARITY of p the pin.

6.5.5 Electrical specification

6.6 IPC — Interprocessor communication

The interprocessor communication (IPC) peripheral is used to send and receive events between MCUs in the system.

Figure 20: IPC block diagram

Functional description

[IPC block diagram](#page-113-0) on page 114 illustrates the interprocessor communication (IPC) peripheral. In a multi-MCU system, each MCU has one dedicated IPC peripheral. The IPC peripheral can be used to send and receive events to and from other IPC peripherals. An instance of the IPC peripheral can have multiple SEND tasks and RECEIVE events. A single SEND task can be configured to signal an event on one or more IPC channels, and a RECEIVE event can be configured to listen on one or more IPC channels. The IPC channels that are triggered in a SEND task can be configured through the [SEND_CNF](#page-117-0) registers, and the IPC channels that trigger a RECEIVE event are configured through the RECEIVE CNF registers. The figure below illustrates how the [SEND_CNF](#page-117-0) and [RECEIVE_CNF](#page-118-0) registers work. Both the SEND task and the RECEIVE event can be connected to all IPC channels.

Figure 21: IPC registers SEND_CNF and RECEIVE_CNF

A SEND task can be viewed as broadcasting events onto one or more IPC channels, and a RECEIVE event can be seen as subscribing to a subset of IPC channels. It is possible for multiple IPCs to trigger events onto the same channel at the same time. When two or more events on the same channel occur within t_{IPC}, the events may be merged into a single event seen from the IPC receiver. One of the events can therefore be lost. To prevent this, the user must ensure that events on the same IPC channel do not occur within t_{IPC} of each other. When implementing firmware data structures, such as queues or mailboxes, this can be done by using one channel for acknowledgements.

An IPC event often does not contain any data itself, it is used to signal other MCUs that something has occurred. Data can be shared through shared memory, for example in the form of a software implemented mailbox, or command/event queues. It is up to software to assign a logical functionality to an IPC channel. For instance, one IPC channel can be used to signal that a command is ready to be executed, and any processor in the system can subscribe to that particular channel and decode/execute the command.

General purpose memory

The [GPMEM](#page-118-1) registers can be used freely to store information. These registers are accessed like any other of the IPC peripheral's registers.

6.6.1 IPC and PPI connections

The IPC SEND tasks and RECEIVE events can be connected through PPI channels. This makes it possible to relay events from peripherals in one MCU to another, without CPU involvement.

Figure below illustrates a timer COMPARE event that is relayed from one MCU to IPC using PPI, then back into a timer CAPTURE event in another MCU.

Figure 22: Example of PPI and IPC connections

6.6.2 Registers

Table 43: Instances

Table 44: Register overview

6.6.2.1 TASKS_SEND[n] (n=0..7)

Address offset: 0x000 + (n × 0x4)

Trigger events on IPC channel enabled in SEND_CNF[n]

6.6.2.2 SUBSCRIBE_SEND[n] (n=0..7)

Address offset: 0x080 + (n × 0x4)

Subscribe configuration for task [SEND\[n\]](#page-115-0)

6.6.2.3 EVENTS_RECEIVE[n] (n=0..7)

Address offset: 0x100 + (n × 0x4)

Event received on one or more of the enabled IPC channels in RECEIVE_CNF[n]

6.6.2.4 PUBLISH_RECEIVE[n] (n=0..7)

Address offset: 0x180 + (n × 0x4)

Publish configuration for event [RECEIVE\[n\]](#page-116-0)

6.6.2.5 INTEN

Address offset: 0x300

Enable or disable interrupt

6.6.2.6 INTENSET

Address offset: 0x304

Enable interrupt

6.6.2.7 INTENCLR

Address offset: 0x308

Disable interrupt

6.6.2.8 INTPEND

Address offset: 0x30C

Pending interrupts

6.6.2.9 SEND_CNF[n] (n=0..7)

Address offset: 0x510 + (n × 0x4)

Send event configuration for TASKS_SEND[n]

6.6.2.10 RECEIVE_CNF[n] (n=0..7)

Address offset: 0x590 + (n × 0x4)

Receive event configuration for EVENTS_RECEIVE[n]

6.6.2.11 GPMEM[n] (n=0..3)

Address offset: $0x610 + (n \times 0x4)$

General purpose memory

Retained only in System ON mode

6.6.3 Electrical specification

6.6.3.1 IPC Electrical Specification

6.7 $1²S$ – Inter-IC sound interface

The I²S (Inter-IC Sound) module, supports the original two-channel I²S format, and left or right-aligned formats. It implements EasyDMA for sample transfer directly to and from RAM without CPU intervention.

The I²S peripheral has the following main features:

- Master and Slave mode
- Simultaneous bi-directional (TX and RX) audio streaming
- Original I²S and left- or right-aligned format

- 8, 16 and 24-bit sample width
- Low-jitter Master Clock generator
- Various sample rates

Figure 23: I² S master

6.7.1 Mode

The I^2 S protocol specification defines two modes of operation, Master and Slave.

The I²S mode decides which of the two sides (Master or Slave) shall provide the clock signals LRCK and SCK, and these signals are always supplied by the Master to the Slave.

6.7.2 Transmitting and receiving

The I²S module supports both transmission (TX) and reception (RX) of serial data. In both cases the serial data is shifted synchronously to the clock signals SCK and LRCK.

TX data is written to the SDOUT pin on the falling edge of SCK, and RX data is read from the SDIN pin on the rising edge of SCK. The most significant bit (MSB) is always transmitted first.

Note: When starting a transmission in master mode, two frames (two left-and-right sample pairs) of value zero will be transmitted after triggering the START task, prior to the RXTXD.MAXCNT samples specified by the TXD.PTR pointer.

TX and RX are available in both Master and Slave modes and can be enabled/disabled independently in the [CONFIG.TXEN](#page-133-0) on page 134 and [CONFIG.RXEN](#page-133-1) on page 134.

Transmission and/or reception is started by triggering the START task. When started and transmission is enabled (in [CONFIG.TXEN](#page-133-0) on page 134), the TXPTRUPD event will be generated for every [RXTXD.MAXCNT](#page-136-0) on page 137 number of transmitted data words (containing one or more samples).

Similarly, when started and reception is enabled (in [CONFIG.RXEN](#page-133-1) on page 134), the RXPTRUPD event will be generated for every [RXTXD.MAXCNT](#page-136-0) on page 137 received data words.

Figure 24: Transmitting and receiving. CONFIG.FORMAT = Aligned, CONFIG.SWIDTH = 8Bit, CONFIG.CHANNELS = Stereo, RXTXD.MAXCNT = 1.

6.7.3 Left right clock (LRCK)

The Left Right Clock (LRCK), often referred to as "word clock", "sample clock" or "word select" in 1^2 S context, is the clock defining the frames in the serial bit streams sent and received on SDOUT and SDIN, respectively.

In I2S mode, each frame contains one left and right sample pair, with the left sample being transferred during the low half period of LRCK followed by the right sample being transferred during the high period of LRCK.

In Aligned mode, each frame contains one left and right sample pair, with the left sample being transferred during the high half period of LRCK followed by the right sample being transferred during the low period of LRCK.

Consequently, the LRCK frequency is equivalent to the audio sample rate.

When operating in Master mode, the LRCK is generated from the MCK, and the frequency of LRCK is then given as:

LRCK = MCK / CONFIG.RATIO

LRCK always toggles around the falling edge of the serial clock SCK.

6.7.4 Serial clock (SCK)

The serial clock (SCK), often referred to as the serial bit clock, pulses once for each data bit being transferred on the serial data lines SDIN and SDOUT.

When operating in Master mode the SCK is generated from the MCK, and the frequency of SCK is then given as:

SCK = 2 * LRCK * CONFIG.SWIDTH

The falling edge of the SCK falls on the toggling edge of LRCK.

When operating in Slave mode SCK is provided by the external I^2 S master.

6.7.5 Master clock (MCK)

The master clock (MCK) is the clock from which LRCK and SCK are derived when operating in Master mode.

The MCK is generated by an internal MCK generator. This generator always needs to be enabled when in Master mode, but the generator can also be enabled when in Slave mode. Enabling the generator when in slave mode can be useful in the case where the external Master is not able to generate its own master clock.

The MCK generator is enabled/disabled in the register [CONFIG.MCKEN](#page-133-2) on page 134, and the generator is started or stopped by the START or STOP tasks.

In Master mode the LRCK and the SCK frequencies are closely related, as both are derived from MCK and set indirectly through [CONFIG.RATIO](#page-134-0) on page 135 and [CONFIG.SWIDTH](#page-135-0) on page 136.

When configuring these registers, the user is responsible for fulfilling the following requirements:

1. SCK frequency can never exceed the MCK frequency, which can be formulated as:

```
CONFIG.RATIO >= 2 * CONFIG.SWIDTH
```
2. The MCK/LRCK ratio shall be a multiple of 2 * CONFIG.SWIDTH, which can be formulated as:

```
Integer = (CONFIG.RATIO / (2 * CONFIG.SWIDTH))
```
The MCK signal can be routed to an output pin (specified in PSEL.MCK) to supply external I^2 S devices that require the MCK to be supplied from the outside.

When operating in Slave mode, the I²S module does not use the MCK and the MCK generator does not need to be enabled.

> MCK LRCK SCK $RATIO = \frac{MCK}{H}$ **LRCK** \leq SWIDTH

Figure 25: Relation between RATIO, MCK and LRCK.

Table 45: Configuration examples

6.7.6 Width, alignment and format

The CONFIG.SWIDTH register primarily defines the sample width of the data written to memory. In master mode, it then also sets the amount of bits per frame. In Slave mode it controls padding/trimming if required. Left, right, transmitted, and received samples always have the same width. The CONFIG.FORMAT

register specifies the position of the data frames with respect to the LRCK edges in both Master and Slave modes.

When using I²S format, the first bit in a half-frame (containing one left or right sample) gets sampled on the second rising edge of the SCK after a LRCK edge. When using Aligned mode, the first bit in a half-frame gets sampled on the first rising edge of SCK following a LRCK edge.

For data being received on SDIN the sample value can be either right or left-aligned inside a half-frame, as specified in [CONFIG.ALIGN](#page-135-1) on page 136. [CONFIG.ALIGN](#page-135-1) on page 136 affects only the decoding of the incoming samples (SDIN), while the outgoing samples (SDOUT) are always left-aligned (or justified).

When using left-alignment, each half-frame starts with the MSB of the sample value (both for data being sent on SDOUT and received on SDIN).

When using right-alignment, each half-frame of data being received on SDIN ends with the LSB of the sample value, while each half-frame of data being sent on SDOUT starts with the MSB of the sample value (same as for left-alignment).

In Master mode, the size of a half-frame (in number of SCK periods) equals the sample width (in number of bits), and in this case the alignment setting does not care as each half-frame in any case will start with the MSB and end with the LSB of the sample value.

In slave mode, however, the sample width does not need to equal the frame size. This means you might have extra or fewer SCK pulses per half-frame than what the sample width specified in [CONFIG.SWIDTH](#page-135-0) requires.

In the case where we use **left-alignment** and the number of SCK pulses per half-frame is **higher** than the sample width, the following will apply:

- For data received on SDIN, all bits after the LSB of the sample value will be discarded.
- For data sent on SDOUT, all bits after the LSB of the sample value will be 0.

In the case where we use **left-alignment** and the number of SCK pulses per frame is **lower** than the sample width, the following will apply:

• Data sent and received on SDOUT and SDIN will be truncated with the LSBs being removed first.

In the case where we use **right-alignment** and the number of SCK pulses per frame is **higher** than the sample width, the following will apply:

- For data received on SDIN, all bits before the MSB of the sample value will be discarded.
- For data sent on SDOUT, all bits after the LSB of the sample value will be 0 (same behavior as for leftalignment).

In the case where we use **right-alignment** and the number of SCK pulses per frame is **lower** than the sample width, the following will apply:

- Data received on SDIN will be sign-extended to "sample width" number of bits before being written to memory.
- Data sent on SDOUT will be truncated with the LSBs being removed first (same behavior as for leftalignment).

Figure 26: I² S format. CONFIG.SWIDTH equalling half-frame size.

Figure 27: Aligned format. CONFIG.SWIDTH equalling half-frame size.

6.7.7 EasyDMA

The I²S module implements EasyDMA for accessing internal Data RAM without CPU intervention.

The source and destination pointers for the TX and RX data are configured in [TXD.PTR](#page-136-1) on page 137 and [RXD.PTR](#page-136-2) on page 137. The memory pointed to by these pointers will only be read or written when TX or RX are enabled in [CONFIG.TXEN](#page-133-0) on page 134 and [CONFIG.RXEN](#page-133-1) on page 134.

The addresses written to the pointer registers [TXD.PTR](#page-136-1) on page 137 and [RXD.PTR](#page-136-2) on page 137 are double-buffered in hardware, and these double buffers are updated for every [RXTXD.MAXCNT](#page-136-0) on page 137 words (containing one or more samples) read/written from/to memory. The events TXPTRUPD and RXPTRUPD are generated whenever the TXD.PTR and RXD.PTR are transferred to these double buffers.

If [TXD.PTR](#page-136-1) on page 137 is not pointing to the Data RAM region when transmission is enabled, or [RXD.PTR](#page-136-2) on page 137 is not pointing to the Data RAM region when reception is enabled, an EasyDMA transfer may result in a HardFault and/or memory corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions.

Due to the nature of I²S, where the number of transmitted samples always equals the number of received samples (at least when both TX and RX are enabled), one common register [RXTXD.MAXCNT](#page-136-0) on page 137 is used for specifying the sizes of these two memory buffers. The size of the buffers is specified in a number of 32-bit words. Such a 32-bit memory word can either contain four 8-bit samples, two 16-bit samples or one right-aligned 24-bit sample sign extended to 32 bit.

In stereo mode (CONFIG.CHANNELS=Stereo), the samples are stored as "left and right sample pairs" in memory. Figure [Memory mapping for 8 bit stereo. CONFIG.SWIDTH = 8Bit, CONFIG.CHANNELS = Stereo.](#page-123-0) on page 124, [Memory mapping for 16 bit stereo. CONFIG.SWIDTH = 16Bit, CONFIG.CHANNELS = Stereo.](#page-124-0) on page 125 and [Memory mapping for 24 bit stereo. CONFIG.SWIDTH = 24Bit, CONFIG.CHANNELS =](#page-124-1) [Stereo.](#page-124-1) on page 125 show how the samples are mapped to memory in this mode. The mapping is valid for both RX and TX.

In mono mode (CONFIG.CHANNELS=Left or Right), RX sample from only one channel in the frame is stored in memory, the other channel sample is ignored. Illustrations [Memory mapping for 8 bit mono.](#page-124-2) [CONFIG.SWIDTH = 8Bit, CONFIG.CHANNELS = Left.](#page-124-2) on page 125, [Memory mapping for 16 bit mono, left](#page-124-3) [channel only. CONFIG.SWIDTH = 16Bit, CONFIG.CHANNELS = Left.](#page-124-3) on page 125 and [Memory mapping](#page-125-0) [for 24 bit mono, left channel only. CONFIG.SWIDTH = 24Bit, CONFIG.CHANNELS = Left.](#page-125-0) on page 126 show how RX samples are mapped to memory in this mode.

For TX, the same outgoing sample read from memory is transmitted on both left and right in a frame, resulting in a mono output stream.

Figure 28: Memory mapping for 8 bit stereo. CONFIG.SWIDTH = 8Bit, CONFIG.CHANNELS = Stereo.

	31	24 23 16 15	87	0
x.PTR	Left sample 3	Left sample 2	Left sample 1	Left sample 0
$x.PTR + 4$	Left sample 7	Left sample 6	Left sample 5	Left sample 4
$x.PTR + n - 4$	Left sample $n-1$	Left sample $n-2$	Left sample $n-3$	Left sample $n-4$

Figure 29: Memory mapping for 8 bit mono. CONFIG.SWIDTH = 8Bit, CONFIG.CHANNELS = Left.

Figure 30: Memory mapping for 16 bit stereo. CONFIG.SWIDTH = 16Bit, CONFIG.CHANNELS = Stereo.

Figure 31: Memory mapping for 16 bit mono, left channel only. CONFIG.SWIDTH = 16Bit, CONFIG.CHANNELS = Left.

Figure 32: Memory mapping for 24 bit stereo. CONFIG.SWIDTH = 24Bit, CONFIG.CHANNELS = Stereo.

Figure 33: Memory mapping for 24 bit mono, left channel only. CONFIG.SWIDTH = 24Bit, CONFIG.CHANNELS = Left.

6.7.8 Module operation

Described here is a typical operating procedure for the I²S module.

1. Configure the I²S module using the CONFIG registers

```
// Enable reception
NRF_I2S->CONFIG.RXEN = (I2S_CONFIG_RXEN_RXEN_Enabled <<
                                      I2S CONFIG RXEN RXEN Pos);
// Enable transmission
NRF_I2S->CONFIG.TXEN = (I2S_CONFIG_TXEN_TXEN_Enabled <<
                                       I2S_CONFIG_TXEN_TXEN_Pos);
// Enable MCK generator
NRF_I2S->CONFIG.MCKEN = (I2S_CONFIG_MCKEN_MCKEN_Enabled <<
                                       I2S CONFIG MCKEN MCKEN Pos);
// MCKFREQ = 4 MHz
NRF_I2S->CONFIG.MCKFREQ = I2S_CONFIG_MCKFREQ_MCKFREQ_32MDIV8 <<
                                       I2S_CONFIG_MCKFREQ_MCKFREQ_Pos;
// Ratio = 256 
NRF_I2S->CONFIG.RATIO = I2S_CONFIG_RATIO_RATIO_256X <<
                                       I2S_CONFIG_RATIO_RATIO_Pos;
// MCKFREQ = 4 MHz and Ratio = 256 gives sample rate = 15.625 ks/s
// Sample width = 16 bit
NRF_I2S->CONFIG.SWIDTH = I2S_CONFIG_SWIDTH_SWIDTH_16Bit <<
                                       I2S_CONFIG_SWIDTH_SWIDTH_Pos;
// Alignment = Left
NRF_I2S->CONFIG.ALIGN = I2S_CONFIG_ALIGN_ALIGN_Left <<
                                        I2S_CONFIG_ALIGN_ALIGN_Pos;
// Format = I2S
NRF_I2S->CONFIG.FORMAT = I2S_CONFIG_FORMAT_FORMAT_I2S <<
                                       I2S_CONFIG_FORMAT_FORMAT_Pos;
// Use stereo 
NRF_I2S->CONFIG.CHANNELS = I2S_CONFIG_CHANNELS_CHANNELS_Stereo <<
                                       I2S CONFIG CHANNELS CHANNELS Pos;
```


2. Map IO pins using the PINSEL registers

```
// MCK routed to pin 0
NRF_I2S->PSEL.MCK = (0 << I2S_PSEL_MCK_PIN_Pos) | 
                    (I2S_PSEL_MCK_CONNECT_Connected <<
                                                 I2S_PSEL_MCK_CONNECT_Pos);
// SCK routed to pin 1
NRF I2S->PSEL.SCK = (1 \leq I2S PSEL SCK PIN POS) |
                     (I2S_PSEL_SCK_CONNECT_Connected <<
                                                  I2S_PSEL_SCK_CONNECT_Pos); 
// LRCK routed to pin 2
NRF I2S->PSEL.LRCK = (2 \lt\lt I2S PSEL_LRCK_PIN_Pos) |
                      (I2S_PSEL_LRCK_CONNECT_Connected <<
                                                 I2S_PSEL_LRCK_CONNECT_Pos);
// SDOUT routed to pin 3
NRF_I2S->PSEL.SDOUT = (3 << I2S_PSEL_SDOUT_PIN_Pos) |
                       (I2S_PSEL_SDOUT_CONNECT_Connected <<
                                                 I2S_PSEL_SDOUT_CONNECT_Pos);
// SDIN routed on pin 4
NRF I2S->PSEL.SDIN = (4 \ll I2S PSEL SDIN PIN POS) |
                      (I2S_PSEL_SDIN_CONNECT_Connected <<
                                                  I2S_PSEL_SDIN_CONNECT_Pos);
```
3. Configure TX and RX data pointers using the TXD, RXD and RXTXD registers

```
NRF I2S->TXD.PTR = my tx buf;
NRF I2S->RXD.PTR = myrxbuf;NRF_I2S->TXD.MAXCNT = MY_BUF_SIZE;
```
4. Enable the I²S module using the ENABLE register

NRF $I2S->ENABLE = 1;$

5. Start audio streaming using the START task

NRF $I2S->TASKS$ START = 1;

6. Handle received and transmitted data when receiving the TXPTRUPD and RXPTRUPD events

```
if(NRF_I2S->EVENTS_TXPTRUPD != 0)
{
   NRF_I2S->TXD.PTR = my_next_tx_buf;
   NRF I2S->EVENTS TXPTRUPD = 0;
}
if(NRF_I2S->EVENTS_RXPTRUPD != 0)
{
    NRF_I2S->RXD.PTR = my_next_rx_buf;
   NRF I2S->EVENTS RXPTRUPD = 0;
}
```


6.7.9 Pin configuration

The MCK, SCK, LRCK, SDIN and SDOUT signals associated with the 1^2 S module are mapped to physical pins according to the pin numbers specified in the PSEL.x registers.

These pins are acquired whenever the I^2 S module is enabled through the register [ENABLE](#page-132-0) on page 133.

When a pin is acquired by the I²S module, the direction of the pin (input or output) will be configured automatically, and any pin direction setting done in the GPIO module will be overridden. The directions for the various I²S pins are shown below in [GPIO configuration before enabling peripheral \(master mode\)](#page-127-0) on page 128 and [GPIO configuration before enabling peripheral \(slave mode\)](#page-127-1) on page 128.

To secure correct signal levels on the pins when the system is in OFF mode, and when the 1^2 S module is disabled, these pins must be configured in the GPIO peripheral directly.

Table 46: GPIO configuration before enabling peripheral (master mode)

Table 47: GPIO configuration before enabling peripheral (slave mode)

6.7.10 Registers

Table 48: Instances

Table 49: Register overview

6.7.10.1 TASKS_START

Address offset: 0x000

Starts continuous I2S transfer. Also starts MCK generator when this is enabled.

6.7.10.2 TASKS_STOP

Address offset: 0x004

Stops I2S transfer. Also stops MCK generator. Triggering this task will cause the [STOPPED](#page-130-0) event to be generated.

6.7.10.3 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-128-0)

6.7.10.4 SUBSCRIBE_STOP

Address offset: 0x084

Subscribe configuration for task [STOP](#page-128-1)

6.7.10.5 EVENTS_RXPTRUPD

Address offset: 0x104

The RXD.PTR register has been copied to internal double-buffers. When the I2S module is started and RX is enabled, this event will be generated for every RXTXD.MAXCNT words that are received on the SDIN pin.

6.7.10.6 EVENTS_STOPPED

Address offset: 0x108

I2S transfer stopped.

6.7.10.7 EVENTS_TXPTRUPD

Address offset: 0x114

The TDX.PTR register has been copied to internal double-buffers. When the I2S module is started and TX is enabled, this event will be generated for every RXTXD.MAXCNT words that are sent on the SDOUT pin.

6.7.10.8 PUBLISH_RXPTRUPD

Address offset: 0x184

Publish configuration for event [RXPTRUPD](#page-129-2)

6.7.10.9 PUBLISH_STOPPED

Address offset: 0x188

Publish configuration for event [STOPPED](#page-130-0)

6.7.10.10 PUBLISH_TXPTRUPD

Address offset: 0x194

Publish configuration for event [TXPTRUPD](#page-130-1)

6.7.10.11 INTEN

Address offset: 0x300

Enable or disable interrupt

6.7.10.12 INTENSET

Address offset: 0x304

Enable interrupt

6.7.10.13 INTENCLR

Address offset: 0x308

Disable interrupt

6.7.10.14 ENABLE

Address offset: 0x500

Enable I2S module.

6.7.10.15 CONFIG.MODE

Address offset: 0x504

I2S mode.

6.7.10.16 CONFIG.RXEN

Address offset: 0x508

Reception (RX) enable.

6.7.10.17 CONFIG.TXEN

Address offset: 0x50C

Transmission (TX) enable.

6.7.10.18 CONFIG.MCKEN

Address offset: 0x510

Master clock generator enable.

6.7.10.19 CONFIG.MCKFREQ

Address offset: 0x514

Master clock generator frequency.

6.7.10.20 CONFIG.RATIO

Address offset: 0x518

MCK / LRCK ratio.

6.7.10.21 CONFIG.SWIDTH

Address offset: 0x51C

Sample width.

6.7.10.22 CONFIG.ALIGN

Address offset: 0x520

Alignment of sample within a frame.

6.7.10.23 CONFIG.FORMAT

Address offset: 0x524

Frame format.

6.7.10.24 CONFIG.CHANNELS

Address offset: 0x528

Enable channels.

6.7.10.25 RXD.PTR

Address offset: 0x538

Receive buffer RAM start address.

word aligned Data RAM address.

word aligned Data RAM address.

6.7.10.26 TXD.PTR

Address offset: 0x540

Transmit buffer RAM start address.

6.7.10.27 RXTXD.MAXCNT

Address offset: 0x550

Size of RXD and TXD buffers.

6.7.10.28 PSEL.MCK

Address offset: 0x560

Pin select for MCK signal.

6.7.10.29 PSEL.SCK

Address offset: 0x564

Pin select for SCK signal.

6.7.10.30 PSEL.LRCK

Address offset: 0x568

Pin select for LRCK signal.

6.7.10.31 PSEL.SDIN

Address offset: 0x56C

Pin select for SDIN signal.

6.7.10.32 PSEL.SDOUT

Address offset: 0x570

Pin select for SDOUT signal.

6.7.11 Electrical specification

6.7.11.1 I2S timing specification

Figure 34: I2S timing diagram

6.8 KMU — Key management unit

The key management unit (KMU) enforces access policies to a subset region of user information configuration register (UICR). This subset region is used for storing cryptographic key values inside the key slots, which the CPU has no access to.

In total there are 128 key slots available, where each key slot can store one 128-bit key value together with an access policy and a destination address for the key value. Multiple key slots can be combined in order to support key sizes larger than 128 bits. The access policy of a key slot governs if and how a key value can

be used, while the destination address determines where in the memory map the KMU pushes the key value upon a request from the CPU.

Key slots can be configured to be pushed directly into write-only key registers in cryptographic accelerators, like e.g. CryptoCell, without exposing the key value itself to the CPU. This enables the CPU to use the key values stored inside the key slots for cryptographic operations without being exposed to the key value.

Access to the KMU, and the key slots in the UICR, is only allowed from secure mode.

6.8.1 Functional view

From a functional view the UICR is divided into two different regions, one-time programmable (OTP) memory and key storage.

Figure 35: Memory map overview

OTP

One-time programmable (OTP) memory is typically used for holding values that are written once, and then never to be changed again throughout the product lifetime. The OTP region of UICR is emulated by placing a write-once per halfword limitation on registers defined here.

Key storage

The key storage region contains multiple key slots, where each slot consists of a key header and an associated key value. The key value is limited to 128 bits. Any key size greater than 128 bits must be divided and distributed over multiple key slot instances.

Key headers are allocated an address range of 0x400 in the UICR memory map, allowing a total of 128 keys to be addressable inside the key storage region.

Note: The use of the key storage region in UICR should be limited to keys with a certain life span, and not per-session derived keys where the CPU is involved in the key exchange.

6.8.2 Access control

Access control to the underlying UICR infopage in flash is enforced by a hardware finite-state machine (FSM). The FSM can allow or block transactions, depending both on the security of the transaction (secure or non-secure) and on the type of register being written and/or read.

Table 50: Access control

Any restricted access requires an explicit key slot selection through the KMU register interface. Any illegal access to restricted key slot registers will be blocked and word $0 \times DEADDEAD$ will be returned on the AHB.

The OTP region has individual access control behavior, while access control to the key storage region is configured on a per key slot basis. The KMU FSM operates on only one key slot instance at a time, and the permissions and the usage restriction for a key value associated with a key slot can be configured individually.

Note: Even if the KMU can be configured as non-secure, all non-secure transactions will be blocked.

6.8.3 Protecting the UICR content

The UICR content can be protected against device-internal NVMC.ERASEALL requests, in addition to device-external ERASEALL requests, through the CTRL-AP interface. This feature is useful if the firmware designers want to prevent the OTP region from being erased.

Since enabling this step will permanently disable erase for the UICR, the procedure requires an implementation defined 32-bit word to be written into the UICR's ERASEPROTECT register.

In case of a field return handling, it is still possible to erase the UICR even if the ERASEPROTECT is set. If this functionality is desired, the secure boot code must implement a secure communication channel over the CTRL-AP mailbox interface. Upon successful authentication of the external party, the secure boot code can temporarily re-enable the CTRL-AP ERASEALL functionality.

6.8.4 Usage

This section describes the specific KMU and UICR behavior in more detail, to help the reader get a better overview of KMU's features and the intended usage.

6.8.4.1 OTP

The OTP region of the UICR contains a user-defined static configuration of the device. The KMU emulates the OTP functionality by placing a write-once per halfword limitation of registers defined in this region, i.e. only halfwords containing all '1's can be written.

An OTP write transaction must consist of a full 32-bit word. Both halfwords can either be written simultaneously or one at a time. The KMU FSM will block any write to a halfword in the OTP region, if the initial value of this halfword is not 0xFFFF. When writing halfwords one at a time, the non-active halfword must be masked as 0xFFFF, otherwise the request will be blocked. For example, writing 0x1234XXXX to an OTP destination address which already contains the value 0xFFFFAABB, must be configured as 0x1234FFFF. The OTP destination address will contain the value 0x1234AABB after both write transactions have been processed.

The KMU will also only allow secure AHB write transactions into the OTP region of the UICR. Any AHB write transaction to this region that does not satisfy the above requirements will be ignored, and the STATUS.BLOCKED register will be set to '1'.

6.8.4.2 Key storage

The key storage region of the UICR can contain multiple keys of different type, including symmetrical keys, hashes, public/private key pairs and other device secrets. One of the key features of the KMU, is that these

device secrets can be installed and made available for use in cryptographic operations without revealing the actual secret values.

Keys in this region will typically have a certain life span. The region is not designed to be used for persession derived keys where the non-secure side (i.e. application) is participating in the key exchange.

All key storage is done through the concept of multiple key slots, where each key slot instance consists of one key header and an associated key value. Each key header supports the configuration of usage permissions and an optional secure destination address.

The key header secure destination address option enables the KMU to push the associated key value over a dedicated secure APB to a pre-configured secure location within the memory map. Such locations typically include a write-only key register of the hardware cryptograhic accelerator, allowing the KMU to distribute keys within the system without compromising the key values.

One key slot instance can store a key value of maximum 128 bits. If a key size exceeds this limit, the key value itself must be split over multiple key slot instances.

The following usage and read permissions scheme is applicable for each key slot:

Table 51: Valid key slot permission schemes

6.8.4.2.1 Selecting a key slot

The KMU FSM is designed to process only one key slot at a time, effectively operating as a memory protection unit for the key storage region. Whenever a key slot is selected, the KMU will allow access to writing, reading, and/or pushing the associated key value according to the selected slot configuration.

A key slot must be selected prior to use, by writing the key slot ID into the KMU SELECTKEYSLOT register. Because the reset value of this register is 0x00000000, there is no key slot associated with ID=0 and no slot is selected by default. All key slots are addressed using IDs from 1 to 128.

SELECTED status is set when a key slot is selected, and a read or write acccess to that keyslot occurs.

BLOCKED status is set when any illegal access to key slot registers is detected.

When the use of the particular key slot is stopped, the key slot selection in SELECTKEYSLOT must be set back to '0'.

By default, all KMU key slots will consist of a 128-bit key value of '1's, where the key headers have no secure destination address, or any usage and read restrictions.

6.8.4.2.2 Writing to a key slot

Writing a key slot into UICR is a five-step process.

- **1.** Select which key slot the KMU shall operate on by writing the desired key slot ID into KMU- >SELECTKEYSLOT. The selected key slot must be empty in order to add a new entry to UICR.
- **2.** If the key value shall be pushable over secure APB, the destination address of the recipient must be configured in register KEYSLOT.CONFIG[ID-1].DEST.

- **3.** Write the 128-bit key value into KEYSLOT.KEY[ID-1].VALUE[0-3].
- **4.** Write the desired key slot permissions into KEYSLOT.CONFIG[ID-1].PERM, including any applicable usage restrictions.
- **5.** Select key slot 0.

In case the total key size is greater than 128 bits, the key value itself must be split into 128-bit segments and written to multiple key slot instances. Steps 1 through 5 above must be repeated for the entire key size.

Note: If a key slot is configured as readable, and KEYSLOT.CONFIG[ID-1].DEST is not to be used, it is recommended to disable the push bit in KEYSLOT.CONFIG[ID-1].PERM when configuring key slot permissions.

Note: A key value distributed over multiple key slots should use the same key slot configuration in its key headers, but the secure destination address for each key slot instance must be incremented by 4 words (128 bits) for each key slot instance spanned.

Note: Write to flash must be enabled in NVMC->CONFIG prior to writing keys to flash, and subsequently disabled once writing is complete.

Steps 1 through 5 above will be blocked if any of the following violations are detected:

- No key slot selected
- Non-empty key slot selected
- NVM destination address not empty
- AHB write to KEYSLOT.KEY[ID-1].VALUE[0-3] registers not belonging to selected key slot

6.8.4.2.3 Reading a key value

Key slots that are configured as readable can have their key value read directly from the UICR memory map by the CPU.

Readable keys are typically used during the secure boot sequence, where the CPU is involved in falsifying or verifying the integrity of the system. Since the CPU is involved in this decision process, it makes little sense not to trust the CPU having access to the actual key value but ultimately trust the decision of the integrity check. Another use-case for readable keys is if the key type in question does not have a HW peripheral in the platform that is able to accept such keys over secure APB.

Reading a key value from the UICR is a three-step process:

- **1.** Select the key slot which the KMU shall operate on by writing the desired key slot ID into KMU- >SELECTKEYSLOT.
- **2.** If STATE and READ permission requirements are fulfilled as defined in KEYSLOT.CONFIG[ID-1].PERM, the key value can be read from region KEYSLOT.KEY[ID-1].VALUE[0-3] for selected key slot.
- **3.** Select key slot 0.

Step 2 will be blocked and word 0xDEADDEAD will be returned on AHB if any of the following violations are detected:

- No key slot selected
- Key slot not configured as readable
- Key slot is revoked
- AHB read to KEYSLOT.KEY[ID-1].VALUE[0-3] registers not belonging to selected key slot

6.8.4.2.4 Push over secure APB

Key slots that are configured as non-readable cannot be read by the CPU regardless of the mode the system is in, and must be pushed over secure APB in order to use the key value for cryptographic operations.

The secure APB destination address is set in the key slot configuration DEST register. Such destination addresses are typically write-only key registers in a hardware cryptographic accelerators memory map. The secure APB allows key slots to be utilized by the software side, without exposing the key value itself.

Figure 36: Tasks and events pattern for key slots

Pushing a key slot over secure APB is a four-step process:

- **1.** Select the key slot on which the KMU shall operate by writing the desired key slot ID into KMU- >SELECTKEYSLOT.
- 2. Start TASKS_PUSH_KEYSLOT to initiate a secure APB transaction, writing the 128-bit key value associated with the selected key slot into address defined in KEYSLOT.CONFIG[ID-1].DEST.
- **3.** After completing the secure APB transaction, the 128-bit key value is ready for use by the peripheral and EVENTS_KEYSLOT_PUSHED is triggered.
- **4.** Select key slot 0.

Note: If a key value is distributed over multiple key slots due to its key size, exceeding the maximum 128-bit key value limitation, then each distributed key slot must be pushed individually in order to transfer the entire key value over secure APB.

Step 3 will trigger other events than EVENTS_KEYSLOT_PUSHED if the following violations are detected:

- EVENTS_KEYSLOT_ERROR:
	- If no key slot is selected
	- If a key slot has no destination address configured
	- If when pushing a key slot, flash or peripheral returns an error
	- If pushing a key slot when push permissions are disabled

- If attempting to push a key slot with default permissions
- EVENTS KEYSLOT REVOKED if a key slot is marked as revoked in its key header configuration

6.8.4.2.5 Revoking the key slots

All key slots within the key storage area can be marked as revoked.

To revoke any key slots, write to the STATE field in the KEYSLOT.CONFIG[ID-1].PERM register. The following rules apply to keys that have been revoked:

- **1.** Key slots that have the PUSH field enabled in PERM register can no longer be pushed. If a revoked key slot is selected and task TASKS_PUSH_KEYSLOT is started, the event EVENTS_KEYSLOT_REVOKED is triggered.
- **2.** Key slots that have the READ field enabled in PERM register can no longer be read. Any read operation to a revoked key value will return word 0xDEADDEAD.
- **3.** Previously pushed key values stored in a peripheral write-only key register are not affected by key revocation. If secure code wants to enforce that a revoked key is no longer usable by a peripheral for cryptographic operations, the secure code should disable or reset the peripheral in question.

6.8.4.3 STATUS register

The KMU uses a STATUS register to indicate its status of operation. The SELECTED bit will be asserted whenever the currently selected key slot is successfully read from or written to.

All read or write operations to other key slots than what is currently selected in KMU->SELECTKEYSLOT will assert the BLOCKED bit. The BLOCKED bit will also be asserted if the KMU fails to select a key slot, or if a request has been blocked due to an access violation. Normal operation using the KMU should never trigger the BLOCKED bit. If this bit is triggered during the development phase, it indicates that the code is using the KMU incorrectly.

The STATUS register is reset every time register SELECTKEYSLOT is written.

6.8.5 Registers

Table 52: Instances

Table 53: Register overview

6.8.5.1 TASKS_PUSH_KEYSLOT

Address offset: 0x0000

Push a key slot over secure APB

6.8.5.2 EVENTS_KEYSLOT_PUSHED

Address offset: 0x100

Key slot successfully pushed over secure APB

6.8.5.3 EVENTS_KEYSLOT_REVOKED

Address offset: 0x104

Key slot has been revoked and cannot be tasked for selection

6.8.5.4 EVENTS_KEYSLOT_ERROR

Address offset: 0x108

No key slot selected, no destination address defined, or error during push operation

6.8.5.5 INTEN

Address offset: 0x300

Enable or disable interrupt

6.8.5.6 INTENSET

Address offset: 0x304

Enable interrupt

6.8.5.7 INTENCLR

Address offset: 0x308

Disable interrupt

6.8.5.8 INTPEND

Address offset: 0x30C

Pending interrupts

6.8.5.9 STATUS

Address offset: 0x40C

Status bits for KMU operation

This register is reset and re-written by the KMU whenever SELECTKEYSLOT is written

6.8.5.10 SELECTKEYSLOT

Address offset: 0x500

Select key slot to be read over AHB or pushed over secure APB when TASKS_PUSH_KEYSLOT is started

6.9 PDM — Pulse density modulation interface

The pulse density modulation (PDM) module enables input of pulse density modulated signals from external audio frontends, for example, digital microphones. The PDM module generates the PDM clock and supports single-channel or dual-channel (left and right) data input. Data is transferred directly to RAM buffers using EasyDMA.

Listed here are the main features for PDM:

- Up to two PDM microphones configured as a left/right pair using the same data input
- 16 kHz output sample rate, 16-bit samples
- EasyDMA support for sample buffering
- HW decimation filters
- Selectable ratio of 64 or 80 between PDM_CLK and output sample rate

The PDM module illustrated below is interfacing up to two digital microphones with the PDM interface. EasyDMA is implemented to relieve the real-time requirements associated with controlling of the PDM slave from a low priority CPU execution context. It also includes all the necessary digital filter elements to produce pulse code modulation (PCM) samples. The PDM module allows continuous audio streaming.

Figure 37: PDM module

6.9.1 Master clock generator

The master clock generator's PDMCLKCTRL register allows adjusting the PDM clock's frequency.

The master clock generator does not add any jitter to the HFCLK source chosen. It is recommended (but not mandatory) to use the Xtal as HFCLK source.

6.9.2 Module operation

By default, bits from the left PDM microphone are sampled on PDM_CLK falling edge, and bits for the right are sampled on the rising edge of PDM_CLK, resulting in two bitstreams. Each bitstream is fed into a digital filter which converts the PDM stream into 16-bit PCM samples, then filters and down-samples them to reach the appropriate sample rate.

The EDGE field in the MODE register allows swapping left and right, so that left will be sampled on rising edge, and right on falling.

The PDM module uses EasyDMA to store the samples coming out from the filters into one buffer in RAM. Depending on the mode chosen in the OPERATION field in the MODE register, memory either contains alternating left and right 16-bit samples (Stereo), or only left 16-bit samples (Mono). To ensure continuous PDM sampling, it is up to the application to update the EasyDMA destination address pointer as the previous buffer is filled.

The continuous transfer can be started or stopped by sending the START and STOP tasks. STOP becomes effective after the current frame has finished transferring, which will generate the STOPPED event. The STOPPED event indicates that all activity in the module is finished, and that the data is available in RAM (EasyDMA has finished transferring as well). Attempting to restart before receiving the STOPPED event may result in unpredictable behavior.

6.9.3 Decimation filter

In order to convert the incoming data stream into PCM audio samples, a decimation filter is included in the PDM interface module.

The input of the filter is the two-channel PDM serial stream (with left channel on clock high, right channel on clock low). Depending on the RATIO selected, its output is 2×16 -bit PCM samples at a sample rate either 64 times or 80 times (depending on the RATIO register) lower than the PDM clock rate.

The filter stage of each channel is followed by a digital volume control, to attenuate or amplify the output samples in a range of -20 dB to +20 dB around the default (reset) setting, defined by G_{PDM,default}. The gain is controlled by the GAINL and GAINR registers.

As an example, if the goal is to achieve 2500 RMS output samples (16-bit) with a 1 kHz 90 dBA signal into a -26 dBFS sensitivity PDM microphone, do the following:

- Sum the PDM module's default gain (G_{PDM,default}) and the gain introduced by the microphone and acoustic path of his implementation (an attenuation would translate into a negative gain)
- Adjust GAINL and GAINR by the above summed amount. Assuming that only the PDM module influences the gain, GAINL and GAINR must be set to -G_{PDM.default} dB to achieve the requirement.

With G_{PDM,default}=3.2 dB, and as GAINL and GAINR are expressed in 0.5 dB steps, the closest value to program would be 3.0 dB, which can be calculated as:

```
GAINL = GAINR = (Definition - (2 * 3))
```
Remember to check that the resulting values programmed into GAINL and GAINR fall within MinGain and MaxGain.

6.9.4 EasyDMA

Samples will be written directly to RAM, and EasyDMA must be configured accordingly.

The address pointer for the EasyDMA channel is set in SAMPLE.PTR register. If the destination address set in SAMPLE.PTR is not pointing to the Data RAM region, an EasyDMA transfer may result in a HardFault or RAM corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions.

DMA supports Stereo (Left+Right 16-bit samples) and Mono (Left only) data transfer, depending on the setting in the OPERATION field in the MODE register. The samples are stored little endian.

Table 54: DMA sample storage

The destination buffer in RAM consists of one block, the size of which is set in SAMPLE.MAXCNT register. Format is number of 16-bit samples. The physical RAM allocated is always:

```
(RAM allocation, in bytes) = SAMPLE. MAXCNT * 2;
```
(but the mapping of the samples depends on MODE.OPERATION.

If OPERATION=Stereo, RAM will contain a succession of left and right samples.

If OPERATION=Mono, RAM will contain a succession of left only samples.

For a given value of SAMPLE.MAXCNT, the buffer in RAM can contain half the stereo sampling time as compared to the mono sampling time.

The PDM acquisition can be started by the START task, after the SAMPLE.PTR and SAMPLE.MAXCNT registers have been written. When starting the module, it will take some time for the filters to start outputting valid data. Transients from the PDM microphone itself may also occur. The first few samples (typically around 50) might hence contain invalid values or transients. It is therefore advised to discard the first few samples after a PDM start.

As soon as the STARTED event is received, the firmware can write the next SAMPLE.PTR value (this register is double-buffered), to ensure continuous operation.

When the buffer in RAM is filled with samples, an END event is triggered. The firmware can start processing the data in the buffer. Meanwhile, the PDM module starts acquiring data into the new buffer pointed to by SAMPLE.PTR, and sends a new STARTED event, so that the firmware can update SAMPLE.PTR to the next buffer address.

6.9.5 Hardware example

PDM can be configured with a single microphone (mono), or with two microphones.

When a single microphone is used, connect the microphone clock to CLK, and data to DIN.

Figure 38: Example of a single PDM microphone, wired as left

Figure 39: Example of a single PDM microphone, wired as right

Note that in a single-microphone (mono) configuration, depending on the microphone's implementation, either the left or the right channel (sampled at falling or rising CLK edge respectively) will contain reliable data.

If two microphones are used, one of them has to be set as left, the other as right (L/R pin tied high or to GND on the respective microphone). It is strongly recommended to use two microphones of exactly the same brand and type so that their timings in left and right operation match.

Figure 40: Example of two PDM microphones

6.9.6 Pin configuration

The CLK and DIN signals associated to the PDM module are mapped to physical pins according to the configuration specified in the PSEL.CLK and PSEL.DIN registers respectively. If the CONNECT field in any PSEL register is set to Disconnected, the associated PDM module signal will not be connected to the required physical pins, and will not operate properly.

The PSEL.CLK and PSEL.DIN registers and their configurations are only used as long as the PDM module is enabled, and retained only as long as the device is in System ON mode. See [POWER — Power control](#page-63-0) on page 64 for more information about power modes. When the peripheral is disabled, the pins will behave as regular GPIOs, and use the configuration in their respective OUT bit field and PIN_CNF[n] register.

To ensure correct behavior in the PDM module, the pins used by the PDM module must be configured in the GPIO peripheral as described in [GPIO configuration before enabling peripheral](#page-151-0) on page 152 before enabling the PDM module. This is to ensure that the pins used by the PDM module are driven correctly if the PDM module itself is temporarily disabled or the device temporarily enters System OFF. This configuration must be retained in the GPIO for the selected I/Os as long as the PDM module is supposed to be connected to an external PDM circuit.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

Table 55: GPIO configuration before enabling peripheral

6.9.7 Registers

Table 56: Instances

Table 57: Register overview

6.9.7.1 TASKS_START

Address offset: 0x000

Starts continuous PDM transfer

6.9.7.2 TASKS_STOP

Address offset: 0x004

Stops PDM transfer

6.9.7.3 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-152-0)

6.9.7.4 SUBSCRIBE_STOP

Address offset: 0x084

Subscribe configuration for task [STOP](#page-152-1)

6.9.7.5 EVENTS_STARTED

Address offset: 0x100

PDM transfer has started

6.9.7.6 EVENTS_STOPPED

Address offset: 0x104

PDM transfer has finished

6.9.7.7 EVENTS_END

Address offset: 0x108

The PDM has written the last sample specified by SAMPLE.MAXCNT (or the last sample after a STOP task has been received) to Data RAM

6.9.7.8 PUBLISH_STARTED

Address offset: 0x180

Publish configuration for event [STARTED](#page-153-1)

6.9.7.9 PUBLISH_STOPPED

Address offset: 0x184

Publish configuration for event [STOPPED](#page-153-2)

6.9.7.10 PUBLISH_END

Address offset: 0x188

Publish configuration for event [END](#page-154-0)

6.9.7.11 INTEN

Address offset: 0x300

Enable or disable interrupt

6.9.7.12 INTENSET

Address offset: 0x304

Enable interrupt

6.9.7.13 INTENCLR

Address offset: 0x308

Disable interrupt

6.9.7.14 ENABLE

Address offset: 0x500

PDM module enable register

6.9.7.15 PDMCLKCTRL

Address offset: 0x504

PDM clock generator control

6.9.7.16 MODE

Address offset: 0x508

Defines the routing of the connected PDM microphones' signals

6.9.7.17 GAINL

Address offset: 0x518

Left output gain adjustment

6.9.7.18 GAINR

Address offset: 0x51C

Right output gain adjustment

6.9.7.19 RATIO

Address offset: 0x520

Selects the ratio between PDM_CLK and output sample rate. Change PDMCLKCTRL accordingly.

6.9.7.20 PSEL.CLK

Address offset: 0x540

Pin number configuration for PDM CLK signal

6.9.7.21 PSEL.DIN

Address offset: 0x544

Pin number configuration for PDM DIN signal

6.9.7.22 SAMPLE.PTR

Address offset: 0x560

RAM address pointer to write samples to with EasyDMA

6.9.7.23 SAMPLE.MAXCNT

Address offset: 0x564

Number of samples to allocate memory for in EasyDMA mode

6.9.8 Electrical specification

6.9.8.1 PDM Electrical Specification

Figure 41: PDM timing diagram

6.10 PWM — Pulse width modulation

The pulse with modulation (PWM) module enables the generation of pulse width modulated signals on GPIO. The module implements an up or up-and-down counter with four PWM channels that drive assigned GPIOs.

The following are the main features of a PWM module:

- Programmable PWM frequency
- Up to four PWM channels with individual polarity and duty cycle values
- Edge or center-aligned pulses across PWM channels
- Multiple duty cycle arrays (sequences) defined in RAM
- Autonomous and glitch-free update of duty cycle values directly from memory through EasyDMA (no CPU involvement)
- Change of polarity, duty cycle, and base frequency possibly on every PWM period
- RAM sequences can be repeated or connected into loops

Figure 42: PWM module

6.10.1 Wave counter

The wave counter is responsible for generating the pulses at a duty cycle that depends on the compare values, and at a frequency that depends on COUNTERTOP.

There is one common 15-bit counter with four compare channels. Thus, all four channels will share the same period (PWM frequency), but can have individual duty cycle and polarity. The polarity is set by a

value read from RAM (see figure [Decoder memory access modes](#page-164-0) on page 165). Whether the counter counts up, or up and down, is controlled by the MODE register.

The timer top value is controlled by the COUNTERTOP register. This register value, in conjunction with the selected PRESCALER of the PWM_CLK, will result in a given PWM period. A COUNTERTOP value smaller than the compare setting will result in a state where no PWM edges are generated. OUT[n] is held high, given that the polarity is set to FallingEdge. All compare registers are internal and can only be configured through decoder presented later. COUNTERTOP can be safely written at any time.

Sampling follows the START task. If DECODER.LOAD=WaveForm, the register value is ignored and taken from RAM instead (see section [Decoder with EasyDMA](#page-164-1) on page 165 for more details). If DECODER.LOAD is anything else than the WaveForm, it is sampled following a STARTSEQ[n] task and when loading a new value from RAM during a sequence playback.

The following figure shows the counter operating in up mode (MODE=PWM_MODE_Up), with three PWM channels with the same frequency but different duty cycle:

Figure 43: PWM counter in up mode example - FallingEdge polarity

The counter is automatically reset to zero when COUNTERTOP is reached and OUT[n] will invert. OUT[n] is held low if the compare value is 0 and held high if set to COUNTERTOP, given that the polarity is set to

FallingEdge. Counter running in up mode results in pulse widths that are edge-aligned. The following is the code for the counter in up mode example:

```
uint16 t pwm seq[4] = {PWM_CH0_DUTY, PWM_CH1_DUTY, PWM_CH2_DUTY, PWM_CH3_DUTY};
NRF_PWM0->PSEL.OUT[0] = (first pin << PWM_PSEL_OUT_PIN_Pos) |
                         (PWM_PSEL_OUT_CONNECT_Connected <<
                                                PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->PSEL.OUT[1] = (second_pin << PWM_PSEL_OUT_PIN_Pos) |
                       (PWM_PSEL_OUT_CONNECT_Connected <<
                                                PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->ENABLE = (PWM_ENABLE_ENABLE_Enabled << PWM_ENABLE_ENABLE_Pos);
NRF_PWM0->MODE = (PWM_MODE_UPDOWN_Up << PWM_MODE_UPDOWN_COS);
NRF_PWM0->PRESCALER = (PWM_PRESCALER_PRESCALER_DIV_1 <<
                                               PWM_PRESCALER_PRESCALER_Pos);
NRF_PWM0->COUNTERTOP = (16000 \ll PWMCOUNTERTOP_COUNTERTOP_Pos); //1 msec
NRF_PWM0->LOOP = (PWM_LOOP_CNT_Disabled << PWM_LOOP_CNT_Pos);
NRF_PWM0->DECODER = (PWM_DECODER_LOAD_Individual << PWM_DECODER_LOAD_Pos) | 
                     (PWM_DECODER_MODE_RefreshCount << PWM_DECODER_MODE_Pos);
NRF_PWM0->SEQ[0].PTR = ((uint32_t)(pwm_seq) << PWM_SEQ_PTR_PTR_Pos);
NRF_PWM0->SEQ[0].CNT = ((sizeof(pwm_seq) / sizeof(uint16_t)) <<
                                               PWM_SEQ_CNT_CNT_Pos);
NRF PWMO->SEQ[0].REFRESH = 0;
NRF PWMO->SEQ[0]. ENDDELAY = 0;
NRF_PWM0->TASKS_SEQSTART[0] = 1;
```
When the counter is running in up mode, the following formula can be used to compute the PWM period and the step size:

PWM period: $T_{\text{PWM (Up)}} = T_{\text{PWM CLK}} \star$ COUNTERTOP

Step width/Resolution: $T_{\text{steps}} = T_{\text{PWM CLK}}$

The following figure shows the counter operating in up-and-down mode (MODE=PWM_MODE_UpAndDown), with two PWM channels with the same frequency but different duty cycle and output polarity:

Figure 44: PWM counter in up-and-down mode example

The counter starts decrementing to zero when COUNTERTOP is reached and will invert the OUT[n] when compare value is hit for the second time. This results in a set of pulses that are center-aligned. The following is the code for the counter in up-and-down mode example:

```
uint16 t pwm seq[4] = {PWM_CHO_DUTY, PWM_CH1_DUTY, PWM_CH2_DUTY, PWM_CH3_DUTY};
NRF_PWM0->PSEL.OUT[0] = (first pin << PWM_PSEL_OUT_PIN_Pos) |
                         (PWM_PSEL_OUT_CONNECT_Connected <<
                                                PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->PSEL.OUT[1] = (second_pin << PWM_PSEL_OUT_PIN_Pos) | 
                         (PWM_PSEL_OUT_CONNECT_Connected <<
                                                PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->ENABLE = (PWM_ENABLE_ENABLE_Enabled << PWM_ENABLE_ENABLE_Pos);
NRF_PWM0->MODE = (PWM_MODE_UPDOWN_UpAndDown << PWM_MODE_UPDOWN_Pos);
NRF_PWM0->PRESCALER = (PWM_PRESCALER_PRESCALER_DIV_1 <<
                                                PWM_PRESCALER_PRESCALER_Pos);
NRF_PWM0->COUNTERTOP = (16000 \ll PWW COUNTERTOP_COUNTERTOP_Pos); //1 msec
NRF_PWM0->LOOP = (PWM_LOOP_CNT_Disabled << PWM_LOOP_CNT_Pos);
NRF_PWM0->DECODER = (PWM_DECODER_LOAD_Individual << PWM_DECODER_LOAD_Pos) | 
                      (PWM_DECODER_MODE_RefreshCount << PWM_DECODER_MODE_Pos);
NRF_PWM0->SEQ[0].PTR = ((uint32 t)(pwm_seq) << PWM_SEQ_PTR_PTR_Pos);
NRF_PWM0->SEQ[0].CNT = ((sizeof(pwm_seq) / sizeof(uint16_t)) <<
                                                PWM_SEQ_CNT_CNT_Pos);
NRF_PWM0->SEQ[0].REFRESH = 0;NRF PWMO->SEO[0]. ENDDELAY = 0;
NRF_PWM0->TASKS_SEQSTART[0] = 1;
```
When the counter is running in up-and-down mode, the following formula can be used to compute the PWM period and the step size:

 $T_{\text{PWM}}(U_{\text{P}}$ and Down) = T_{PWM} CLK * 2 * COUNTERTOP Step width/Resolution: $T_{\text{steps}} = T_{\text{PWM CLK}} \star 2$

6.10.2 Decoder with EasyDMA

The decoder uses EasyDMA to take PWM parameters stored in RAM and update the internal compare registers of the wave counter, based on the mode of operation.

PWM parameters are organized into a sequence containing at least one half word (16 bit). Its most significant bit[15] denotes the polarity of the OUT[n] while bit[14:0] is the 15-bit compare value.

The DECODER register controls how the RAM content is interpreted and loaded into the internal compare registers. The LOAD field controls if the RAM values are loaded to all compare channels, or to update a group or all channels with individual values. The following figure illustrates how parameters stored in RAM are organized and routed to various compare channels in different modes:

Figure 45: Decoder memory access modes

A special mode of operation is available when DECODER.LOAD is set to WaveForm. In this mode, up to three PWM channels can be enabled - OUT[0] to OUT[2]. In RAM, four values are loaded at a time: the first, second and third location are used to load the values, and the fourth RAM location is used to load the COUNTERTOP register. This way one can have up to three PWM channels with a frequency base that changes on a per PWM period basis. This mode of operation is useful for arbitrary wave form generation in applications, such as LED lighting.

The register SEQ[n].REFRESH=N (one per sequence n=0 or 1) will instruct a new RAM stored pulse width value on every $(N+1)^{th}$ PWM period. Setting the register to zero will result in a new duty cycle update every PWM period, as long as the minimum PWM period is observed.

Note that registers SEQ[n].REFRESH and SEQ[n].ENDDELAY are ignored when DECODER.MODE=NextStep. The next value is loaded upon every received NEXTSTEP task.

SEQ[n].PTR is the pointer used to fetch COMPARE values from RAM. If the SEQ[n].PTR is not pointing to a RAM region, an EasyDMA transfer may result in a HardFault or RAM corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions. After the SEQ[n].PTR is set to the desired RAM location, the SEQ[n].CNT register must be set to the number of 16-bit half words in the sequence. It is important to observe that the Grouped mode requires one half word per group, while the Single mode requires one half word per channel, thus increasing the RAM size occupation. If PWM generation is not running when the SEQSTART[n] task is triggered, the task will load the first value from RAM and then start the PWM generation. A SEQSTARTED[n] event is generated as soon as the EasyDMA has read the first PWM parameter from RAM and the wave counter has started executing it. When LOOP.CNT=0, sequence n=0 or 1 is played back once. After the last value in the sequence has been loaded and started executing, a SEQEND[n] event is generated. The PWM generation will then continue with the last loaded value. The following figure illustrates an example of a simple playback.

Figure 46: Simple sequence example

The following source code is used for configuration and timing details in a sequence where only sequence 0 is used and only run once with a new PWM duty cycle for each period.

```
NRF_PWM0->PSEL.OUT[0] = (first pin << PWM_PSEL_OUT_PIN_Pos) |
                        (PWM_PSEL_OUT_CONNECT_Connected <<
                                               PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->ENABLE = (PWM_ENABLE_ENABLE_ENABLE_ENABLE_ENABLE_Pos);
NRF PWM0->MODE = (PWM_MODE_UPDOWN_Up << PWM_MODE_UPDOWN_Pos);
NRF_PWM0->PRESCALER = (PWM_PRESCALER_PRESCALER_DIV_1 <<
                                               PWM_PRESCALER_PRESCALER_Pos);
NRF_PWM0->COUNTERTOP = (16000 \llPWM_COUNTERTOP_COUNTERTOP_Pos); //1 msec
NRF_PWM0->LOOP = (PWM_LOOP_CNT_Disabled << PWM_LOOP_CNT_Pos);
NRF_PWM0->DECODER = (PWM_DECODER_LOAD_Common << PWM_DECODER_LOAD_Pos) | 
                     (PWM_DECODER_MODE_RefreshCount << PWM_DECODER_MODE_Pos);
NRF_PWM0->SEQ[0].PTR = ((uint32 t)(seq0 ram) << PWM SEQ PTR PTS);NRF_PWM0->SEQ[0].CNT = ((sizeof(seq0_ram) / sizeof(uint16_t)) <<
                                                PWM_SEQ_CNT_CNT_Pos);
NRF_PWM0->SEQ[0].REFRESH = 0;
NRF PWM0->SEQ[0] .ENDDELAY = 0;NRF_PWM0->TASKS_SEQSTART[0] = 1;
```
To completely stop the PWM generation and force the associated pins to a defined state, a STOP task can be triggered at any time. A STOPPED event is generated when the PWM generation has stopped at the end of the currently running PWM period, and the pins go into their idle state as defined in GPIO OUT register.

PWM generation can then only be restarted through a SEQSTART[n] task. SEQSTART[n] will resume PWM generation after having loaded the first value from the RAM buffer defined in the SEQ[n].PTR register.

The following table indicates when specific registers get sampled by the hardware. Care should be taken when updating these registers to avoid that values are applied earlier than expected.

Table 58: When to safely update PWM registers

Note: SEQ[n].REFRESH and SEQ[n].ENDDELAY are ignored at the end of a complex sequence, indicated by a LOOPSDONE event. The reason for this is that the last value loaded from RAM is maintained until further action from software (restarting a new sequence, or stopping PWM generation).

The following figure shows a more complex example using the register [LOOP](#page-181-0) on page 182.

Figure 47: Example using two sequences

In this case, an automated playback takes place, consisting of SEQ[0], delay 0, SEQ[1], delay 1, then again SEQ[0], etc. The user can choose to start a complex playback with SEQ[0] or SEQ[1] through sending the SEQSTART[0] or SEQSTART[1] task. The complex playback always ends with delay 1.

The two sequences 0 and 1 are defined by the addresses of value tables in RAM (pointed to by SEQ[n].PTR) and the buffer size (SEQ[n].CNT). The rate at which a new value is loaded is defined individually for each sequence by SEQ[n].REFRESH. The chaining of sequence 1 following the sequence 0 is implicit, the LOOP.CNT register allows the chaining of sequence 1 to sequence 0 for a determined number of times. In other words, it allows to repeat a complex sequence a number of times in a fully automated way.

In the following code example, sequence 0 is defined with SEQ[0].REFRESH set to 1, meaning that a new PWM duty cycle is pushed every second PWM period. This complex sequence is started with the SEQSTART[0] task, so SEQ[0] is played first. Since SEQ[0].ENDDELAY=1 there will be one PWM period delay between last period on sequence 0 and the first period on sequence 1. Since SEQ[1]. ENDDELAY=0 there is no delay 1, so SEQ[0] would be started immediately after the end of SEQ[1]. However, as LOOP.CNT is

1, the playback stops after having played SEQ[1] only once, and both SEQEND[1] and LOOPSDONE are generated (their order is not guaranteed in this case).

```
NRF_PWM0->PSEL.OUT[0] = (first pin << PWM_PSEL_OUT_PIN_Pos) |
                        (PWM_PSEL_OUT_CONNECT_Connected <<
                                               PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->ENABLE = (PWM_ENABLE_ENABLE_Enabled << PWM_ENABLE_ENABLE_Pos);
NRF\_PWM0->MODE = (PWM_MODE\_UPDOWN\_Up \ll PWM_MODE\_UPDOWN\_Pos);
NRF_PWM0->PRESCALER = (PWM_PRESCALER_PRESCALER_DIV_1 <<
                                                PWM_PRESCALER_PRESCALER_Pos);
NRF_PWM0->COUNTERTOP = (16000 << PWM_COUNTERTOP_COUNTERTOP_Pos); //1 msec
NRF_PWM0->LOOP = (1 \leq x \leq 1) = (1 \leq x \leq 1)NRF_PWM0->DECODER = (PWM_DECODER_LOAD_Common << PWM_DECODER_LOAD_Pos) |
                     (PWM_DECODER_MODE_RefreshCount << PWM_DECODER_MODE_Pos);
NRF_PWM0->SEQ[0].PTR = ((uint32 t)(seq0_ram) << PWM_SEQ_PTR_PTR_Pos);
NRF_PWM0->SEQ[0].CNT = ((size of(seq0ram) / size of(uint16 t)) \llPWM_SEQ_CNT_CNT_Pos);
NRF_PWM0->SEQ[0].REFRESH = 1;NRF_PWM0->SEQ[0].ENDDELAY = 1;
NRF_PWM0->SEQ[1].PTR = ((uint32 t)(seq1_ram) << PWM_SEQ_PTR_PTR_Pos);
NRF PWM0->SEQ[1].CNT = ((sizeof(seq1 ram) / sizeof(uint16 t)) <<
                                               PWM_SEQ_CNT_CNT_Pos);
NRF_PWM0->SEQ[1].REFRESH = 0;
NRF PWMO->SEQ[1]. ENDDELAY = 0;
NRF_PWM0->TASKS_SEQSTART[0] = 1;
```
The decoder can also be configured to asynchronously load new PWM duty cycle. If the DECODER.MODE register is set to NextStep, then the NEXTSTEP task will cause an update of internal compare registers on the next PWM period.

The following figures provide an overview of each part of an arbitrary sequence, in various modes (LOOP.CNT=0 and LOOP.CNT>0). In particular, the following are represented:

- Initial and final duty cycle on the PWM output(s)
- Chaining of SEQ[0] and SEQ[1] if LOOP.CNT>0
- Influence of registers on the sequence
- Events generated during a sequence
- DMA activity (loading of next value and applying it to the output(s))

Peripherals

Figure 48: Single shot (LOOP.CNT=0)

Figure 49: Complex sequence (LOOP.CNT>0) starting with SEQ[0]

Figure 50: Complex sequence (LOOP.CNT>0) starting with SEQ[1]

Note: If a sequence is in use in a simple or complex sequence, it must have a length of SEQ[n].CNT $> 0.$

This example shows how the PWM module can be configured to repeat a single sequence until stopped.

```
NRF_PWM0->PSEL.OUT[0] = (first pin << PWM_PSEL_OUT_PIN_Pos) |
                         (PWM_PSEL_OUT_CONNECT_Connected <<
                                                PWM_PSEL_OUT_CONNECT_Pos);
NRF_PWM0->ENABLE = (PWM_ENABLE_ENABLE_Enabled << PWM_ENABLE_ENABLE_Pos);
NRF_PWM0->MODE = (PWM_MODE_UPDOWN_Up << PWM_MODE_UPDOWN_Pos);
NRF_PWM0->PRESCALER = (PWM_PRESCALER_PRESCALER_DIV_1 <<
                                                PWM_PRESCALER_PRESCALER_Pos);
NRF_PWM0->COUNTERTOP = (16000 \ll PWMCOUNTERTOP_COUNTERTOP_Pos); //1 msec
// Enable the shortcut from LOOPSDONE event to SEQSTART1 task for infinite loop
NRF_PWM0->SHORTS = (PWM_SHORTS_LOOPSDONE_SEQSTART1_Enabled <<
                                         PWM_SHORTS_LOOPSDONE_SEQSTART1_Pos);
// LOOP_CNT must be greater than 0 for the LOOPSDONE event to trigger and enable looping
NRF\_PWM0->LOOP = (1 << PWM\_LOOP_CNT_Pos);
NRF_PWM0->DECODER = (PWM_DECODER_LOAD_Common << PWM_DECODER_LOAD_Pos) |
                     (PWM_DECODER_MODE_RefreshCount << PWM_DECODER_MODE_Pos);
// To repeat a single sequence until stopped, it must be configured in SEQ[1]
NRF PWM0->SEQ[1].PTR = ((uint32_t)(seq0_ram) << PWM_SEQ_PTR_PTR_Pos);
NRF_PWM0->SEQ[1].CNT = ((sizeof(seq0_ram) / sizeof(uint16_t)) <<
                                                PWM_SEQ_CNT_CNT_Pos);
NRF_PWM0->SEQ[1].REFRESH = 0;NRF_PWM0->SEQ[1].ENDDELAY = 0;
NRF_PWM0->TASKS_SEQSTART[1] = 1;
```


6.10.3 Limitations

The previous compare value is repeated if the PWM period is shorter than the time it takes for the EasyDMA to retrieve from RAM and update the internal compare registers. This is to ensure a glitch-free operation even for very short PWM periods.

Only SEQ[1] can trigger the [LOOPSDONE](#page-175-0) event upon completion, not SEQ[0]. This requires looping to be enabled [\(LOOP](#page-181-0) > 0) and [SEQ\[1\].CNT](#page-181-1) > 0 when sequence playback starts.

6.10.4 Pin configuration

The OUT[n] (n=0..3) signals associated with each PWM channel are mapped to physical pins according to the configuration of PSEL.OUT[n] registers. If PSEL.OUT[n].CONNECT is set to Disconnected, the associated PWM module signal will not be connected to any physical pins.

The PSEL.OUT[n] registers and their configurations are used as long as the PWM module is enabled and the PWM generation active (wave counter started). They are retained only as long as the device is in System ON mode (see the [POWER](#page-63-0) section for more information about power modes).

To ensure correct behavior in the PWM module, the pins that are used must be configured in the GPIO peripheral in the following way before the PWM module is enabled:

Table 59: Recommended GPIO configuration before starting PWM generation

The idle state of a pin is defined by the OUT register in the GPIO module, to ensure that the pins used by the PWM module are driven correctly. If PWM generation is stopped by triggering a STOP task, the PWM module itself is temporarily disabled or the device temporarily enters System OFF. This configuration must be retained in the GPIO for the selected pins (I/Os) for as long as the PWM module is supposed to be connected to an external PWM circuit.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

6.10.5 Registers

Table 60: Instances

Table 61: Register overview

6.10.5.1 TASKS_STOP

Address offset: 0x004

Stops PWM pulse generation on all channels at the end of current PWM period, and stops sequence playback

6.10.5.2 TASKS_SEQSTART[n] (n=0..1)

Address offset: 0x008 + (n × 0x4)

Loads the first PWM value on all enabled channels from sequence n, and starts playing that sequence at the rate defined in SEQ[n]REFRESH and/or DECODER.MODE. Causes PWM generation to start if not running.

6.10.5.3 TASKS_NEXTSTEP

Address offset: 0x010

Steps by one value in the current sequence on all enabled channels if DECODER.MODE=NextStep. Does not cause PWM generation to start if not running.

6.10.5.4 SUBSCRIBE_STOP

Address offset: 0x084

Subscribe configuration for task [STOP](#page-172-0)

6.10.5.5 SUBSCRIBE_SEQSTART[n] (n=0..1)

Address offset: 0x088 + (n × 0x4)

Subscribe configuration for task [SEQSTART\[n\]](#page-173-0)

6.10.5.6 SUBSCRIBE_NEXTSTEP

Address offset: 0x090

Subscribe configuration for task [NEXTSTEP](#page-173-1)

6.10.5.7 EVENTS_STOPPED

Address offset: 0x104

Response to STOP task, emitted when PWM pulses are no longer generated

6.10.5.8 EVENTS_SEQSTARTED[n] (n=0..1)

Address offset: 0x108 + (n × 0x4)

First PWM period started on sequence n

6.10.5.9 EVENTS_SEQEND[n] (n=0..1)

Address offset: 0x110 + (n × 0x4)

Emitted at end of every sequence n, when last value from RAM has been applied to wave counter

6.10.5.10 EVENTS_PWMPERIODEND

Address offset: 0x118

Emitted at the end of each PWM period

6.10.5.11 EVENTS_LOOPSDONE

Address offset: 0x11C

Concatenated sequences have been played the amount of times defined in LOOP.CNT

This event triggers after the last SEQ[1] completion of the loop, and only if looping was enabled (LOOP > 0) when the sequence playback was started.

6.10.5.12 PUBLISH_STOPPED

Address offset: 0x184

Publish configuration for event [STOPPED](#page-174-1)

6.10.5.13 PUBLISH_SEQSTARTED[n] (n=0..1)

Address offset: 0x188 + (n × 0x4)

Publish configuration for event [SEQSTARTED\[n\]](#page-174-2)

6.10.5.14 PUBLISH_SEQEND[n] (n=0..1)

Address offset: 0x190 + (n × 0x4)

Publish configuration for event [SEQEND\[n\]](#page-175-1)

6.10.5.15 PUBLISH_PWMPERIODEND

Address offset: 0x198

Publish configuration for event [PWMPERIODEND](#page-175-2)

6.10.5.16 PUBLISH_LOOPSDONE

Address offset: 0x19C

Publish configuration for event [LOOPSDONE](#page-175-0)

This event triggers after the last SEQ[1] completion of the loop, and only if looping was enabled (LOOP > 0) when the sequence playback was started.

6.10.5.17 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.10.5.18 INTEN

Address offset: 0x300

Enable or disable interrupt

6.10.5.19 INTENSET

Address offset: 0x304

Enable interrupt

6.10.5.20 INTENCLR

Address offset: 0x308

Disable interrupt

6.10.5.21 ENABLE

Address offset: 0x500

PWM module enable register

6.10.5.22 MODE

Address offset: 0x504

Selects operating mode of the wave counter

6.10.5.23 COUNTERTOP

Address offset: 0x508

Value up to which the pulse generator counter counts

6.10.5.24 PRESCALER

Address offset: 0x50C

Configuration for PWM_CLK

6.10.5.25 DECODER

Address offset: 0x510

Configuration of the decoder

6.10.5.26 LOOP

Address offset: 0x514

Number of playbacks of a loop

6.10.5.27 SEQ[n].PTR (n=0..1)

Address offset: 0x520 + (n × 0x20)

Beginning address in RAM of this sequence

Note: See the memory chapter for details about which memories are available for EasyDMA.

6.10.5.28 SEQ[n].CNT (n=0..1)

Address offset: $0x524 + (n \times 0x20)$

Number of values (duty cycles) in this sequence

6.10.5.29 SEQ[n].REFRESH (n=0..1)

Address offset: 0x528 + (n × 0x20)

Number of additional PWM periods between samples loaded into compare register

6.10.5.30 SEQ[n].ENDDELAY (n=0..1)

Address offset: 0x52C + (n × 0x20)

Time added after the sequence

6.10.5.31 PSEL.OUT[n] (n=0..3)

Address offset: 0x560 + (n × 0x4)

Output pin select for PWM channel n

6.11 RTC — Real-time counter

The real-time counter (RTC) module provides a generic, low-power timer on the low frequency clock source (LFCLK).

Figure 51: RTC block diagram

The RTC module features a 24-bit COUNTER, a 12-bit (1/X) prescaler, compare registers, and a tick event generator.

6.11.1 Clock source

The RTC will run off the LFCLK.

When started, the RTC will automatically request the LFCLK source with RC oscillator if the LFCLK is not already running.

See [CLOCK — Clock control](#page-69-0) on page 70 for more information about clock sources.

6.11.2 Resolution versus overflow and the prescaler

The relationship between the prescaler, counter resolution, and overflow is summarized in the following table.

Table 62: RTC resolution versus overflow

The counter increment frequency is given by the following equation:

 f_{RTC} [kHz] = 32.768 / (PRESCALER + 1)

The [PRESCALER](#page-196-0) register can only be written when the RTC is stopped.

The prescaler is restarted on tasks [START,](#page-190-0) [CLEAR](#page-191-0) and [TRIGOVRFLW.](#page-191-1) That is, the prescaler value is latched to an internal register (<<PRESC>>) on these tasks.

Examples:

1. Desired COUNTER frequency 100 Hz (10 ms counter period)

PRESCALER = round(32.768 kHz / 100 Hz) - 1 = 327

 f_{RTC} = 99.9 Hz

10009.576 μs counter period

2. Desired COUNTER frequency 8 Hz (125 ms counter period)

PRESCALER = round(32.768 kHz / 8 Hz) – 1 = 4095

 $f_{\text{RTC}} = 8$ Hz

125 ms counter period

6.11.3 Counter register

The internal <<COUNTER>> register increments on LFCLK when the internal [PRESCALER](#page-196-0) register (<<PRESC>>) is 0x00. <<PRESC>> is reloaded from the [PRESCALER](#page-196-0) register. If enabled, the [TICK](#page-192-0) event occurs on each increment of the [COUNTER](#page-196-1).

Figure 53: Timing diagram - COUNTER_PRESCALER_1

6.11.3.1 Reading the counter register

To read the COUNTER register, the internal <<COUNTER>> value is sampled.

To ensure that the <<COUNTER>> is safely sampled (considering that an LFCLK transition may occur during a read), the CPU and core memory bus are halted for PCLK16M cycles. In addition, the read takes the CPU two PCLK16M cycles, resulting in the COUNTER register read taking maximum six PCLK16M clock cycles.

6.11.4 Overflow

An [OVRFLW](#page-192-1) event is generated on [COUNTER](#page-196-1) register overflow (overflowing from 0xFFFFFF to 0).

The [TRIGOVRFLW](#page-191-1) task will set the [COUNTER](#page-196-1) value to 0xFFFFF0, to allow software test of the overflow condition.

Note: The [OVRFLW](#page-192-1) event is disabled by default.

6.11.5 Tick event

The [TICK](#page-192-0) event enables low-power tickless RTOS implementation, as it optionally provides a regular interrupt source for an RTOS with no need for use of the ARM SysTick feature.

Using the [TICK](#page-192-0) event, rather than the SysTick, allows the CPU to be powered down while keeping RTOS scheduling active.

Note: The [TICK](#page-192-0) event is disabled by default.

6.11.6 Event control

To optimize the RTC power consumption, events in the RTC can be individually disabled to prevent PCLK16M and HFCLK from being requested when those events are triggered. This is managed using the [EVTEN](#page-195-0) register.

This means that the RTC implements a slightly different task and event system compared to the standard system described in [Peripheral interface](#page-14-0) on page 15. The RTC task and event system is illustrated in the following figure.

Figure 54: Tasks, events, and interrupts in the RTC

6.11.7 Compare

The RTC implements one [COMPARE](#page-193-0) event for every available compare register.

When the [COUNTER](#page-196-1) is incremented and then becomes equal to the value specified in the register [CC\[n\],](#page-196-2) the corresponding compare event [COMPARE\[n\]](#page-193-0) is generated.

When writing a [CC\[n\]](#page-196-2) register, the [RTC COMPARE](#page-193-0) event exhibits several behaviors. See the following figures for more information.

If a [CC](#page-196-2) value is 0 when a [CLEAR](#page-191-0) task is set, this will not trigger a [COMPARE](#page-193-0) event.

If a [CC](#page-196-2) value is N and the [COUNTER](#page-196-1) value is N when the [START](#page-190-0) task is set, this will not trigger a [COMPARE](#page-193-0) event.

Figure 56: Timing diagram - COMPARE_START

A [COMPARE](#page-193-0) event occurs when a [CC](#page-196-2) value is N, and the [COUNTER](#page-196-1) value transitions from N-1 to N.

If the [COUNTER](#page-196-1) value is N, writing N+2 to a [CC](#page-196-2) register is guaranteed to trigger a [COMPARE](#page-193-0) event at N+2.

Figure 58: Timing diagram - COMPARE_N+2

If the [COUNTER](#page-196-1) value is N, writing N or N+1 to a [CC](#page-196-2) register may not trigger a [COMPARE](#page-193-0) event.

Figure 59: Timing diagram - COMPARE_N+1

If the [COUNTER](#page-196-1) value is N, and the current [CC](#page-196-2) value is N+1 or N+2 when a new CC value is written, a match may trigger on the previous CC value before the new value takes effect. If the current CC value is greater than N+2 when the new value is written, there will be no event due to the old value.

Figure 60: Timing diagram - COMPARE_N-1

6.11.8 Task and event jitter/delay

Jitter or delay in the RTC, is due to the peripheral clock being a low frequency clock (LFCLK), which is not synchronous to the faster PCLK16M.

Registers in the peripheral interface that are part of the PCLK16M domain, have a set of mirrored registers in the LFCLK domain. For example, the [COUNTER](#page-196-1) value accessible from the CPU is in the PCLK16M domain, and is latched on a read from an internal COUNTER register in the LFCLK domain. The [COUNTER](#page-196-1) register

is modified each time the RTC ticks. The registers are synchronised between the two clock domains (PCLK16M and LFCLK).

[CLEAR](#page-191-0) and [STOP](#page-190-1) (and [TRIGOVRFLW](#page-191-1), which is not shown) will be delayed as long as it takes for the peripheral to clock a falling edge and a rising edge of the LFCLK. This is between 15.2585 μs and 45.7755 μs – rounded to 15 μs and 46 μs for the remainder of the section.

Figure 61: Timing diagram - DELAY_CLEAR

When a [STOP](#page-190-1) task is triggered, the PCLK16M domain will immediately prevent the generation of any EVENTS from the RTC. However, as seen in the following figure, the [COUNTER](#page-196-1) value can still increment one final time.

Figure 62: Timing diagram - DELAY_STOP

The [START](#page-190-0) task will start the RTC. Assuming that the LFCLK was previously running and stable, the first increment of [COUNTER](#page-196-1) (and instance of TICK event) will be typically after 30.5 μs +/-15 μs. Additional delay will occur if the RTC is started before the LFCLK is running, see CLOCK $-$ Clock control on page 70 for LFLK startup times. The software should therefore wait for the first TICK if it has to make sure that the RTC is running. Sending a TRIGOVRFLW task sets the [COUNTER](#page-196-1) to a value close to overflow. However, since the update of [COUNTER](#page-196-1) relies on a stable LFCLK, sending this task while LFCLK is not running will also add additional delay as previously described. The figures show the smallest and largest delays on the [START](#page-190-0) task, appearing as a +/-15 μs jitter on the first [COUNTER](#page-196-1) increment.

Figure 63: Timing diagram - JITTER_START-

Figure 64: Timing diagram - JITTER_START+

The following tables summarize jitter introduced for tasks and events. Any 32.768 kHz clock jitter will come in addition to these numbers.

Table 63: RTC jitter magnitudes on tasks

Table 64: RTC jitter magnitudes on events

6.11.9 Registers

Table 65: Instances

¹² Assumes RTC runs continuously between these events.

Table 66: Register overview

6.11.9.1 TASKS_START

Address offset: 0x000

Start RTC counter

6.11.9.2 TASKS_STOP

Address offset: 0x004

Stop RTC counter

6.11.9.3 TASKS_CLEAR

Address offset: 0x008

Clear RTC counter

6.11.9.4 TASKS_TRIGOVRFLW

Address offset: 0x00C

Set counter to 0xFFFFF0

6.11.9.5 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-190-0)

6.11.9.6 SUBSCRIBE_STOP

Address offset: 0x084

Subscribe configuration for task [STOP](#page-190-1)

6.11.9.7 SUBSCRIBE_CLEAR

Address offset: 0x088

Subscribe configuration for task [CLEAR](#page-191-0)

6.11.9.8 SUBSCRIBE_TRIGOVRFLW

Address offset: 0x08C

Subscribe configuration for task [TRIGOVRFLW](#page-191-1)

6.11.9.9 EVENTS_TICK

Address offset: 0x100

Event on counter increment

6.11.9.10 EVENTS_OVRFLW

Address offset: 0x104

Event on counter overflow

6.11.9.11 EVENTS_COMPARE[n] (n=0..3)

Address offset: 0x140 + (n × 0x4)

Compare event on CC[n] match

6.11.9.12 PUBLISH_TICK

Address offset: 0x180

Publish configuration for event [TICK](#page-192-0)

6.11.9.13 PUBLISH_OVRFLW

Address offset: 0x184

Publish configuration for event [OVRFLW](#page-192-1)

6.11.9.14 PUBLISH_COMPARE[n] (n=0..3)

Address offset: 0x1C0 + (n × 0x4)

Publish configuration for event [COMPARE\[n\]](#page-193-0)

6.11.9.15 INTENSET

Address offset: 0x304

Enable interrupt

6.11.9.16 INTENCLR

Address offset: 0x308

Disable interrupt

6.11.9.17 EVTEN

Address offset: 0x340

Enable or disable event routing

6.11.9.18 EVTENSET

Address offset: 0x344

Enable event routing

6.11.9.19 EVTENCLR

Address offset: 0x348

Disable event routing

6.11.9.20 COUNTER

Address offset: 0x504

Current counter value

6.11.9.21 PRESCALER

Address offset: 0x508

12-bit prescaler for counter frequency (32768/(PRESCALER+1)). Must be written when RTC is stopped.

6.11.9.22 CC[n] (n=0..3)

Address offset: 0x540 + (n × 0x4)

Compare register n

6.11.10 Electrical specification

6.12 SAADC — Successive approximation analog-todigital converter

The SAADC is a differential successive approximation register (SAR) analog-to-digital converter.

Listed here are the main features of SAADC:

- 8/10/12-bit resolution, 14-bit resolution with oversampling
- Multiple analog inputs:
	- AIN0 to AIN7 pins
	- VDD_GPIO pin
- Up to eight input channels:
	- One channel per single-ended input and two channels per differential input
	- Scan mode can be configured with both single-ended channels and differential channels
	- Each channel can be configured to select any of the above analog inputs
- Full scale input range (0 to VDD_GPIO)
- Sampling triggered via a task from software or a PPI channel for full flexibility on sample frequency source from low-power 32.768 kHz RTC or more accurate 1/16 MHz timers
- One-shot conversion mode to sample a single channel
- Scan mode to sample a series of channels in sequence with configurable sample delay
- Support for direct sample transfer to RAM using EasyDMA
- Interrupts on single sample and full buffer events
- Samples stored as 16-bit two's complement values for differential and single-ended sampling
- Continuous sampling without the need of an external timer
- Internal resistor string
- On-the-fly limit checking

6.12.1 Overview

The ADC supports up to eight external analog input channels. It can be operated in One-shot mode with sampling under software control, or Continuous mode with a programmable sampling rate.

The analog inputs can be configured as eight single-ended inputs, four differential inputs or a combination of these. Each channel can be configured to select:

- AIN0 to AIN7 pins
- VDD_GPIO pin

Channels can be sampled individually in one-shot or continuous sampling modes, or, using scan mode, multiple channels can be sampled in sequence. Channels can also be oversampled to improve noise performance.

Figure 65: Simplified ADC block diagram

Internally, the ADC is always a differential analog-to-digital converter, but by default it is configured with single-ended input in the MODE field of the CH[n].CONFIG register. In single-ended mode, the negative input will be shorted to ground internally.

The assumption in single-ended mode is that the internal ground of the ADC is the same as the external ground that the measured voltage is referred to. The ADC is thus sensitive to ground bounce on the PCB in single-ended mode. If this is a concern we recommend using differential measurement.

6.12.2 Digital output

The output result of the ADC depends on the settings in the CH[n].CONFIG and RESOLUTION registers as follows:

RESULT = $[V(P) - V(N)] * GAIN/REFERENCE * 2^{(RESOLUTION - m)}$

is the selected reference voltage

where **V(P)** is the voltage at input P **V(N)** is the voltage at input N **GAIN** is the selected gain setting **m** is the mode setting. Use m=0 if CONFIG.MODE=SE, or m=1 if CONFIG.MODE=Diff **REFERENCE**

The result generated by the ADC will deviate from the expected due DC errors like offset, gain, differential non-linearity (DNL), and integral non-linearity (INL). See [Electrical specification](#page-222-0) for details on these parameters. The result can also vary due to AC errors like non-linearities in the GAIN block, settling errors

due to high source impedance and sampling jitter. For battery measurement, the DC errors are most noticeable.

The ADC has a wide selection of gains controlled in the GAIN field of the CH[n].CONFIG register. If CH[n].CONFIG.REFSEL=0, the input range of the ADC core is nominally ±0.6 V differential and the input must be scaled accordingly.

The ADC has a temperature dependent offset. If the ADC is to operate over a large temperature range, we recommend running CALIBRATEOFFSET at regular intervals. The CALIBRATEDONE event will be fired when the calibration has been completed. Note that the DONE and RESULTDONE events will also be generated.

6.12.3 Analog inputs and channels

Up to eight analog input channels, CH[n](n=0..7), can be configured.

Any one of the available channels can be enabled for the ADC to operate in one-shot mode. If more than one CH[n] is configured, the ADC enters scan mode.

An analog input is selected as a positive converter input if CH[n].PSELP is set, setting CH[n].PSELP also enables the particular channel.

An analog input is selected as a negative converter input if CH[n].PSELN is set. The CH[n].PSELN register will have no effect unless differential mode is enabled, see MODE field in CH[n].CONFIG register.

If more than one of the CH[n].PSELP registers is set, the device enters scan mode. Input selections in scan mode are controlled by the CH[n].PSELP and CH[n].PSELN registers, where CH[n].PSELN is only used if the particular scan channel is specified as differential, see MODE field in CH[n].CONFIG register.

6.12.4 Operation modes

The ADC input configuration supports one-shot mode, continuous mode and scan mode.

Note: Scan mode and oversampling cannot be combined.

The ADC indicates a single ongoing conversion via the register [STATUS](#page-218-0) on page 219. During scan mode, oversampling, or continuous modes, more than a single conversion take place in the ADC. As consequence, the value reflected in STATUS register will toggle at the end of each single conversion.

6.12.4.1 One-shot mode

One-shot operation is configured by enabling only one of the available channels defined by CH[n].PSELP, CH[n].PSELN, and CH[n].CONFIG registers.

Upon a SAMPLE task, the ADC starts to sample the input voltage. The CH[n].CONFIG.TACQ controls the acquisition time.

A DONE event signals that one sample has been taken.

In this mode, the RESULTDONE event has the same meaning as DONE when no oversampling takes place. Note that both events may occur before the actual value has been transferred into RAM by EasyDMA. For more information, see [EasyDMA](#page-201-0) on page 202.

6.12.4.2 Continuous mode

Continuous sampling can be achieved by using the internal timer in the ADC, or triggering the SAMPLE task from one of the general purpose timers through the PPI system.

Care shall be taken to ensure that the sample rate fulfils the following criteria, depending on how many channels are active:

```
f_{SAMPLE} < 1/(t_{ACQ} + t_{conv})
```


The SAMPLERATE register can be used as a local timer instead of triggering individual SAMPLE tasks. When SAMPLERATE.MODE is set to Timers, it is sufficient to trigger SAMPLE task only once in order to start the SAADC and triggering the STOP task will stop sampling. The SAMPLERATE.CC field controls the sample rate.

The SAMPLERATE timer mode cannot be combined with SCAN mode, and only one channel can be enabled in this mode.

A DONE event signals that one sample has been taken.

In this mode, the RESULTDONE event has the same meaning as DONE when no oversampling takes place. Note that both events may occur before the actual value has been transferred into RAM by EasyDMA.

6.12.4.3 Oversampling

An accumulator in the ADC can be used to average noise on the analog input. In general, oversampling improves the signal-to-noise ratio (SNR). Oversampling, however, does not improve the integral nonlinearity (INL), or differential non-linearity (DNL).

Oversampling and scan should not be combined, since oversampling and scan will average over input channels.

The accumulator is controlled in the OVERSAMPLE register. The SAMPLE task must be set $2^{\text{OVERSAMPLE}}$ number of times before the result is written to RAM. This can be achieved by:

- Configuring a fixed sampling rate using the local timer or a general purpose timer and the PPI system to trigger a SAMPLE task
- Triggering SAMPLE 2^{OVERSAMPLE} times from software
- Enabling BURST mode

CH[n].CONFIG.BURST can be enabled to avoid setting SAMPLE task $2^{OVERSAMPLE}$ times. With BURST = 1 the ADC will sample the input $2^{OVERSAMPLE}$ times as fast as it can (actual timing: $\langle (t_{ACQ}+t_{CONV}) \times 2^{OVERSAMPLE} \rangle$). Thus, for the user it will just appear like the conversion took a bit longer time, but other than that, it is similar to one-shot mode.

A DONE event signals that one sample has been taken.

In this mode, the RESULTDONE event signals that enough conversions have taken place for an oversampled result to get transferred into RAM. Note that both events may occur before the actual value has been transferred into RAM by EasyDMA.

6.12.4.4 Scan mode

A channel is considered enabled if CH[n].PSELP is set. If more than one channel, CH[n], is enabled, the ADC enters scan mode.

In scan mode, one SAMPLE task will trigger one conversion per enabled channel. The time it takes to sample all channels is:

Total time < Sum $(CH[x].t_{ACQ}+t_{CONV})$, x=0..enabled channels

A DONE event signals that one sample has been taken.

In this mode, the RESULTDONE event signals has the same meaning as DONE when no oversampling takes place. Note that both events may occur before the actual values have been transferred into RAM by EasyDMA.

The figure below provides an example of results placement in Data RAM, with an even RESULT.MAXCNT. In this example, channels 1, 2 and 5 are enabled, all others are disabled.

	31	16 15
RESULT.PTR	CH[2] $1st$ result	CH[1] 1^{st} result
RESULT PTR + 4	CH[1] 2^{nd} result	CH[5] $1st$ result
RESULT.PTR + 8	CH[5] 2^{nd} result	CH[2] 2 nd result
	()	
RESULT PTR + 2*(RESULT.MAXCNT-2)	CH[5] last result	CH[2] last result

Figure 66: Example of RAM placement (even RESULT.MAXCNT), channels 1, 2 and 5 enabled

The figure below provides an example of results placement in Data RAM, with an odd RESULT.MAXCNT. In this example, channels 1, 2 and 5 are enabled, all others are disabled. The last 32-bit word is populated only with one 16-bit result.

	31 16 15	
RESULT.PTR	CH[2] $1st$ result	CH[1] $1st$ result
RESULT.PTR + 4	CH[1] 2^{nd} result	CH[5] $1st$ result
RESULT.PTR + 8	CH[5] 2^{nd} result	CH[2] 2 nd result
	()	
RESULT.PTR + 2*(RESULT.MAXCNT - 1)		CH[5] last result

Figure 67: Example of RAM placement (odd RESULT.MAXCNT), channels 1, 2 and 5 enabled

6.12.5 EasyDMA

After configuring RESULT.PTR and RESULT.MAXCNT, the ADC resources are started by triggering the START task. The ADC is using EasyDMA to store results in a Result buffer in RAM.

The Result buffer is located at the address specified in the RESULT.PTR register. The RESULT.PTR register is double-buffered and it can be updated and prepared for the next START task immediately after the STARTED event is generated. The size of the Result buffer is specified in the RESULT.MAXCNT register and the ADC will generate an END event when it has filled up the Result buffer, see [ADC](#page-202-0) on page 203. Results are stored in little-endian byte order in Data RAM. Every sample will be sign extended to 16 bit before stored in the Result buffer.

The ADC is stopped by triggering the STOP task. The STOP task will terminate an ongoing sampling. The ADC will generate a STOPPED event when it has stopped. If the ADC is already stopped when the STOP task is triggered, the STOPPED event will still be generated.

Figure 68: ADC

If the RESULT.PTR is not pointing to a RAM region accessible from the peripheral, an EasyDMA transfer may result in a HardFault and/or memory corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions.

The EasyDMA will have finished accessing the RAM when the END or STOPPED event has been generated.

The RESULT.AMOUNT register can be read following an END event or a STOPPED event to see how many results have been transferred to the Result buffer in RAM since the START task was triggered.

In scan mode, SAMPLE tasks can be triggered once the START task is triggered. The END event is generated when the number of samples transferred to memory reaches the value specified by RESULT.MAXCNT. After an END event, the START task needs to be triggered again before new samples can be taken. Also make sure that the size of the Result buffer is large enough to have space for minimum one result from each of the enabled channels, by specifying RESULT.MAXCNT >= number of channels enabled. For more information about the scan mode, see [Scan mode](#page-200-0) on page 201.

6.12.6 Resistor ladder

The ADC has an internal resistor string for positive and negative input.

See [Resistor ladder for positive input \(negative input is equivalent, using RESN instead of RESP\)](#page-203-0) on page 204. The resistors are controlled in the CH[n].CONFIG.RESP and CH[n].CONFIG.RESN registers.

Figure 69: Resistor ladder for positive input (negative input is equivalent, using RESN instead of RESP)

6.12.7 Reference

The ADC can use two different references, controlled in the REFSEL field of the CH[n].CONFIG register.

These are:

- Internal reference
- VDD_GPIO as reference

The internal reference results in an input range of ± 0.6 V on the ADC core. VDD GPIO as reference results in an input range of ±VDD_GPIO/4 on the ADC core. The gain block can be used to change the effective input range of the ADC.

Input range = $(+ - 0.6 \text{ V or } +\text{-VDD GPIO}/4)/\text{Gain}$

For example, choosing VDD_GPIO as reference, single ended input (grounded negative input), and a gain of 1/4 the input range will be:

Input range = $(VDD_GPIO/4)/(1/4)$ = VDD_GPIO

With internal reference, single ended input (grounded negative input), and a gain of 1/6 the input range will be:

Input range = $(0.6 \text{ V}) / (1/6) = 3.6 \text{ V}$

The AIN0-AIN7 inputs cannot exceed VDD_GPIO, or be lower than VSS.

6.12.8 Acquisition time

To sample the input voltage, the ADC connects a capacitor to the input.

For illustration, see [Simplified ADC sample network](#page-204-0) on page 205. The acquisition time indicates how long the capacitor is connected, see TACQ field in CH[n].CONFIG register. The required acquisition time depends on the source (R_{source}) resistance. For high source resistance the acquisition time should be increased, see [Acquisition time](#page-204-1) on page 205.

Figure 70: Simplified ADC sample network

Table 67: Acquisition time

6.12.9 Limits event monitoring

A channel can be event monitored by configuring limit register CH[n].LIMIT.

If the conversion result is higher than the defined high limit, or lower than the defined low limit, the appropriate event will get fired.

Figure 71: Example of limits monitoring on channel 'n'

Note that when setting the limits, CH[n].LIMIT.HIGH shall always be higher than or equal to CH[n].LIMIT.LOW . In other words, an event can be fired only when the input signal has been sampled outside of the defined limits. It is not possible to fire an event when the input signal is inside a defined range by swapping high and low limits.

The comparison to limits always takes place, there is no need to enable it. If comparison is not required on a channel, the software shall simply ignore the related events. In that situation, the value of the limits registers is irrelevant, so it does not matter if CH[n].LIMIT.LOW is lower than CH[n].LIMIT.HIGH or not.

6.12.10 Registers

Table 68: Instances

Table 69: Register overview

6.12.10.1 TASKS_START

Address offset: 0x000

Start the ADC and prepare the result buffer in RAM

6.12.10.2 TASKS_SAMPLE

Address offset: 0x004

Take one ADC sample, if scan is enabled all channels are sampled

6.12.10.3 TASKS_STOP

Address offset: 0x008

Stop the ADC and terminate any on-going conversion

6.12.10.4 TASKS_CALIBRATEOFFSET

Address offset: 0x00C

Starts offset auto-calibration

6.12.10.5 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-206-0)

6.12.10.6 SUBSCRIBE_SAMPLE

Address offset: 0x084

Subscribe configuration for task [SAMPLE](#page-206-1)

6.12.10.7 SUBSCRIBE_STOP

Address offset: 0x088

Subscribe configuration for task [STOP](#page-206-2)

6.12.10.8 SUBSCRIBE_CALIBRATEOFFSET

Address offset: 0x08C

Subscribe configuration for task [CALIBRATEOFFSET](#page-206-3)

6.12.10.9 EVENTS_STARTED

Address offset: 0x100

The ADC has started

6.12.10.10 EVENTS_END

Address offset: 0x104

The ADC has filled up the Result buffer

6.12.10.11 EVENTS_DONE

Address offset: 0x108

A conversion task has been completed. Depending on the mode, multiple conversions might be needed for a result to be transferred to RAM.

6.12.10.12 EVENTS_RESULTDONE

Address offset: 0x10C

A result is ready to get transferred to RAM.

6.12.10.13 EVENTS_CALIBRATEDONE

Address offset: 0x110

Calibration is complete

6.12.10.14 EVENTS_STOPPED

Address offset: 0x114

The ADC has stopped

6.12.10.15 EVENTS_CH[n].LIMITH (n=0..7)

Address offset: 0x118 + (n × 0x8)

Last results is equal or above CH[n].LIMIT.HIGH

6.12.10.16 EVENTS_CH[n].LIMITL (n=0..7)

Address offset: 0x11C + (n × 0x8)

Last results is equal or below CH[n].LIMIT.LOW

6.12.10.17 PUBLISH_STARTED

Address offset: 0x180

Publish configuration for event [STARTED](#page-208-0)

6.12.10.18 PUBLISH_END

Address offset: 0x184

Publish configuration for event [END](#page-208-1)

6.12.10.19 PUBLISH_DONE

Address offset: 0x188

Publish configuration for event [DONE](#page-208-2)

6.12.10.20 PUBLISH_RESULTDONE

Address offset: 0x18C

Publish configuration for event [RESULTDONE](#page-209-0)

6.12.10.21 PUBLISH_CALIBRATEDONE

Address offset: 0x190

Publish configuration for event [CALIBRATEDONE](#page-209-1)

6.12.10.22 PUBLISH_STOPPED

Address offset: 0x194

Publish configuration for event [STOPPED](#page-209-2)

6.12.10.23 PUBLISH_CH[n].LIMITH (n=0..7)

Address offset: 0x198 + (n × 0x8)

Publish configuration for event [CH\[n\].LIMITH](#page-209-3)

6.12.10.24 PUBLISH_CH[n].LIMITL (n=0..7)

Address offset: 0x19C + (n × 0x8)

Publish configuration for event [CH\[n\].LIMITL](#page-210-0)

6.12.10.25 INTEN

Address offset: 0x300

Enable or disable interrupt

6.12.10.26 INTENSET

Address offset: 0x304

Enable interrupt

6.12.10.27 INTENCLR

Address offset: 0x308

Disable interrupt

6.12.10.28 STATUS

Address offset: 0x400

Status

6.12.10.29 ENABLE

Address offset: 0x500

Enable or disable ADC

When enabled, the ADC will acquire access to the analog input pins specified in the CH[n].PSELP and CH[n].PSELN registers.

6.12.10.30 CH[n].PSELP (n=0..7)

Address offset: 0x510 + (n × 0x10)

Input positive pin selection for CH[n]

6.12.10.31 CH[n].PSELN (n=0..7)

Address offset: 0x514 + (n × 0x10)

Input negative pin selection for CH[n]

6.12.10.32 CH[n].CONFIG (n=0..7)

Address offset: $0x518 + (n \times 0x10)$

Input configuration for CH[n]

6.12.10.33 CH[n].LIMIT (n=0..7)

Address offset: 0x51C + (n × 0x10)

High/low limits for event monitoring a channel

6.12.10.34 RESOLUTION

Address offset: 0x5F0

Resolution configuration

6.12.10.35 OVERSAMPLE

Address offset: 0x5F4

Oversampling configuration. OVERSAMPLE should not be combined with SCAN. The RESOLUTION is applied before averaging, thus for high OVERSAMPLE a higher RESOLUTION should be used.

6.12.10.36 SAMPLERATE

Address offset: 0x5F8

Controls normal or continuous sample rate

6.12.10.37 RESULT.PTR

Address offset: 0x62C

Data pointer

memories are available for EasyDMA.

6.12.10.38 RESULT.MAXCNT

Address offset: 0x630

Maximum number of buffer words to transfer

6.12.10.39 RESULT.AMOUNT

Address offset: 0x634

Number of buffer words transferred since last START

be read after an END or STOPPED event.

6.12.11 Electrical specification

6.12.11.1 SAADC Electrical Specification

^a Digital output code at zero volt differential input.

6.12.12 Performance factors

Clock jitter, affecting sample timing accuracy, and circuit noise can affect ADC performance.

Jitter can be between START tasks or from START task to acquisition. START timer accuracy and startup times of regulators and references will contribute to variability. Sources of circuit noise may include CPU activity and the DC/DC regulator. Best ADC performance is achieved using START timing based on the TIMER module, HFXO clock source, and Constant Latency mode.

6.13 SPIM — Serial peripheral interface master with EasyDMA

The SPI master can communicate with multiple slaves using individual chip select signals for each of the slave devices attached to a bus.

Listed here are the main features for the SPIM

- SPI mode 0-3
- EasyDMA direct transfer to/from RAM for both SPI Slave and SPI Master
- Individual selection of IO pin for each SPI signal

b Does not include temperature drift

¹³ Maximum gain corresponds to highest capacitance.

The SPIM does not implement support for chip select directly. Therefore, the CPU must use available GPIOs to select the correct slave and control this independently of the SPI master. The SPIM supports SPI modes 0 through 3. The CONFIG register allows setting CPOL and CPHA appropriately.

Table 70: SPI modes

6.13.1 SPI master transaction sequence

An SPI master transaction consists of a sequence started by the START task followed by a number of events, and finally the STOP task.

An SPI master transaction is started by triggering the START task. The ENDTX event will be generated when the transmitter has transmitted all bytes in the TXD buffer as specified in the TXD.MAXCNT register. The ENDRX event will be generated when the receiver has filled the RXD buffer, i.e. received the last possible byte as specified in the RXD.MAXCNT register.

Following a START task, the SPI master will generate an END event when both ENDRX and ENDTX have been generated.

The SPI master is stopped by triggering the STOP task. A STOPPED event is generated when the SPI master has stopped.

If the ENDRX event has not already been generated when the SPI master has come to a stop, the SPI master will generate the ENDRX event explicitly even though the RX buffer is not full.

If the ENDTX event has not already been generated when the SPI master has come to a stop, the SPI master will generate the ENDTX event explicitly even though all bytes in the TXD buffer, as specified in the TXD.MAXCNT register, have not been transmitted.

The SPI master is a synchronous interface, and for every byte that is sent, a different byte will be received at the same time; this is illustrated in [SPI master transaction](#page-225-0) on page 226.

6.13.2 Master mode pin configuration

The SCK, MOSI, and MISO signals associated with the SPI master are mapped to physical pins according to the configuration specified in the PSEL.SCK, PSEL.MOSI, and PSEL.MISO registers respectively.

The PSEL.SCK, PSEL.MOSI, and PSEL.MISO registers and their configurations are only used as long as the SPI master is enabled, and retained only as long as the device is in ON mode. PSEL.SCK, PSEL.MOSI and PSEL.MISO must only be configured when the SPI master is disabled.

To secure correct behavior in the SPI, the pins used by the SPI must be configured in the GPIO peripheral as described in [GPIO configuration](#page-225-1) on page 226 prior to enabling the SPI. This configuration must be retained in the GPIO for the selected IOs as long as the SPI is enabled.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

Table 71: GPIO configuration

6.13.3 Shared resources

The SPI shares registers and other resources with other peripherals that have the same ID as the SPI. Therefore, the user must disable all peripherals that have the same ID as the SPI before the SPI can be configured and used.

Disabling a peripheral that has the same ID as the SPI will not reset any of the registers that are shared with the SPI. It is therefore important to configure all relevant SPI registers explicitly to secure that it operates correctly.

See the Instantiation table in [Instantiation](#page-23-0) on page 24 for details on peripherals and their IDs.

6.13.4 EasyDMA

The SPIM implements EasyDMA for accessing RAM without CPU involvement.

The SPIM peripheral implements the following EasyDMA channels:

Table 72: SPIM EasyDMA Channels

For detailed information regarding the use of EasyDMA, see [EasyDMA](#page-44-0) on page 45.

The .PTR and .MAXCNT registers are double-buffered. They can be updated and prepared for the next transmission immediately after having received the STARTED event.

The SPI master will automatically stop transmitting after TXD.MAXCNT bytes have been transmitted and RXD.MAXCNT bytes have been received. If RXD.MAXCNT is larger than TXD.MAXCNT, the remaining transmitted bytes will contain the value defined in the ORC register. If TXD.MAXCNT is larger than RXD.MAXCNT, the superfluous received bytes will be discarded.

The ENDRX/ENDTX event indicate that EasyDMA has finished accessing respectively the RX/TX buffer in RAM. The END event gets generated when both RX and TX are finished accessing the buffers in RAM.

In the case of bus congestion as described in [AHB multilayer interconnect](#page-46-0) on page 47, data loss may occur.

6.13.5 Low power

When putting the system in low power and the peripheral is not needed, lowest possible power consumption is achieved by stopping, and then disabling the peripheral.

The STOP task may not be always needed (the peripheral might already be stopped), but if it is sent, software shall wait until the STOPPED event was received as a response before disabling the peripheral through the ENABLE register.

6.13.6 Registers

Table 73: Instances

Table 74: Register overview

6.13.6.1 TASKS_START

Address offset: 0x010

Start SPI transaction

6.13.6.2 TASKS_STOP

Address offset: 0x014

Stop SPI transaction

6.13.6.3 TASKS_SUSPEND

Address offset: 0x01C

Suspend SPI transaction

6.13.6.4 TASKS_RESUME

Address offset: 0x020

Resume SPI transaction

6.13.6.5 SUBSCRIBE_START

Address offset: 0x090

Subscribe configuration for task [START](#page-228-0)

6.13.6.6 SUBSCRIBE_STOP

Address offset: 0x094

Subscribe configuration for task [STOP](#page-228-1)

6.13.6.7 SUBSCRIBE_SUSPEND

Address offset: 0x09C

Subscribe configuration for task [SUSPEND](#page-228-2)

6.13.6.8 SUBSCRIBE_RESUME

Address offset: 0x0A0

Subscribe configuration for task [RESUME](#page-228-3)

6.13.6.9 EVENTS_STOPPED

Address offset: 0x104

SPI transaction has stopped

6.13.6.10 EVENTS_ENDRX

Address offset: 0x110

End of RXD buffer reached

6.13.6.11 EVENTS_END

Address offset: 0x118

End of RXD buffer and TXD buffer reached

6.13.6.12 EVENTS_ENDTX

Address offset: 0x120

End of TXD buffer reached

6.13.6.13 EVENTS_STARTED

Address offset: 0x14C

Transaction started

6.13.6.14 PUBLISH_STOPPED

Address offset: 0x184

Publish configuration for event [STOPPED](#page-230-0)

6.13.6.15 PUBLISH_ENDRX

Address offset: 0x190

Publish configuration for event [ENDRX](#page-230-1)

6.13.6.16 PUBLISH_END

Address offset: 0x198

Publish configuration for event [END](#page-230-2)

6.13.6.17 PUBLISH_ENDTX

Address offset: 0x1A0

Publish configuration for event [ENDTX](#page-230-3)

6.13.6.18 PUBLISH_STARTED

Address offset: 0x1CC

Publish configuration for event [STARTED](#page-231-0)

6.13.6.19 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.13.6.20 INTENSET

Address offset: 0x304

Enable interrupt

6.13.6.21 INTENCLR

Address offset: 0x308

Disable interrupt

6.13.6.22 ENABLE

Address offset: 0x500

Enable SPIM

6.13.6.23 PSEL.SCK

Address offset: 0x508

Pin select for SCK

6.13.6.24 PSEL.MOSI

Address offset: 0x50C

Pin select for MOSI signal

6.13.6.25 PSEL.MISO

Address offset: 0x510

Pin select for MISO signal

6.13.6.26 FREQUENCY

Address offset: 0x524

SPI frequency. Accuracy depends on the HFCLK source selected.

6.13.6.27 RXD.PTR

Address offset: 0x534

Data pointer

Note: See the memory chapter for details about which memories are available for EasyDMA.

6.13.6.28 RXD.MAXCNT

Address offset: 0x538

Maximum number of bytes in receive buffer

6.13.6.29 RXD.AMOUNT

Address offset: 0x53C

Number of bytes transferred in the last transaction

6.13.6.30 RXD.LIST

Address offset: 0x540

EasyDMA list type

6.13.6.31 TXD.PTR

Address offset: 0x544

Data pointer

memories are available for EasyDMA.

6.13.6.32 TXD.MAXCNT

Address offset: 0x548

Maximum number of bytes in transmit buffer

6.13.6.33 TXD.AMOUNT

Address offset: 0x54C

Number of bytes transferred in the last transaction

6.13.6.34 TXD.LIST

Address offset: 0x550

EasyDMA list type

6.13.6.35 CONFIG

Address offset: 0x554

Configuration register

6.13.6.36 ORC

Address offset: 0x5C0

Over-read character. Character clocked out in case an over-read of the TXD buffer.

TXD buffer.

6.13.7 Electrical specification

6.13.7.1 SPIM master interface electrical specifications

6.13.7.2 Serial Peripheral Interface Master (SPIM) timing specifications

¹⁴ High bit rates may require GPIOs to be set as High Drive, see GPIO chapter for more details.
^a At 25pF load, including GPIO pin capacitance, see GPIO spec.

Figure 74: SPIM timing diagram

6.14 SPIS — Serial peripheral interface slave with EasyDMA

SPI slave (SPIS) is implemented with EasyDMA support for ultra low power serial communication from an external SPI master. EasyDMA in conjunction with hardware-based semaphore mechanisms removes all real-time requirements associated with controlling the SPI slave from a low priority CPU execution context.

Figure 75: SPI slave

The SPIS supports SPI modes 0 through 3. The CONFIG register allows setting CPOL and CPHA appropriately.

Table 75: SPI modes

6.14.1 Shared resources

The SPI slave shares registers and other resources with other peripherals that have the same ID as the SPI slave. Therefore, you must disable all peripherals that have the same ID as the SPI slave before the SPI slave can be configured and used.

Disabling a peripheral that has the same ID as the SPI slave will not reset any of the registers that are shared with the SPI slave. It is important to configure all relevant SPI slave registers explicitly to secure that it operates correctly.

The Instantiation table in [Instantiation](#page-23-0) on page 24 shows which peripherals have the same ID as the SPI slave.

6.14.2 EasyDMA

The SPIS implements EasyDMA for accessing RAM without CPU involvement.

The SPIS peripheral implements the following EasyDMA channels:

Table 76: SPIS EasyDMA Channels

For detailed information regarding the use of EasyDMA, see [EasyDMA](#page-44-0) on page 45.

If RXD.MAXCNT is larger than TXD.MAXCNT, the remaining transmitted bytes will contain the value defined in the ORC register.

The END event indicates that EasyDMA has finished accessing the buffer in RAM.

6.14.3 SPI slave operation

SPI slave uses two memory pointers, RXD.PTR and TXD.PTR, that point to the RXD buffer (receive buffer) and TXD buffer (transmit buffer) respectively. Since these buffers are located in RAM, which can be accessed by both the SPI slave and the CPU, a hardware based semaphore mechanism is implemented to enable safe sharing.

Before the CPU can safely update the RXD.PTR and TXD.PTR pointers it must first acquire the SPI semaphore. The CPU can acquire the semaphore by triggering the ACQUIRE task and then receiving the ACQUIRED event. When the CPU has updated the RXD.PTR and TXD.PTR pointers the CPU must release the semaphore before the SPI slave will be able to acquire it.

The CPU releases the semaphore by triggering the RELEASE task, this is illustrated in [SPI transaction when](#page-241-0) [shortcut between END and ACQUIRE is enabled](#page-241-0) on page 242. Triggering the RELEASE task when the semaphore is not granted to the CPU will have no effect. See [Semaphore operation](#page-242-0) on page 243 for more information

If the CPU is not able to reconfigure the TXD.PTR and RXD.PTR between granted transactions, the same TX data will be clocked out and the RX buffers will be overwritten. To prevent this from happening, the END_ACQUIRE shortcut can be used. With this shortcut enabled the semaphore will be handed over to the CPU automatically after the granted transaction has completed, giving the CPU the ability to update the TXPTR and RXPTR between every granted transaction.

The ENDRX event is generated when the RX buffer has been filled.

The RXD.MAXCNT register specifies the maximum number of bytes the SPI slave can receive in one granted transaction. If the SPI slave receives more than RXD.MAXCNT number of bytes, an OVERFLOW will be indicated in the STATUS register and the incoming bytes will be discarded.

The TXD.MAXCNT parameter specifies the maximum number of bytes the SPI slave can transmit in one granted transaction. If the SPI slave is forced to transmit more than TXD.MAXCNT number of bytes, an OVERREAD will be indicated in the STATUS register and the ORC character will be clocked out.

The RXD.AMOUNT and TXD.AMOUNT registers are updated when a granted transaction is completed. The TXD.AMOUNT register indicates how many bytes were read from the TX buffer in the last transaction, that is, ORC (over-read) characters are not included in this number. Similarly, the RXD.AMOUNT register indicates how many bytes were written into the RX buffer in the last transaction.

Figure 76: SPI transaction when shortcut between END and ACQUIRE is enabled

6.14.4 Semaphore operation

The semaphore is a mechanism implemented inside the SPI slave that prevents simultaneous access to the data buffers by the SPI slave and CPU.

The semaphore is by default assigned to the CPU after the SPI slave is enabled. No ACQUIRED event will be generated for this initial semaphore handover. An ACQUIRED event will be generated immediately if the ACQUIRE task is triggered while the semaphore is assigned to the CPU. The figure [SPI semaphore FSM](#page-242-1) on page 243 illustrates the transitions between states in the semaphore based on the relevant tasks and events.

Figure 77: SPI semaphore FSM

Note: The semaphore mechanism does not, at any time, prevent the CPU from performing read or write access to the RXD.PTR register, the TXD.PTR registers, or the RAM that these pointers are pointing to. The semaphore is only telling when these can be updated by the CPU so that safe sharing is achieved.

The SPI slave will try to acquire the semaphore when STARTED event is detected, the even also indicates that CSN is currently low. If the SPI slave does not manage to acquire the semaphore at this point (i.e., it is under CPU's control), the transaction will be ignored. This means that all incoming data on MOSI will be discarded, and the DEF (default) character will be clocked out on the MISO line throughout the whole transaction. This will also be the case even if the semaphore is released by the CPU during the transaction. In case of a race condition where the CPU and the SPI slave try to acquire the semaphore at the same time, as illustrated in lifeline item 2 in figure [SPI transaction when shortcut between END and ACQUIRE is](#page-241-0) [enabled](#page-241-0) on page 242, the semaphore will be granted to the CPU.

If the SPI slave acquires the semaphore, the transaction will be granted. The incoming data on MOSI will be stored in the RXD buffer and the data in the TXD buffer will be clocked out on MISO.

When a granted transaction is completed and CSN goes high, the SPI slave will automatically release the semaphore and generate the END event.

As long as the semaphore is available, the SPI slave can be granted multiple transactions one after the other.

If the CPU tries to acquire the semaphore while it is assigned to the SPI slave, an immediate handover will not be granted. However, the semaphore will be handed over to the CPU as soon as the SPI slave has released the semaphore after the granted transaction is completed. If the END ACQUIRE shortcut is enabled and the CPU has triggered the ACQUIRE task during a granted transaction, only one ACQUIRE request will be served following the END event.

6.14.5 Pin configuration

The CSN, SCK, MOSI, and MISO signals associated with the SPI slave are mapped to physical pins according to the configuration specified in the PSEL.CSN, PSEL.SCK, PSEL.MOSI, and PSEL.MISO registers respectively. If the CONNECT field of any of these registers is set to Disconnected, the associated SPI slave signal will not be connected to any physical pins.

The PSEL.CSN, PSEL.SCK, PSEL.MOSI, and PSEL.MISO registers and their configurations are only used as long as the SPI slave is enabled, and retained only as long as the device is in System ON mode, see [POWER](#page-63-0) [— Power control](#page-63-0) on page 64 chapter for more information about power modes. When the peripheral is disabled, the pins will behave as regular GPIOs, and use the configuration in their respective OUT bit field and PIN_CNF[n] register. PSEL.CSN, PSEL.SCK, PSEL.MOSI, and PSEL.MISO must only be configured when the SPI slave is disabled.

To secure correct behavior in the SPI slave, the pins used by the SPI slave must be configured in the GPIO peripheral as described in [GPIO configuration before enabling peripheral](#page-243-0) on page 244 before enabling the SPI slave. This is to secure that the pins used by the SPI slave are driven correctly if the SPI slave itself is temporarily disabled, or if the device temporarily enters System OFF. This configuration must be retained in the GPIO for the selected I/Os as long as the SPI slave is to be recognized by an external SPI master.

The MISO line is set in high impedance as long as the SPI slave is not selected with CSN.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

Table 77: GPIO configuration before enabling peripheral

6.14.6 Registers

Table 78: Instances

Table 79: Register overview

6.14.6.1 TASKS_ACQUIRE

Address offset: 0x024

Acquire SPI semaphore

6.14.6.2 TASKS_RELEASE

Address offset: 0x028

Release SPI semaphore, enabling the SPI slave to acquire it

6.14.6.3 SUBSCRIBE_ACQUIRE

Address offset: 0x0A4

Subscribe configuration for task [ACQUIRE](#page-244-0)

6.14.6.4 SUBSCRIBE_RELEASE

Address offset: 0x0A8

Subscribe configuration for task [RELEASE](#page-245-0)

6.14.6.5 EVENTS_END

Address offset: 0x104

Granted transaction completed

6.14.6.6 EVENTS_ENDRX

Address offset: 0x110

End of RXD buffer reached

6.14.6.7 EVENTS_ACQUIRED

Address offset: 0x128

Semaphore acquired

6.14.6.8 PUBLISH_END

Address offset: 0x184

Publish configuration for event [END](#page-245-3)

6.14.6.9 PUBLISH_ENDRX

Address offset: 0x190

Publish configuration for event [ENDRX](#page-246-0)

6.14.6.10 PUBLISH_ACQUIRED

Address offset: 0x1A8

Publish configuration for event [ACQUIRED](#page-246-1)

6.14.6.11 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.14.6.12 INTENSET

Address offset: 0x304

Enable interrupt

6.14.6.13 INTENCLR

Address offset: 0x308

Disable interrupt

6.14.6.14 SEMSTAT

Address offset: 0x400

Semaphore status register

6.14.6.15 STATUS

Address offset: 0x440

Status from last transaction

Note: Individual bits are cleared by writing a '1' to the bits that shall be cleared

6.14.6.16 ENABLE

Address offset: 0x500

Enable SPI slave

6.14.6.17 PSEL.SCK

Address offset: 0x508

Pin select for SCK

6.14.6.18 PSEL.MISO

Address offset: 0x50C

Pin select for MISO signal

6.14.6.19 PSEL.MOSI

Address offset: 0x510

Pin select for MOSI signal

6.14.6.20 PSEL.CSN

Address offset: 0x514

Pin select for CSN signal

6.14.6.21 PSELSCK (Deprecated)

Address offset: 0x508

Pin select for SCK

This register is deprecated.

6.14.6.22 PSELMISO (Deprecated)

Address offset: 0x50C

Pin select for MISO

This register is deprecated.

6.14.6.23 PSELMOSI (Deprecated)

Address offset: 0x510

Pin select for MOSI

This register is deprecated.

6.14.6.24 PSELCSN (Deprecated)

Address offset: 0x514

Pin select for CSN

This register is deprecated.

6.14.6.25 RXD.PTR

Address offset: 0x534 RXD data pointer

memories are available for EasyDMA.

6.14.6.26 RXD.MAXCNT

Address offset: 0x538

Maximum number of bytes in receive buffer

6.14.6.27 RXD.AMOUNT

Address offset: 0x53C

Number of bytes received in last granted transaction

6.14.6.28 RXD.LIST

Address offset: 0x540

EasyDMA list type

6.14.6.29 RXDPTR (Deprecated)

Address offset: 0x534

RXD data pointer

This register is deprecated.

memories are available for EasyDMA.

6.14.6.30 MAXRX (Deprecated)

Address offset: 0x538

Maximum number of bytes in receive buffer

This register is deprecated.

6.14.6.31 AMOUNTRX (Deprecated)

Address offset: 0x53C

Number of bytes received in last granted transaction

This register is deprecated.

6.14.6.32 TXD.PTR

Address offset: 0x544

TXD data pointer

Note: See the memory chapter for details about which memories are available for EasyDMA.

6.14.6.33 TXD.MAXCNT

Address offset: 0x548

Maximum number of bytes in transmit buffer

6.14.6.34 TXD.AMOUNT

Address offset: 0x54C

Number of bytes transmitted in last granted transaction

6.14.6.35 TXD.LIST

Address offset: 0x550

EasyDMA list type

6.14.6.36 TXDPTR (Deprecated)

Address offset: 0x544

TXD data pointer

This register is deprecated.

6.14.6.37 MAXTX (Deprecated)

Address offset: 0x548

Maximum number of bytes in transmit buffer

This register is deprecated.

6.14.6.38 AMOUNTTX (Deprecated)

Address offset: 0x54C

Number of bytes transmitted in last granted transaction

This register is deprecated.

6.14.6.39 CONFIG

Address offset: 0x554

Configuration register

6.14.6.40 DEF

Address offset: 0x55C

Default character. Character clocked out in case of an ignored transaction.

6.14.6.41 ORC

Address offset: 0x5C0

Over-read character

transmit buffer.

6.14.7 Electrical specification

6.14.7.1 SPIS slave interface electrical specifications

6.14.7.2 Serial Peripheral Interface Slave (SPIS) timing specifications

Symbol	Description	Min.	Typ.	Max.	Units
t _{SPIS, CSCKIN}	SCK input period	125			ns
t _{SPIS, RFSCKIN}	SCK input rise/fall time			30	ns
t _{SPIS} , WHSCKIN	SCK input high time	30			ns
t _{SPIS, WLSCKIN}	SCK input low time	30			ns
t _{SPIS, SUCSN}	CSN to CLK setup time	1000			ns
t _{SPIS, HCSN}	CLK to CSN hold time	2000			ns
t _{SPIS,ASA}	CSN to MISO driven	$\mathbf 0$			ns
t _{SPIS,ASO}	CSN to MISO valid ^a			1000	ns
t _{SPIS, DISSO}	CSN to MISO disabled ^a			68	ns
t _{SPIS, CWH}	CSN inactive time	300			ns
t _{SPIS,VSO}	CLK edge to MISO valid			19	ns
t _{SPIS, HSO}	MISO hold time after CLK edge	18^{17}			ns
t _{SPIS} , SUSI	MOSI to CLK edge setup time	59			ns
t _{SPIS,HSI}	CLK edge to MOSI hold time	20			ns

¹⁵ High bit rates may require GPIOs to be set as High Drive, see GPIO chapter for more details.

¹⁷ This is to ensure compatibility to SPI masters sampling MISO on the same edge as MOSI is output

¹⁶ The actual maximum data rate depends on the master's CLK to MISO and MOSI setup and hold timings.

^a At 25pF load, including GPIO capacitance, see GPIO spec.

Figure 78: SPIS timing diagram

Figure 79: Common SPIM and SPIS timing diagram

6.15 SPU — System protection unit

SPU is the central point in the system to control access to memories, peripherals and other resources.

Listed here are the main features of the SPU:

- ARM TrustZone support, allowing definition of secure, non-secure and non-secure callable memory regions
- Extended ARMTrustZone, protecting memory regions and peripherals from non-CPU devices like EasyDMA transfer
- Pin access protection, preventing non-secure code and peripherals from accessing secure pin resources
- DPPI access protection, realized by preventing non-secure code and peripherals to publish from or subscribe to secured DPPI channels
- External domain access protection, controlling access rights from other MCUs

6.15.1 General concepts

SPU provides a register interface to control the various internal logic blocks that monitor access to memory-mapped slave devices (RAM, flash, peripherals, etc) and other resources (device pins, DPPI channels, etc).

For memory-mapped devices like RAM, flash and peripherals, the internal logic checks the address and attributes (e.g. read, write, execute, secure) of the incoming transfer to block it if necessary. Whether a secure resource can be accessed by a given master is defined:

For a CPU-type master

By the security state of the CPU and the security state reported by the SPU, for the address in the bus transfer

For a non-CPU master

By the security attribute of the master that initiates the transfer, defined by a SPU register

The [Simplified view of the protection of RAM, flash and peripherals using SPU](#page-258-0) on page 259 shows a simplified view of the SPU registers controlling several internal modules.

Figure 80: Simplified view of the protection of RAM, flash and peripherals using SPU

The protection logic implements a read-as-zero/write-ignore (RAZ/WI) policy:

- A blocked read operation will always return a zero value on the bus, preventing information leak
- A write operation to a forbidden region or peripheral will be ignored

An error is reported through dedicated error signals. For security state violations from an M33 master this will be a SecureFault exception, for other violations this will be an SPU event. The SPU event can be configured to generate an interrupt towards the CPU.

Other resources like pins and DPPI channels are protected by comparing the security attributes of the protected resource with the security attribute of the peripheral that wants to access it. The SPU is the only place where those security attributes can be configured.

6.15.1.1 Special considerations for ARM TrustZone for Cortex-M enabled system

For a ARM TrustZone for Cortex-M enabled CPU, the SPU also controls custom logic.

Custom logic is shown as the implementation defined attribution unit (IDAU) in figure [Simplified view of](#page-258-0) [the protection of RAM, flash and peripherals using SPU](#page-258-0) on page 259. Full support is provided for:

- ARM TrustZone for Cortex-M related instructions, like test target (TT) for reporting the security attributes of a region
- Non-secure callable (NSC) regions, to implement secure entry points from non-secure code

The SPU provides the necessary registers to configure the security attributes for memory regions and peripherals. However, as a requirement to use the SPU, the secure attribution unit (SAU) needs to be disabled and all memory set as non-secure in the ARM core. This will allow the SPU to control the IDAU and set the security attribution of all addresses as originally intended.

6.15.2 Flash access control

The flash memory space is divided in regions, each of them with configurable permissions settings.

The flash memory space is divided into 32 regions of 32 KiB .

For each region, four different types of permissions can be configured:

Read

Allows data read access to the region. Note that code fetch from this region is not controlled by the read permission but by the execute permission described below.

Write

Allows write or page erase access to the region

Execute

Allows code fetch from this region, even if data read is disabled

Secure

Allows only bus accesses with the security attribute set to access the region

Permissions can be set independently. For example, it is possible to configure a flash region to be accessible only through secure transfer, being read-only (no write allowed) and non-executable (no code fetch allowed). For each region, permissions can be set and then locked by using the [FLASHREGION\[n\].PERM](#page-278-0).LOCK bit, to prevent subsequent modifications.

Note that the debugger is able to step through execute-protected memory regions.

The following figure shows the flash memory space and the divided regions:

Flash address space

Figure 81: Definition of the N=32 regions, each of 32 KiB, in the flash memory space

6.15.2.1 Non-secure callable (NSC) region definition in flash

The SPU provides support for the definition of non-secure callable (NSC) sub-regions to allow non-secure to secure function calls.

A non-secure callable sub-region can only exist within an existing secure region and its definition is done using two registers:

- [FLASHNSC\[n\].REGION](#page-276-0), used to select the secure region that will contain the NSC sub-region
- [FLASHNSC\[n\].SIZE](#page-276-1), used to define the size of the NSC sub-region within the secure region

The NSC sub-region will be defined from the highest address in that region, going downwards. Figure below illustrates the NSC sub-regions and the registers used for their definition:

Figure 82: Non-secure callable region definition in the flash memory space

The NSC sub-region will only be defined if:

- FLASHNSC[*i*].SIZE value is non zero
- FLASHNSC[*i*].REGION defines a secure region

If FLASHNSC[*i*].REGION and FLASHNSC[*j*].REGION have the same value, there is only one sub-region defined as NSC, with the size given by the maximum of FLASHNSC[*i*].SIZE and FLASHNSC[*j*].SIZE.

If FLASHNSC[*i*].REGION defines a non-secure region, then there is no non-secure callable region defined and the selected region stays non-secure.

6.15.2.2 Flash access error reporting

The SPU and the logic controlled by it will respond with a certain behavior once an access violation is detected.

The following will happen once the logic controlled by the SPU detects an access violation on one of the flash ports:

- The faulty transfer will be blocked
- In case of a read transfer, the bus will be driven to zero
- Feedback will be sent to the master through specific bus error signals, if this is supported by the master. Moreover, the SPU will receive an event that can optionally trigger an interrupt towards the CPU.
- SecureFault exception will be triggered if security violation is detected for access from Cortex-M33
- BusFault exception will be triggered when read/write/execute protection violation is detected for Cortex-M33
- FLASHACCERR event will be triggered if any access violations are detected for all master types except for Cortex-M33 security violation

The following table summarizes the SPU behavior based on the type of initiator and access violation:

Table 80: Error reporting for flash access errors

For a Cortex-M33 master, the SecureFault exception will take precedence over the BusFault exception if a security violation occurs simultaneously with another type of violation.

6.15.2.3 UICR and FICR protections

The user information configuration registers (UICR) and factory information configuration registers (FICR) are always considered as secure. FICR registers are read-only. UICR registers can be read and written by secure code only.

Writing new values to user information configuration registers must follow the procedure described in [NVMC — Non-volatile memory controller](#page-28-0) on page 29. Code execution from FICR and UICR address spaces will always be reported as access violation, an exception to this rule applies during a debug session.

6.15.3 RAM access control

The RAM memory space is divided in regions, each of them with configurable permissions settings.

The RAM memory space is divided into 32 regions of 8 KiB.

For each region, four different types of permissions can be configured:

Read

Allows data read access to the region. Code fetch from this region is not controlled by the read permission but by the execute permission described below.

Write

Allows write access to the region

Execute

Allows code fetch from this region

Secure

Allows only bus accesses with the security attribute set to access the region

Permissions can be set independently. For example, it is possible to configure a RAM region to be accessible only through secure transfer, being read-only (no write allowed) and non-executable (no code fetch allowed). For each region, permissions can be set and then locked to prevent subsequent modifications by using the [RAMREGION\[n\].PERM](#page-278-1).LOCK bit.

The following figure shows the RAM memory space and the devided regions:

Figure 83: Definition of the N=32 regions, each of 8 KiB, in the RAM memory space

6.15.3.1 Non-secure callable (NSC) region definition in RAM

The SPU provides support for the definition of non-secure callable (NSC) sub-regions to allow non-secure to secure function calls.

A non-secure callable sub-region can only exist within an existing secure region and its definition is done using two registers:

- [RAMNSC\[n\].REGION](#page-277-0), used to select the secure region that will contain the NSC sub-region
- [RAMNSC\[n\].SIZE](#page-277-1), used to define the size of the NSC sub-region within the secure region

The NSC sub-region will be defined from the highest address in that region, going downwards. Figure below illustrates the NSC sub-regions and the registers used for their definition:

Figure 84: Non-secure callable region definition in the RAM memory space

The NSC sub-region will only be defined if:

- RAMNSC[*i*].SIZE value is non zero
- RAMNSC[*i*].REGION defines a secure region

If RAMNSC[*i*].REGION and RAMNSC[*j*].REGION have the same value, there is only one sub-region defined as NSC, with the size given by the maximum of RAMNSC[*i*].SIZE and RAMNSC[*j*].SIZE.

If RAMNSC[*i*].REGION defines a non-secure region, then there is no non-secure callable region defined and the selected region stays non-secure.

6.15.3.2 RAM access error reporting

The SPU and the logic controlled by it will respond with a certain behavior once an access violation is detected.

The following will happen once the logic controlled by the SPU detects an access violation on one of the RAM ports:

- The faulty transfer will be blocked
- In case of a read transfer, the bus will be driven to zero
- Feedback will be sent to the master through specific bus error signals, if this is supported by the master
- SecureFault exception will be triggered if security violation is detected for access from Cortex-M33
- BusFault exception will be triggered when read/write/execute protection violation is detected for Cortex-M33. The SPU will also generate an event that can optionally trigger an interrupt towards the CPU.
- RAMACCERR event will be triggered if any access violations are detected for all master types but for Cortex-M33 security violation

The following table summarizes the SPU behavior based on the type of initiator and access violation:

Table 81: Error reporting for RAM access errors

For a Cortex-M33 master, the SecureFault exception will take precedence over the BusFault exception if a security violation occurs simultaneously with another type of violation.

6.15.4 Peripheral access control

Access controls are defined by the characteristics of the peripheral.

Peripherals can have their security attribute set as:

Always secure

For a peripheral related to system control

Always non-secure

For some general-purpose peripherals

Configurable

For general-purpose peripherals that may be configured for secure only access

The full list of peripherals and their corresponding security attributes can be found in [Memory map](#page-22-0) on page 23. For each peripheral with ID *n*, [PERIPHID\[](#page-279-0)*n*]. PERM will show whether the security attribute for this peripheral is configurable or not.

If not hardcoded, the security attribute can configured using the PERIPHID[*id*].PERM.

At reset, all user-selectable and split security peripherals are set to be secure, with secure DMA where present.

Secure code can access both secure peripherals and non-secure peripherals.

The nRF9160 does not support runtime security configuration of peripherals. It is thus, advisable that all security settings on peripherals are set during boot time. Doing so will ensure the desired system security configuration is deployed simultaneously system-wide.

6.15.4.1 Peripherals with split security

Peripherals with split security are defined to handle use-cases when both secure and non-secure code needs to control the same resource.

When peripherals with split security have their security attribute set to non-secure, access to specific registers and bitfields within some registers is dependent on the security attribute of the bus transfer. For example, some registers will not be accessible for a non-secure transfer.

When peripherals with split security have their security attribute set to secure, then only secure transfers can access their registers.

See [Instantiation](#page-23-0) on page 24 for an overview of split security peripherals. Respective peripheral chapters explain the specific security behavior of each peripheral.

6.15.4.2 Peripheral address mapping

Peripherals that have non-secure security mapping have their address starting with 0x4XXX_XXXX. Peripherals that have secure security mapping have their address starting with 0x5XXX_XXXX.

Peripherals with a user-selectable security mapping are available at an address starting with:

- 0x4XXX_XXXX, if the peripheral security attribute is set to non-secure
- 0x5XXX_XXXX, if the peripheral security attribute is set to secure

Note: Accesses to the 0x4XXX_XXXX address range from secure or non-secure code for a peripheral marked as secure will result in a bus-error.

Secure code accessing the 0x5XXX_XXXX address range of a peripheral marked as non-secure will also result in a bus-error.

Peripherals with a split security mapping are available at an address starting with:

- Ox4XXX XXXX for non-secure access and 0x5XXX XXXX for secure access, if the peripheral security attribute is set to non-secure
	- Secure registers in the 0x4XXX XXXX range are not visible for secure or non-secure code, and an attempt to access such a register will result in write-ignore, read-as-zero behavior
	- Secure code can access both non-secure and secure registers in the 0x5XXX_XXXX range
- 0x5XXX_XXXX, if the peripheral security attribute is set to secure

Any attempt to access the 0x5000_0000-0x5FFF_FFFF address range from non-secure code will be ignored and generate a SecureFault exception.

The table below illustrates the address mapping for the three type of peripherals in all possible configurations

Table 82: Peripheral's address mapping in relation to its security-features and configuration

6.15.4.3 Special considerations for peripherals with DMA master

Peripherals containing a DMA master can be configured so the security attribute of the DMA transfers is different from the security attribute of the peripheral itself. This allows a secure peripheral to do nonsecure data transfers to or from the system memories.

The following conditions must be met:

- The DMA field of [PERIPHID\[n\].PERM](#page-279-0).SECURITYMAPPING should read as "SeparateAttribute"
- The peripheral itself should be secure ([PERIPHID\[n\].PERM](#page-279-0).SECATTR == 1)

Then it is possible to select the security attribute of the DMA transfers using the field DMASEC [\(PERIPHID\[n\].PERM.](#page-279-0)DMASEC == Secure and [PERIPHID\[n\].PERM.](#page-279-0)DMASEC == NonSecure) in [PERIPHID\[n\].PERM.](#page-279-0)

6.15.4.4 Peripheral access error reporting

Peripherals send error reports once access violation is detected.

The following will happen if the logic controlled by the SPU detects an access violation on one of the peripherals:

- The faulty transfer will be blocked
- In case of a read transfer, the bus will be driven to zero

- Feedback is sent to the master through specific bus error signals, if this is supported by the master. If the master is a processor supporting ARM TrustZone for Cortex-M, a SecureFault exception will be generated for security related errors.
- The PERIPHACCERR event will be triggered

6.15.5 Pin access control

Access to device pins can be controlled by the SPU. A pin can be declared as secure so that only secure peripherals or secure code can access it. Pins declared as non-secure can be accessed by both secure and non-secure peripherals or code.

The security attribute of each pin can be individually configured in SPU's [GPIOPORT\[n\].PERM](#page-276-2) register. When the secure attribute is set for a pin, only peripherals that have the secure attribute set will be able to read the value of the pin or change it.

Peripherals can select the pin(s) they need access to through their PSEL register(s). If a peripheral has its attribute set to non-secure, but one of its PSEL registers selects a pin with the attribute set to secure, the SPU controlled logic will ensure that the pin selection is not propagated. In addition, the pin value will always be read as zero, to prevent a non-secure peripheral from obtaining a value from a secure pin. Whereas access to other pins with attribute set as non-secure will not be blocked.

Pins can be assigned to other domains than the application domain by changing the MCUSEL value in the GPIO PIN_CNF[n] register. Domains that do not have a pin assigned to them can neither control that pin nor read its status. Any pin configuration set in a domain that doesn't have ownership of that pin will not take effect until the MCUSEL is updated to assign that pin to the domain. Within each domain, pin access is controlled by that domain's local security configuration and peripheral PSEL registers. This is illustrated in the following figure:

Note: The SPU setting will still count when the APP domain accesses its local GPIO peripheral, as local registers are still writable even though MCUSEL is set to a different domain. Any changes in the APP GPIO peripheral done to a GPIO controlled by another domain will not affect the GPIO pad until MCUSEL is changed to APP.

Figure 85: Pin access for domains other than the application domain

6.15.6 DPPI access control

Access to DPPI channels can be restricted. A channel can be declared as secure so that only secure peripherals can access it.

The security attribute of a DPPI channel is configured in [DPPI\[n\].PERM \(n=0..0\)](#page-275-0) on page 276. When the secure attribute is set for a channel, only peripherals that have the secure attribute set will be able to publish events to this channel or subscribe to this channel to receive tasks.

The DPPI controller peripheral (DPPIC) is a split security peripheral, i.e., its security behavior depends on the security attributes of both the DPPIC and the accessing party. See [Special considerations regarding the](#page-268-0) [DPPIC configuration registers](#page-268-0) on page 269 for more information about the DPPIC security behavior.

If a non-secure peripheral wants to publish an event on a secure DPPI channel, the channel will ignore the event. If a non-secure peripheral subscribes to a secure DPPI channel, it will not receive any events from this channel. The following figure illustrates the principle of operation of the security logic for a subscribed channel:

Figure 86: Subscribed channel security concept

No error reporting mechanism is associated with the DPPI access control logic.

6.15.6.1 Special considerations regarding the DPPIC configuration registers

DPPI channels can be enabled, disabled and grouped through the DPPI controller (DPPIC). The DPPIC is a split-security peripheral, and handles both secure and non-secure accesses.

A non-secure peripheral access will only be able to configure and control DPPI channels defined as non-secure in SPU's [DPPI\[n\].PERM](#page-275-0) register(s). A secure peripheral access can control all DPPI channels, independently of the configuration in the [DPPI\[n\].PERM](#page-275-0) register(s).

The DPPIC allows the creation of group of channels to be able to enable or disable all channels within a group simultaneously. The security attribute of a group of channels (secure or non-secure) is defined as follows:

- If all channels (enabled or not) in the group are non-secure, then the group is considered non-secure
- If at least one of the channels (enabled or not) in the group is secure, then the group is considered secure

A non-secure access to a DPPIC register, or a bitfield controlling a channel marked as secure in [DPPI\[n\].PERM](#page-275-0) register(s), will be ignored:

• Write accesses will have no effect

• Read will always return a zero value

No exceptions are thrown when a non-secure access targets a register or bitfield controlling a secure channel. For example, if the bit *i* is set in the [DPPI\[n\].PERM](#page-275-0) register (declaring the DPPI channel *i* as secure), then:

- Non-secure write accesses to registers CHEN, CHENSET and CHENCLR will not be able to write to bit *i* of those registers
- Non-secure write accesses to registers TASK_CHG[*j*].EN and TASK_CHG[*j*].DIS will be ignored if the channel group *j* contains at least one channel defined as secure (it can be the channel *i* itself or any channel declared as secured)
- Non-secure read accesses to registers CHEN, CHENSET and CHENCLR will always read zero for the bit at position *i*

For the channel configuration registers (DPPIC.CHG[n]), access from non-secure code is only possible if the included channels are all non-secure, whether the channels are enabled or not. If a DPPIC.CHG[*g*] register included one or more secure channels, then the group *g*is considered as secure and only a secure transfer can read or write DPPIC.CHG[*g*]. A non-secure write will be ignored and a non-secure read will return zero.

The DPPIC can subscribe to secure or non-secure channels through SUBSCRIBE_CHG[n] registers in order to trigger task for enabling or disabling groups of channels. But an event from a non-secure channel will be ignored if the group subscribing to this channel is secure. An event from a secure channel can trigger both secure and non-secure tasks.

6.15.7 External domain access control

Other domains with their own CPUs can access peripherals, flash and RAM memories. The SPU allows controlling accesses from those bus masters.

The external domains can access application MCU memories and peripherals. External domains are assigned security attributes as described in register EXTDOMAIN[n].PERM.

Table 83: Register mapping for external domains

The figure below illustrates how the security control units are used to assign security attributes to transfers initiated by the external domains:

Figure 87: Access control from external domains

6.15.8 TrustZone for Cortex-M ID allocation

Flash and RAM regions, as well as non-secure and secure peripherals, are assigned unique TrustZone IDs.

Note: TrustZone ID should not be confounded with the peripheral ID used to identify peripherals.

The table below shows the TrustZone ID allocation:

Table 84: TrustZone ID allocation

6.15.9 Registers

Table 86: Register overview

6.15.9.1 EVENTS_RAMACCERR

Address offset: 0x100

A security violation has been detected for the RAM memory space

6.15.9.2 EVENTS_FLASHACCERR

Address offset: 0x104

A security violation has been detected for the flash memory space

6.15.9.3 EVENTS_PERIPHACCERR

Address offset: 0x108

A security violation has been detected on one or several peripherals

6.15.9.4 PUBLISH_RAMACCERR

Address offset: 0x180

Publish configuration for event [RAMACCERR](#page-271-0)

6.15.9.5 PUBLISH_FLASHACCERR

Address offset: 0x184

Publish configuration for event [FLASHACCERR](#page-271-1)

6.15.9.6 PUBLISH_PERIPHACCERR

Address offset: 0x188

Publish configuration for event [PERIPHACCERR](#page-272-0)

6.15.9.7 INTEN

Address offset: 0x300

Enable or disable interrupt

6.15.9.8 INTENSET

Address offset: 0x304

Enable interrupt

6.15.9.9 INTENCLR

Disable interrupt

6.15.9.10 CAP

Address offset: 0x400

Show implemented features for the current device

6.15.9.11 EXTDOMAIN[n].PERM (n=0..0)

Address offset: 0x440 + (n × 0x4)

Access for bus access generated from the external domain n

List capabilities of the external domain n

6.15.9.12 DPPI[n].PERM (n=0..0)

Address offset: 0x480 + (n × 0x8)

Select between secure and non-secure attribute for the DPPI channels.

6.15.9.13 DPPI[n].LOCK (n=0..0)

Address offset: 0x484 + (n × 0x8)

Prevent further modification of the corresponding PERM register

6.15.9.14 GPIOPORT[n].PERM (n=0..0) (Retained)

Address offset: 0x4C0 + (n × 0x8)

Select between secure and non-secure attribute for pins 0 to 31 of port n.

This register is retained.

6.15.9.15 GPIOPORT[n].LOCK (n=0..0)

Address offset: 0x4C4 + (n × 0x8)

Prevent further modification of the corresponding PERM register

6.15.9.16 FLASHNSC[n].REGION (n=0..1)

Address offset: 0x500 + (n × 0x8)

Define which flash region can contain the non-secure callable (NSC) region n

6.15.9.17 FLASHNSC[n].SIZE (n=0..1)

Address offset: 0x504 + (n × 0x8)

Define the size of the non-secure callable (NSC) region n

6.15.9.18 RAMNSC[n].REGION (n=0..1)

Address offset: 0x540 + (n × 0x8)

Define which RAM region can contain the non-secure callable (NSC) region n

6.15.9.19 RAMNSC[n].SIZE (n=0..1)

Address offset: 0x544 + (n × 0x8)

Define the size of the non-secure callable (NSC) region n

6.15.9.20 FLASHREGION[n].PERM (n=0..31)

Address offset: 0x600 + (n × 0x4)

Access permissions for flash region n

6.15.9.21 RAMREGION[n].PERM (n=0..31)

Address offset: 0x700 + (n × 0x4)

Access permissions for RAM region n

6.15.9.22 PERIPHID[n].PERM (n=0..66)

Address offset: 0x800 + (n × 0x4)

List capabilities and access permissions for the peripheral with ID n

Note: Reset values are unique per peripheral instantation. Please refer to the peripheral instantiation table. Entries not listed in the instantiation table are undefined.

6.16 TIMER — Timer/counter

This peripheral is a general purpose timer designed to keep track of time in user-selective time intervals, it can operate in two modes: timer and counter.

Figure 88: Block schematic for timer/counter

The timer/counter runs on the high-frequency clock source (HFCLK) and includes a four-bit (1/2X) prescaler that can divide the timer input clock from the HFCLK controller. Clock source selection between PCLK16M and PCLK1M is automatic according to TIMER base frequency set by the prescaler. The TIMER base frequency is always given as 16 MHz divided by the prescaler value.

The PPI system allows a TIMER event to trigger a task of any other system peripheral of the device. The PPI system also enables the TIMER task/event features to generate periodic output and PWM signals to any GPIO. The number of input/outputs used at the same time is limited by the number of GPIOTE channels.

TIMER can operate in two modes: Timer mode and Counter mode. In both modes, TIMER is started by triggering the START task, and stopped by triggering the STOP task. After the timer is stopped the timer can resume timing/counting by triggering the START task again. When timing/counting is resumed, the timer will continue from the value it had prior to being stopped.

In Timer mode, the TIMER's internal Counter register is incremented by one for every tick of the timer frequency f_{TIMER} as illustrated in [Block schematic for timer/counter](#page-280-0) on page 281. The timer frequency is derived from PCLK16M as shown in the following example, using the values specified in the PRESCALER register.

```
f_{\text{TIMER}} = 16 MHz / (2<sup>PRESCALER</sup>)
```
When $f_{TIMER} \leq 1$ MHz, TIMER will use PCLK1M instead of PCLK16M for reduced power consumption.

In counter mode, the TIMER's internal Counter register is incremented by one each time the COUNT task is triggered, meaning the timer frequency and the prescaler are not utilized in counter mode. Similarly, the COUNT task has no effect in Timer mode.

The TIMER's maximum value is configured by changing the bit-width of the timer in register [BITMODE](#page-288-0) on page 289.

[PRESCALER](#page-288-1) on page 289 and [BITMODE](#page-288-0) on page 289 must only be updated when the timer is stopped. If these registers are updated while the timer is started, unpredictable behavior may occur.

When the timer is incremented beyond its maximum value, the Counter register will overflow and the timer will automatically start over from zero.

The Counter register can be cleared by triggering the CLEAR task. This will explicitly set the internal value to zero.

TIMER implements multiple capture/compare registers.

Independent of prescaler setting, the accuracy of TIMER is equivalent to one tick of the timer frequency f_{TIMFR} as illustrated in [Block schematic for timer/counter](#page-280-0) on page 281.

6.16.1 Capture

TIMER implements one capture task for every available capture/compare register.

Every time the CAPTURE[n] task is triggered, the Counter value is copied to the CC[n] register.

6.16.2 Compare

TIMER implements one COMPARE event for every available capture/compare register.

A COMPARE event is generated when the Counter is incremented and then becomes equal to the value specified in one of the capture compare registers. When the Counter value becomes equal to the value specified in a capture compare register CC[n], the corresponding compare event COMPARE[n] is generated.

[BITMODE](#page-288-0) on page 289 specifies how many bits of the Counter register and the capture/compare register that are used when the comparison is performed. Other bits will be ignored.

The COMPARE event can be configured to operate in one-shot mode by configuring the corresponding ONESHOTEN[n] register. COMPARE[n] event is generated the first time the Counter matches CC[n] after CC[n] has been written.

6.16.3 Task delays

After TIMER is started, the CLEAR, COUNT, and STOP tasks are guaranteed to take effect within one clock cycle of the PCLK16M.

6.16.4 Task priority

If the START task and the STOP task are triggered at the same time, meaning within the same period of PCLK16M, the STOP task will be prioritized.

If one or more of the CAPTURE tasks and the CLEAR task is triggered at the same time, that is, within the same period of PCLK16M, the CLEAR task will be prioritized. This means that the CC register for the relevant CAPTURE task will be set to 0.

6.16.5 Registers

Table 87: Instances

Table 88: Register overview

6.16.5.1 TASKS_START

Address offset: 0x000

Start Timer

6.16.5.2 TASKS_STOP

Address offset: 0x004

Stop Timer

6.16.5.3 TASKS_COUNT

Address offset: 0x008

Increment Timer (Counter mode only)

6.16.5.4 TASKS_CLEAR

Address offset: 0x00C

Clear time

6.16.5.5 TASKS_SHUTDOWN (Deprecated)

Address offset: 0x010

Shut down timer

This register is deprecated.

6.16.5.6 TASKS_CAPTURE[n] (n=0..5)

Address offset: 0x040 + (n × 0x4)

Capture Timer value to CC[n] register

6.16.5.7 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-282-0)

6.16.5.8 SUBSCRIBE_STOP

Address offset: 0x084

Subscribe configuration for task [STOP](#page-283-0)

6.16.5.9 SUBSCRIBE_COUNT

Address offset: 0x088

Subscribe configuration for task [COUNT](#page-283-1)

6.16.5.10 SUBSCRIBE_CLEAR

Address offset: 0x08C

Subscribe configuration for task [CLEAR](#page-283-2)

6.16.5.11 SUBSCRIBE_SHUTDOWN (Deprecated)

Address offset: 0x090

Subscribe configuration for task [SHUTDOWN](#page-283-3)

This register is deprecated.

6.16.5.12 SUBSCRIBE_CAPTURE[n] (n=0..5)

Address offset: 0x0C0 + (n × 0x4)

Subscribe configuration for task [CAPTURE\[n\]](#page-284-0)

6.16.5.13 EVENTS_COMPARE[n] (n=0..5)

Address offset: 0x140 + (n × 0x4)

Compare event on CC[n] match

6.16.5.14 PUBLISH_COMPARE[n] (n=0..5)

Address offset: 0x1C0 + (n × 0x4)

Publish configuration for event [COMPARE\[n\]](#page-286-0)

6.16.5.15 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.16.5.16 INTENSET

Address offset: 0x304

Enable interrupt

6.16.5.17 INTENCLR

Address offset: 0x308

Disable interrupt

6.16.5.18 MODE

Address offset: 0x504

Timer mode selection

6.16.5.19 BITMODE

Address offset: 0x508

Configure the number of bits used by the TIMER

6.16.5.20 PRESCALER

Address offset: 0x510

Timer prescaler register

6.16.5.21 ONESHOTEN[n] (n=0..5)

Address offset: 0x514 + (n × 0x4)

Enable one-shot operation for Capture/Compare channel n

6.16.5.22 CC[n] (n=0..5)

Address offset: $0x540 + (n \times 0x4)$

Capture/Compare register n

Only the number of bits indicated by BITMODE will be used by the TIMER.

6.16.6 Electrical specification

6.17 TWIM 1^2 C compatible two-wire interface master with EasyDMA

TWI master with EasyDMA (TWIM) is a two-wire half-duplex master which can communicate with multiple slave devices connected to the same bus.

Listed here are the main features for TWIM:

- \cdot I^2C compatible
- Supported baud rates: 100, 250, 400 kbps
- Support for clock stretching (non I^2C compliant)
- EasyDMA

The two-wire interface can communicate with a bi-directional wired-AND bus with two lines (SCL, SDA). The protocol makes it possible to interconnect up to 127 individually addressable devices. TWIM is not compatible with CBUS.

The GPIOs used for each two-wire interface line can be chosen from any GPIO on the device and are independently configurable. This enables great flexibility in device pinout and efficient use of board space and signal routing.

Figure 89: TWI master with EasyDMA

A typical TWI setup consists of one master and one or more slaves. For an example, see the following figure. This TWIM is only able to operate as a single master on the TWI bus. Multi-master bus configuration is not supported.

Figure 90: A typical TWI setup comprising one master and three slaves

This TWI master supports clock stretching performed by the slaves. The SCK pulse following a stretched clock cycle may be shorter than specified by the I2C specification.

The TWI master is started by triggering the STARTTX or STARTRX tasks, and stopped by triggering the STOP task. The TWI master will generate a STOPPED event when it has stopped following a STOP task.

After the TWI master is started, the STARTTX or STARTRX tasks should not be triggered again until the TWI master has issued a LASTRX, LASTTX, or STOPPED event.

The TWI master can be suspended using the SUSPEND task, this can be used when using the TWI master in a low priority interrupt context. When the TWIM enters suspend state, will automatically issue a SUSPENDED event while performing a continuous clock stretching until it is instructed to resume operation via a RESUME task. The TWI master cannot be stopped while it is suspended, thus the STOP task has to be issued after the TWI master has been resumed.

Note: Any ongoing byte transfer will be allowed to complete before the suspend is enforced. A SUSPEND task has no effect unless the TWI master is actively involved in a transfer.

If a NACK is clocked in from the slave, the TWI master will generate an ERROR event.

6.17.1 Shared resources

The TWI master shares registers and other resources with other peripherals that have the same ID as the TWI master. Therefore, you must disable all peripherals that have the same ID as the TWI master before the TWI master can be configured and used.

Disabling a peripheral that has the same ID as the TWI master will not reset any of the registers that are shared with the TWI master. It is therefore important to configure all relevant registers explicitly to secure that the TWI master operates correctly.

The Instantiation table in [Instantiation](#page-23-0) on page 24 shows which peripherals have the same ID as the TWI.

6.17.2 EasyDMA

The TWIM implements EasyDMA for accessing RAM without CPU involvement.

The TWIM peripheral implements the EasyDMA channels found in the following table.

Table 89: TWIM EasyDMA Channels

For detailed information regarding the use of EasyDMA, see [EasyDMA](#page-44-0) on page 45.

The .PTR and .MAXCNT registers are double-buffered. They can be updated and prepared for the next RX/ TX transmission immediately after having received the RXSTARTED/TXSTARTED event.

The STOPPED event indicates that EasyDMA has finished accessing the buffer in RAM.

6.17.3 Master write sequence

A TWI master write sequence is started by triggering the STARTTX task. After the STARTTX task has been triggered, the TWI master will generate a start condition on the TWI bus, followed by clocking out the address and the READ/WRITE bit set to 0 (WRITE=0, READ=1).

The address must match the address of the slave device that the master wants to write to. The READ/ WRITE bit is followed by an ACK/NACK bit (ACK=0 or NACK=1) generated by the slave.

After receiving the ACK bit, the TWI master will clock out the data bytes found in the transmit buffer located in RAM at the address specified in the TXD.PTR register. Each byte clocked out from the master will be followed by an ACK/NACK bit clocked in from the slave.

A typical TWI master write sequence is shown in the following figure. Occurrence 2 in the figure illustrates clock stretching performed by the TWI master following a SUSPEND task.

A SUSPENDED event indicates that the SUSPEND task has taken effect. This event can be used to synchronize the software.

The TWI master will generate a LASTTX event when it starts to transmit the last byte, this is shown in the following figure.

Figure 91: TWI master writing data to a slave

The TWI master is stopped by triggering the STOP task. This task should be triggered during the transmission of the last byte to secure that the TWI master will stop as fast as possible after sending the last byte. The shortcut between LASTTX and STOP can alternatively be used to accomplish this.

Note: The TWI master does not stop by itself when the entire RAM buffer has been sent, or when an error occurs. The STOP task must be issued, through the use of a local or PPI shortcut, or in software as part of the error handler.

6.17.4 Master read sequence

A TWI master read sequence is started by triggering the STARTRX task. After the STARTRX task has been triggered, the TWI master will generate a start condition on the TWI bus, followed by clocking out the address and the READ/WRITE bit set to 1 (WRITE = 0, READ = 1). The address must match the address of the slave device that the master wants to read from. The READ/WRITE bit is followed by an ACK/NACK bit $(ACK=0 \text{ or } NACK = 1)$ generated by the slave.

After sending the ACK bit, the TWI slave will send data to the master using the clock generated by the master.

Data received will be stored in RAM at the address specified in the RXD.PTR register. The TWI master will generate an ACK after all but the last byte have been received from the slave. The TWI master will generate a NACK after the last byte received to indicate that the read sequence shall stop.

A typical TWI master read sequence is illustrated in [The TWI master reading data from a slave](#page-293-0) on page 294. Occurrence 2 in the figure illustrates clock stretching performed by the TWI master following a SUSPEND task.

A SUSPENDED event indicates that the SUSPEND task has taken effect. This event can be used to synchronize the software.

The TWI master will generate a LASTRX event when it is ready to receive the last byte, as shown in [The](#page-293-0) [TWI master reading data from a slave](#page-293-0) on page 294. If RXD.MAXCNT > 1, the LASTRX event is generated after sending the ACK of the previously received byte. If RXD.MAXCNT = 1, the LASTRX event is generated after receiving the ACK following the address and READ bit.

The TWI master is stopped by triggering the STOP task. This task must be triggered before the NACK bit is supposed to be transmitted. The STOP task can be triggered at any time during the reception of the last byte. It is recommended to use the shortcut between LASTRX and STOP to accomplish this.

The TWI master does not stop by itself when the RAM buffer is full, or when an error occurs. The STOP task must be issued, through the use of a local or PPI shortcut, or in software as part of the error handler.

The TWI master cannot be stopped while suspended, so the STOP task must be issued after the TWI master has been resumed.

Figure 92: The TWI master reading data from a slave

6.17.5 Master repeated start sequence

A typical repeated start sequence is one in which the TWI master writes two bytes to the slave followed by reading four bytes from the slave. This example uses shortcuts to perform the simplest type of repeated start sequence, i.e. one write followed by one read. The same approach can be used to perform a repeated start sequence where the sequence is read followed by write.

The following figure shows an example of a repeated start sequence where the TWI master writes two bytes followed by reading four bytes from the slave.

Figure 93: Master repeated start sequence

If a more complex repeated start sequence is needed, and the TWI firmware drive is serviced in a low priority interrupt, it may be necessary to use the SUSPEND task and SUSPENDED event to guarantee that the correct tasks are generated at the correct time. A double repeated start sequence using the SUSPEND task to secure safe operation in low priority interrupts is shown in the following figure.

Figure 94: Double repeated start sequence

6.17.6 Low power

When putting the system in low power and the peripheral is not needed, lowest possible power consumption is achieved by stopping, and then disabling the peripheral.

When the STOP task is sent, the software shall wait until the STOPPED event is received as a response before disabling the peripheral through the ENABLE register. If the peripheral is already stopped, the STOP task is not required.

6.17.7 Master mode pin configuration

The SCL and SDA signals associated with the TWI master are mapped to physical pins according to the configuration specified in the PSEL.SCL and PSEL.SDA registers respectively.

The PSEL.SCL and PSEL.SDA registers and their configurations are only used as long as the TWI master is enabled, and retained only as long as the device is in ON mode. When the peripheral is disabled, the pins will behave as regular GPIOs, and use the configuration in their respective OUT bit field and PIN_CNF[n] register. PSEL.SCL, PSEL.SDA must only be configured when the TWI master is disabled.

To secure correct signal levels on the pins used by the TWI master when the system is in OFF mode, and when the TWI master is disabled, these pins must be configured in the GPIO peripheral as described in the following table.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

Table 90: GPIO configuration before enabling peripheral

6.17.8 Registers

Table 91: Instances

Table 92: Register overview

6.17.8.1 TASKS_STARTRX

Address offset: 0x000

Start TWI receive sequence

6.17.8.2 TASKS_STARTTX

Address offset: 0x008

Start TWI transmit sequence

6.17.8.3 TASKS_STOP

Address offset: 0x014

Stop TWI transaction. Must be issued while the TWI master is not suspended.

6.17.8.4 TASKS_SUSPEND

Address offset: 0x01C

Suspend TWI transaction

6.17.8.5 TASKS_RESUME

Address offset: 0x020

Resume TWI transaction

6.17.8.6 SUBSCRIBE_STARTRX

Address offset: 0x080

Subscribe configuration for task [STARTRX](#page-296-0)

6.17.8.7 SUBSCRIBE_STARTTX

Address offset: 0x088

Subscribe configuration for task [STARTTX](#page-296-1)

6.17.8.8 SUBSCRIBE_STOP

Address offset: 0x094

Subscribe configuration for task [STOP](#page-296-2)

6.17.8.9 SUBSCRIBE_SUSPEND

Address offset: 0x09C

Subscribe configuration for task [SUSPEND](#page-296-3)

6.17.8.10 SUBSCRIBE_RESUME

Address offset: 0x0A0

Subscribe configuration for task [RESUME](#page-297-0)

6.17.8.11 EVENTS_STOPPED

Address offset: 0x104

TWI stopped

6.17.8.12 EVENTS_ERROR

Address offset: 0x124

TWI error

6.17.8.13 EVENTS_SUSPENDED

Address offset: 0x148

SUSPEND task has been issued, TWI traffic is now suspended.

6.17.8.14 EVENTS_RXSTARTED

Address offset: 0x14C

Receive sequence started

6.17.8.15 EVENTS_TXSTARTED

Address offset: 0x150

Transmit sequence started

6.17.8.16 EVENTS_LASTRX

Address offset: 0x15C

Byte boundary, starting to receive the last byte

6.17.8.17 EVENTS_LASTTX

Address offset: 0x160

Byte boundary, starting to transmit the last byte

6.17.8.18 PUBLISH_STOPPED

Address offset: 0x184

Publish configuration for event [STOPPED](#page-298-2)

6.17.8.19 PUBLISH_ERROR

Address offset: 0x1A4

Publish configuration for event [ERROR](#page-299-0)

6.17.8.20 PUBLISH_SUSPENDED

Address offset: 0x1C8

Publish configuration for event [SUSPENDED](#page-299-1)

6.17.8.21 PUBLISH_RXSTARTED

Address offset: 0x1CC

Publish configuration for event [RXSTARTED](#page-299-2)

6.17.8.22 PUBLISH_TXSTARTED

Address offset: 0x1D0

Publish configuration for event [TXSTARTED](#page-299-3)

6.17.8.23 PUBLISH_LASTRX

Address offset: 0x1DC

Publish configuration for event [LASTRX](#page-300-0)

6.17.8.24 PUBLISH_LASTTX

Address offset: 0x1E0

Publish configuration for event [LASTTX](#page-300-1)

6.17.8.25 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.17.8.26 INTEN

Address offset: 0x300

Enable or disable interrupt

6.17.8.27 INTENSET

Address offset: 0x304

Enable interrupt

6.17.8.28 INTENCLR

Address offset: 0x308

Disable interrupt

6.17.8.29 ERRORSRC

Address offset: 0x4C4

Error source

6.17.8.30 ENABLE

Address offset: 0x500

Enable TWIM

6.17.8.31 PSEL.SCL

Address offset: 0x508

Pin select for SCL signal

6.17.8.32 PSEL.SDA

Address offset: 0x50C

Pin select for SDA signal

6.17.8.33 FREQUENCY

Address offset: 0x524

TWI frequency. Accuracy depends on the HFCLK source selected.

6.17.8.34 RXD.PTR

Address offset: 0x534

Data pointer

See the memory chapter for details about which memories are available for EasyDMA.

6.17.8.35 RXD.MAXCNT

Address offset: 0x538

Maximum number of bytes in receive buffer

6.17.8.36 RXD.AMOUNT

Address offset: 0x53C

Number of bytes transferred in the last transaction

6.17.8.37 RXD.LIST

Address offset: 0x540

EasyDMA list type

6.17.8.38 TXD.PTR

Address offset: 0x544

Data pointer

See the memory chapter for details about which memories are available for EasyDMA.

6.17.8.39 TXD.MAXCNT

Address offset: 0x548

Maximum number of bytes in transmit buffer

6.17.8.40 TXD.AMOUNT

Address offset: 0x54C

Number of bytes transferred in the last transaction

6.17.8.41 TXD.LIST

Address offset: 0x550

EasyDMA list type

6.17.8.42 ADDRESS

Address offset: 0x588

Address used in the TWI transfer

6.17.9 Electrical specification

6.17.9.1 TWIM interface electrical specifications

6.17.9.2 Two Wire Interface Master (TWIM) timing specifications

Symbol	Description	Min.	Typ.	Units Max.	
t _{twim, su dat}	Data setup time before positive edge on SCL - all modes	300		ns	
t _{TWIM,HD} DAT	Data hold time after negative edge on SCL - 100, 250 and	500		ns	
	400 kbps				
t _{TWIM,HD} STA,100kbps	TWIM master hold time for START and repeated START	10000		ns	
	condition, 100 kbps				
t _{TWIM,HD_STA,250kbps}	TWIM master hold time for START and repeated START	4000		ns	
	condition, 250 kbps				
t _{TWIM,HD_STA,400kbps}	TWIM master hold time for START and repeated START	2500		ns	
	condition, 400 kbps				
t _{TWIM,SU} STO,100kbps	TWIM master setup time from SCL high to STOP condition,	5000		ns	
	100 kbps				
t _{TWIM,SU_STO,250kbps}	TWIM master setup time from SCL high to STOP condition,	2000		ns	
	250 kbps				
t _{TWIM,SU} STO,400kbps	TWIM master setup time from SCL high to STOP condition,	1250		ns	
	400 kbps				
t _{TWIM,BUF,100kbps}	TWIM master bus free time between STOP and START	5800		ns	
	conditions, 100 kbps				
t _{TWIM,BUF,250kbps}	TWIM master bus free time between STOP and START	2700		ns	
	conditions, 250 kbps				
t _{TWIM,BUF,400kbps}	TWIM master bus free time between STOP and START	2100		ns	
	conditions, 400 kbps				
SCL t HD_STA	t _{su} DAT $1/f_{SCL}$ THD DAT		$t_{\scriptstyle\text{SU_STO}}$	t_{BUF}	
SDA					

Figure 95: TWIM timing diagram, 1 byte transaction

 18 High bit rates or stronger pull-ups may require GPIOs to be set as High Drive, see GPIO $-$ General [purpose input/output](#page-96-0) on page 97 for more details.

6.17.10 Pullup resistor

Figure 96: Recommended TWIM pullup value vs. line capacitance

- The I2C specification allows a line capacitance of 400 pF at most.
- The value of internal pullup resistor (R_{PU}) for nRF9160 can be found in GPIO General purpose input/ [output](#page-96-0) on page 97.

6.18 TWIS 1^2 C compatible two-wire interface slave with EasyDMA

TWI slave with EasyDMA (TWIS) is compatible with I^2C operating at 100 kHz and 400 kHz. The TWI transmitter and receiver implement EasyDMA.

Figure 97: TWI slave with EasyDMA

A typical TWI setup consists of one master and one or more slaves. For an example, see the following figure. TWIS is only able to operate with a single master on the TWI bus.

Figure 98: A typical TWI setup comprising one master and three slaves

The following figure shows the TWI slave state machine.

Figure 99: TWI slave state machine

The following table contains descriptions of the symbols used in the state machine.

Symbol	Type	Description
ENABLE	Register	The TWI slave has been enabled via the ENABLE register.
PREPARETX	Task	The TASKS PREPARETX task has been triggered.
STOP	Task	The TASKS STOP task has been triggered.
PREPARERX	Task	The TASKS PREPARERX task has been triggered.
STOPPED	Event	The EVENTS STOPPED event was generated.
RXSTARTED	Event	The EVENTS RXSTARTED event was generated.
TXSTARTED	Event	The EVENTS TXSTARTED event was generated.
TX prepared	Internal	Internal flag indicating that a TASKS PREPARETX task has been triggered. This flag is not visible to the
		user.
RX prepared	Internal	Internal flag indicating that a TASKS PREPARERX task has been triggered. This flag is not visible to the
		user.
Unprepare TX	Internal	Clears the internal 'TX prepared' flag until next TASKS PREPARETX task.
Unprepare RX	Internal	Clears the internal 'RX prepared' flag until next TASKS PREPARERX task.
Stop condition	TWI protocol	A TWI stop condition was detected.
Restart condition	TWI protocol	A TWI restart condition was detected.

Table 93: TWI slave state machine symbols

The TWI slave can perform clock stretching, with the premise that the master is able to support it.

The TWI slave operates in a low power mode while waiting for a TWI master to initiate a transfer. As long as the TWI slave is not addressed, it will remain in this low power mode.

To secure correct behavior of the TWI slave, PSEL.SCL, PSEL.SDA, CONFIG, and the ADDRESS[n] registers must be configured prior to enabling the TWI slave through the ENABLE register. Similarly, changing these settings must be performed while the TWI slave is disabled. Failing to do so may result in unpredictable behavior.

6.18.1 Shared resources

The TWI slave shares registers and other resources with other peripherals that have the same ID as the TWI slave.

Therefore, you must disable all peripherals that have the same ID as the TWI slave before the TWI slave can be configured and used. Disabling a peripheral that has the same ID as the TWI slave will not reset any of the registers that are shared with the TWI slave. It is therefore important to configure all relevant registers explicitly to secure that the TWI slave operates correctly.

The Instantiation table in [Instantiation](#page-23-0) on page 24 shows which peripherals have the same ID as the TWI slave.

6.18.2 EasyDMA

The TWIS implements EasyDMA for accessing RAM without CPU involvement.

The following table shows the Easy DMA channels that the TWIS peripheral implements.

Table 94: TWIS EasyDMA Channels

For detailed information regarding the use of EasyDMA, see [EasyDMA](#page-44-0) on page 45.

The STOPPED event indicates that EasyDMA has finished accessing the buffer in RAM.

6.18.3 TWI slave responding to a read command

Before the TWI slave can respond to a read command, the TWI slave must be configured correctly and enabled via the ENABLE register. When enabled, the TWI slave will be in its IDLE state. .

A read command is started when the TWI master generates a start condition on the TWI bus, followed by clocking out the address and the READ/WRITE bit set to 1 (WRITE=0, READ=1). The READ/WRITE bit is followed by an ACK/NACK bit (ACK=0 or NACK=1) response from the TWI slave.

The TWI slave is able to listen for up to two addresses at the same time. This is configured in the ADDRESS registers and the CONFIG register.

The TWI slave will only acknowledge (ACK) the read command if the address presented by the master matches one of the addresses the slave is configured to listen for. The TWI slave will generate a READ event when it acknowledges the read command.

The TWI slave is only able to detect a read command from the IDLE state.

The TWI slave will set an internal 'TX prepared' flag when the PREPARETX task is triggered.

When the read command is received, the TWI slave will enter the TX state if the internal 'TX prepared' flag is set.

If the internal 'TX prepared' flag is not set when the read command is received, the TWI slave will stretch the master's clock until the PREPARETX task is triggered and the internal 'TX prepared' flag is set.

The TWI slave will generate the TXSTARTED event and clear the 'TX prepared' flag ('unprepare TX') when it enters the TX state. In this state the TWI slave will send the data bytes found in the transmit buffer to the master using the master's clock.

The TWI slave will go back to the IDLE state if the TWI slave receives a restart command when it is in the TX state.

The TWI slave is stopped when it receives the stop condition from the TWI master. A STOPPED event will be generated when the transaction has stopped. The TWI slave will clear the 'TX prepared' flag ('unprepare TX') and go back to the IDLE state when it has stopped.

The transmit buffer is located in RAM at the address specified in the TXD.PTR register. The TWI slave will only be able to send TXD.MAXCNT bytes from the transmit buffer for each transaction. If the TWI master forces the slave to send more than TXD.MAXCNT bytes, the slave will send the byte specified in the ORC register to the master instead. If this happens, an ERROR event will be generated.

The EasyDMA configuration registers, see TXD.PTR etc., are latched when the TXSTARTED event is generated.

The TWI slave can be forced to stop by triggering the STOP task. A STOPPED event will be generated when the TWI slave has stopped. The TWI slave will clear the 'TX prepared' flag and go back to the IDLE state when it has stopped, see also [Terminating an ongoing TWI transaction](#page-316-0) on page 317.

Each byte sent from the slave will be followed by an ACK/NACK bit sent from the master. The TWI master will generate a NACK following the last byte that it wants to receive to tell the slave to release the bus so that the TWI master can generate the stop condition. The TXD.AMOUNT register can be queried after a transaction to see how many bytes were sent.

A typical TWI slave read command response is shown in the following figure. Occurrence 2 in the figure illustrates clock stretching performed by the TWI slave following a SUSPEND task.

Figure 100: The TWI slave responding to a read command

6.18.4 TWI slave responding to a write command

Before the TWI slave can respond to a write command, the TWI slave must be configured correctly and enabled via the ENABLE register. When enabled, the TWI slave will be in its IDLE state.

A write command is started when the TWI master generates a start condition on the TWI bus, followed by clocking out the address and the READ/WRITE bit set to 0 (WRITE=0, READ=1). The READ/WRITE bit is followed by an ACK/NACK bit (ACK=0 or NACK=1) response from the slave.

The TWI slave is able to listen for up to two addresses at the same time. This is configured in the ADDRESS registers and the CONFIG register.

The TWI slave will only acknowledge (ACK) the write command if the address presented by the master matches one of the addresses the slave is configured to listen for. The TWI slave will generate a WRITE event if it acknowledges the write command.

The TWI slave is only able to detect a write command from the IDLE state.

The TWI slave will set an internal 'RX prepared' flag when the PREPARERX task is triggered.

When the write command is received, the TWI slave will enter the RX state if the internal 'RX prepared' flag is set.

If the internal 'RX prepared' flag is not set when the write command is received, the TWI slave will stretch the master's clock until the PREPARERX task is triggered and the internal 'RX prepared' flag is set.

The TWI slave will generate the RXSTARTED event and clear the internal 'RX prepared' flag ('unprepare RX') when it enters the RX state. In this state, the TWI slave will be able to receive the bytes sent by the TWI master.

The TWI slave will go back to the IDLE state if the TWI slave receives a restart command when it is in the RX state.

The TWI slave is stopped when it receives the stop condition from the TWI master. A STOPPED event will be generated when the transaction has stopped. The TWI slave will clear the internal 'RX prepared' flag ('unprepare RX') and go back to the IDLE state when it has stopped.

The receive buffer is located in RAM at the address specified in the RXD.PTR register. The TWI slave will only be able to receive as many bytes as specified in the RXD.MAXCNT register. If the TWI master tries to send more bytes to the slave than it can receive, the extra bytes are discarded and NACKed by the slave. If this happens, an ERROR event will be generated.

The EasyDMA configuration registers, see RXD.PTR etc., are latched when the RXSTARTED event is generated.

The TWI slave can be forced to stop by triggering the STOP task. A STOPPED event will be generated when the TWI slave has stopped. The TWI slave will clear the internal 'RX prepared' flag and go back to the IDLE state when it has stopped, see also [Terminating an ongoing TWI transaction](#page-316-0) on page 317.

The TWI slave will generate an ACK after every byte received from the master. The RXD.AMOUNT register can be queried after a transaction to see how many bytes were received.

A typical TWI slave write command response is show in the following figure. Occurrence 2 in the figure illustrates clock stretching performed by the TWI slave following a SUSPEND task.

Figure 101: The TWI slave responding to a write command

6.18.5 Master repeated start sequence

An example of a repeated start sequence is one in which the TWI master writes two bytes to the slave followed by reading four bytes from the slave.

This is illustrated in the following figure.

In this example, the receiver does not know what the master wants to read in advance. This information is in the first two received bytes of the write in the repeated start sequence. To guarantee that the CPU is able to process the received data before the TWI slave starts to reply to the read command, the SUSPEND task is triggered via a shortcut from the READ event generated when the read command is received. When the CPU has processed the incoming data and prepared the correct data response, the CPU will resume the transaction by triggering the RESUME task.

Figure 102: Repeated start sequence

6.18.6 Terminating an ongoing TWI transaction

In some situations, e.g. if the external TWI master is not responding correctly, it may be required to terminate an ongoing transaction.

This can be achieved by triggering the STOP task. In this situation, a STOPPED event will be generated when the TWI has stopped independent of whether or not a STOP condition has been generated on the TWI bus. The TWI slave will release the bus when it has stopped and go back to its IDLE state.

6.18.7 Low power

When putting the system in low power and the peripheral is not needed, lowest possible power consumption is achieved by stopping, and then disabling the peripheral.

The STOP task may not be always needed (the peripheral might already be stopped), but if it is sent, software shall wait until the STOPPED event was received as a response before disabling the peripheral through the ENABLE register.

6.18.8 Slave mode pin configuration

The SCL and SDA signals associated with the TWI slave are mapped to physical pins according to the configuration specified in the PSEL.SCL and PSEL.SDA registers respectively.

The PSEL.SCL and PSEL.SDA registers and their configurations are only used as long as the TWI slave is enabled, and retained only as long as the device is in ON mode. When the peripheral is disabled, the pins will behave as regular GPIOs, and use the configuration in their respective OUT bit field and PIN_CNF[n] register. PSEL.SCL and PSEL.SDA must only be configured when the TWI slave is disabled.

To secure correct signal levels on the pins used by the TWI slave when the system is in OFF mode, and when the TWI slave is disabled, these pins must be configured in the GPIO peripheral as described in the following table.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

TWI slave signal	TWI slave pin	Direction	Output value	Drive strength
SCL	As specified in PSEL.SCL	Input	Not applicable	SOD1
SDA	As specified in PSEL.SDA	Input	Not applicable	SOD1

Table 95: GPIO configuration before enabling peripheral

6.18.9 Registers

Table 96: Instances

Table 97: Register overview

6.18.9.1 TASKS_STOP

Address offset: 0x014 Stop TWI transaction

6.18.9.2 TASKS_SUSPEND

Address offset: 0x01C

Suspend TWI transaction

6.18.9.3 TASKS_RESUME

Address offset: 0x020

Resume TWI transaction

6.18.9.4 TASKS_PREPARERX

Address offset: 0x030

Prepare the TWI slave to respond to a write command

6.18.9.5 TASKS_PREPARETX

Address offset: 0x034

Prepare the TWI slave to respond to a read command

6.18.9.6 SUBSCRIBE_STOP

Address offset: 0x094

Subscribe configuration for task [STOP](#page-317-0)

6.18.9.7 SUBSCRIBE_SUSPEND

Address offset: 0x09C

Subscribe configuration for task [SUSPEND](#page-318-2)

6.18.9.8 SUBSCRIBE_RESUME

Address offset: 0x0A0

Subscribe configuration for task [RESUME](#page-318-3)

6.18.9.9 SUBSCRIBE_PREPARERX

Address offset: 0x0B0

Subscribe configuration for task [PREPARERX](#page-318-1)

6.18.9.10 SUBSCRIBE_PREPARETX

Address offset: 0x0B4

Subscribe configuration for task [PREPARETX](#page-318-0)

6.18.9.11 EVENTS_STOPPED

Address offset: 0x104

TWI stopped

6.18.9.12 EVENTS_ERROR

Address offset: 0x124

TWI error

6.18.9.13 EVENTS_RXSTARTED

Address offset: 0x14C

Receive sequence started

6.18.9.14 EVENTS_TXSTARTED

Address offset: 0x150

Transmit sequence started

6.18.9.15 EVENTS_WRITE

Address offset: 0x164

Write command received

6.18.9.16 EVENTS_READ

Address offset: 0x168

Read command received

6.18.9.17 PUBLISH_STOPPED

Address offset: 0x184

Publish configuration for event [STOPPED](#page-320-0)

6.18.9.18 PUBLISH_ERROR

Address offset: 0x1A4

Publish configuration for event [ERROR](#page-320-2)

6.18.9.19 PUBLISH_RXSTARTED

Address offset: 0x1CC

Publish configuration for event [RXSTARTED](#page-321-0)

6.18.9.20 PUBLISH_TXSTARTED

Address offset: 0x1D0

Publish configuration for event [TXSTARTED](#page-321-1)

6.18.9.21 PUBLISH_WRITE

Address offset: 0x1E4

Publish configuration for event [WRITE](#page-321-2)

6.18.9.22 PUBLISH_READ

Address offset: 0x1E8

Publish configuration for event [READ](#page-321-3)

6.18.9.23 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.18.9.24 INTEN

Address offset: 0x300

Enable or disable interrupt

6.18.9.25 INTENSET

Address offset: 0x304

Enable interrupt

6.18.9.26 INTENCLR

Address offset: 0x308

Disable interrupt

6.18.9.27 ERRORSRC

Address offset: 0x4D0

Error source

6.18.9.28 MATCH

Address offset: 0x4D4

Status register indicating which address had a match

6.18.9.29 ENABLE

Address offset: 0x500

Enable TWIS

6.18.9.30 PSEL.SCL

Address offset: 0x508

Pin select for SCL signal

6.18.9.31 PSEL.SDA

Address offset: 0x50C

Pin select for SDA signal

6.18.9.32 RXD.PTR

Address offset: 0x534

RXD Data pointer

See the memory chapter for details about which memories are available for EasyDMA.

6.18.9.33 RXD.MAXCNT

Address offset: 0x538

Maximum number of bytes in RXD buffer

6.18.9.34 RXD.AMOUNT

Address offset: 0x53C

Number of bytes transferred in the last RXD transaction

6.18.9.35 RXD.LIST

Address offset: 0x540

EasyDMA list type

6.18.9.36 TXD.PTR

Address offset: 0x544

TXD Data pointer

available for EasyDMA.

6.18.9.37 TXD.MAXCNT

Address offset: 0x548

Maximum number of bytes in TXD buffer

6.18.9.38 TXD.AMOUNT

Address offset: 0x54C

Number of bytes transferred in the last TXD transaction

6.18.9.39 TXD.LIST

EasyDMA list type

6.18.9.40 ADDRESS[n] (n=0..1)

```
Address offset: 0x588 + (n \times 0x4)
```
TWI slave address n

6.18.9.41 CONFIG

Address offset: 0x594

Configuration register for the address match mechanism

6.18.9.42 ORC

Address offset: 0x5C0

Over-read character. Character sent out in case of an over-read of the transmit buffer.

6.18.10 Electrical specification

6.18.10.1 TWIS slave timing specifications

Symbol	Description	Min.	Typ.	Max.	Units
f _{TWIS,SCL}	Bit rates for TWIS ¹⁹	100		400	kbps
t _{TWIS, START}	Time from PREPARERX/PREPARETX task to ready to receive/		1.5		μ s
	transmit				
t _{TWIS, SU DAT}	Data setup time before positive edge on SCL - all modes	300			ns
t _{TWIS, HD} DAT	Data hold time after negative edge on SCL - all modes	500			ns
t _{TWIS,HD_STA,100kbps}	TWI slave hold time from for START condition (SDA low to	5200			ns
	SCL low), 100 kbps				
t _{TWIS,HD} STA,400kbps	TWI slave hold time from for START condition (SDA low to	1300			ns
	SCL low), 400 kbps				
trwis, SU STO, 100kbps	TWI slave setup time from SCL high to STOP condition, 100	5200			ns
	kbps				
trwis, SU STO, 400kbps	TWI slave setup time from SCL high to STOP condition, 400	1300			ns
	kbps				
t _{TWIS,BUF,100kbps}	TWI slave bus free time between STOP and START		4700		ns
	conditions, 100 kbps				
t _{TWIS,BUF,400kbps}	TWI slave bus free time between STOP and START		1300		ns
	conditions, 400 kbps				
SCL					
THD STA	t _{SU_DAT} $1/f_{SCL}$ thd_dat		t _{su_sto}	IBUF	

Figure 103: TWIS timing diagram, 1 byte transaction

6.19 UARTE — Universal asynchronous receiver/ transmitter with EasyDMA

The Universal asynchronous receiver/transmitter with EasyDMA (UARTE) offers fast, full-duplex, asynchronous serial communication with built-in flow control (CTS, RTS) support in hardware at a rate up to 1 Mbps, and EasyDMA data transfer from/to RAM.

Listed here are the main features for UARTE:

- Full-duplex operation
- Automatic hardware flow control
- Optional even parity bit checking and generation
- EasyDMA

SDA

- Up to 1 Mbps baudrate
- Return to IDLE between transactions supported (when using HW flow control)
- One or two stop bit
- Least significant bit (LSB) first

¹⁹ High bit rates or stronger pull-ups may require [GPIO](#page-96-0)s to be set as High Drive, see GPIO chapter for more details.

Figure 104: UARTE configuration

The GPIOs used for each UART interface can be chosen from any GPIO on the device and are independently configurable. This enables great flexibility in device pinout and efficient use of board space and signal routing.

Note: The external crystal oscillator must be enabled to obtain sufficient clock accuracy for stable communication. See [CLOCK — Clock control](#page-69-0) on page 70 for more information.

6.19.1 EasyDMA

The UARTE implements EasyDMA for reading and writing to and from the RAM.

If the TXD.PTR and the RXD.PTR are not pointing to the Data RAM region, an EasyDMA transfer may result in a HardFault or RAM corruption. See [Memory](#page-20-0) on page 21 for more information about the different memory regions.

The .PTR and .MAXCNT registers are double-buffered. They can be updated and prepared for the next RX/ TX transmission immediately after having received the RXSTARTED/TXSTARTED event.

The ENDRX and ENDTX events indicate that the EasyDMA is finished accessing the RX or TX buffer in RAM.

6.19.2 Transmission

The first step of a DMA transmission is storing bytes in the transmit buffer and configuring EasyDMA. This is achieved by writing the initial address pointer to TXD.PTR, and the number of bytes in the RAM buffer to TXD.MAXCNT. The UARTE transmission is started by triggering the STARTTX task.

After each byte has been sent over the TXD line, a TXDRDY event will be generated.

When all bytes in the TXD buffer, as specified in the TXD.MAXCNT register, have been transmitted, the UARTE transmission will end automatically and an ENDTX event will be generated.

A UARTE transmission sequence is stopped by triggering the STOPTX task. A TXSTOPPED event will be generated when the UARTE transmitter has stopped.

If the ENDTX event has not already been generated when the UARTE transmitter has come to a stop, the UARTE will generate the ENDTX event explicitly even though all bytes in the TXD buffer, as specified in the TXD.MAXCNT register, have not been transmitted.

If flow control is enabled through the HWFC field in the CONFIG register, a transmission will be automatically suspended when CTS is deactivated and resumed when CTS is activated again, as shown in the following figure. A byte that is in transmission when CTS is deactivated will be fully transmitted before the transmission is suspended.

Figure 105: UARTE transmission

The UARTE transmitter will be in its lowest activity level, and consume the least amount of energy, when it is stopped, i.e. before it is started via STARTTX or after it has been stopped via STOPTX and the TXSTOPPED event has been generated. See [POWER — Power control](#page-63-0) on page 64 for more information about power modes.

6.19.3 Reception

The UARTE receiver is started by triggering the STARTRX task. The UARTE receiver is using EasyDMA to store incoming data in an RX buffer in RAM.

The RX buffer is located at the address specified in the RXD.PTR register. The RXD.PTR register is doublebuffered and it can be updated and prepared for the next STARTRX task immediately after the RXSTARTED event is generated. The size of the RX buffer is specified in the RXD.MAXCNT register. The UARTE generates an ENDRX event when it has filled up the RX buffer, as seen in the following figure.

For each byte received over the RXD line, an RXDRDY event will be generated. This event is likely to occur before the corresponding data has been transferred to Data RAM.

The RXD.AMOUNT register can be queried following an ENDRX event to see how many new bytes have been transferred to the RX buffer in RAM since the previous ENDRX event.

Figure 106: UARTE reception

The UARTE receiver is stopped by triggering the STOPRX task. An RXTO event is generated when the UARTE has stopped. The UARTE will make sure that an impending ENDRX event will be generated before the RXTO event is generated. This means that the UARTE will guarantee that no ENDRX event will be generated after RXTO, unless the UARTE is restarted or a FLUSHRX command is issued after the RXTO event is generated.

Note: If the ENDRX event has not been generated when the UARTE receiver stops, indicating that all pending content in the RX FIFO has been moved to the RX buffer, the UARTE will generate the ENDRX event explicitly even though the RX buffer is not full. In this scenario the ENDRX event will be generated before the RXTO event is generated.

To determine the amount of bytes the RX buffer has received, the CPU can read the RXD.AMOUNT register following the ENDRX event or the RXTO event.

The UARTE is able to receive up to four bytes after the STOPRX task has been triggered, as long as these are sent in succession immediately after the RTS signal is deactivated. After the RTS is deactivated, the UART is able to receive bytes for a period of time equal to the time needed to send four bytes on the configured baud rate.

After the RXTO event is generated the internal RX FIFO may still contain data, and to move this data to RAM the FLUSHRX task must be triggered. To make sure that this data does not overwrite data in the RX buffer, the RX buffer should be emptied or the RXD.PTR should be updated before the FLUSHRX task is triggered. To make sure that all data in the RX FIFO is moved to the RX buffer, the RXD.MAXCNT register must be set to RXD.MAXCNT > 4, as seen in the following figure. The UARTE will generate the ENDRX event after completing the FLUSHRX task even if the RX FIFO was empty or if the RX buffer does not get filled up. To be able to know how many bytes have actually been received into the RX buffer in this case, the CPU can read the RXD.AMOUNT register following the ENDRX event.

Figure 107: UARTE reception with forced stop via STOPRX

If HW flow control is enabled through the HWFC field in the CONFIG register, the RTS signal will be deactivated when the receiver is stopped via the STOPRX task or when the UARTE is only able to receive four more bytes in its internal RX FIFO.

With flow control disabled, the UARTE will function in the same way as when the flow control is enabled except that the RTS line will not be used. This means that no signal will be generated when the UARTE has reached the point where it is only able to receive four more bytes in its internal RX FIFO. Data received when the internal RX FIFO is filled up, will be lost.

The UARTE receiver will be in its lowest activity level, and consume the least amount of energy, when it is stopped, i.e. before it is started via STARTRX or after it has been stopped via STOPRX and the RXTO event has been generated. See [POWER — Power control](#page-63-0) on page 64 for more information about power modes.

6.19.4 Error conditions

An ERROR event, in the form of a framing error, will be generated if a valid stop bit is not detected in a frame. Another ERROR event, in the form of a break condition, will be generated if the RXD line is held active low for longer than the length of a data frame. Effectively, a framing error is always generated before a break condition occurs.

An ERROR event will not stop reception. If the error was a parity error, the received byte will still be transferred into Data RAM, and so will following incoming bytes. If there was a framing error (wrong stop bit), that specific byte will NOT be stored into Data RAM, but following incoming bytes will.

6.19.5 Using the UARTE without flow control

If flow control is not enabled, the interface will behave as if the CTS and RTS lines are kept active all the time.

6.19.6 Parity and stop bit configuration

Automatic even parity generation for both transmission and reception can be configured using the register [CONFIG](#page-352-0) on page 353. See the register description for details.

The amount of stop bits can also be configured through the register [CONFIG](#page-352-0) on page 353.

6.19.7 Low power

When putting the system in low power and the peripheral is not needed, lowest possible power consumption is achieved by stopping, and then disabling the peripheral.

The STOPTX and STOPRX tasks may not be always needed (the peripheral might already be stopped), but if STOPTX and/or STOPRX is sent, software shall wait until the TXSTOPPED and/or RXTO event is received in response, before disabling the peripheral through the ENABLE register.

6.19.8 Pin configuration

The different signals RXD, CTS (Clear To Send, active low), RTS (Request To Send, active low), and TXD associated with the UARTE are mapped to physical pins according to the configuration specified in the PSEL.RXD, PSEL.CTS, PSEL.RTS, and PSEL.TXD registers respectively.

The PSEL.RXD, PSEL.CTS, PSEL.RTS, and PSEL.TXD registers and their configurations are only used as long as the UARTE is enabled, and retained only for the duration the device is in ON mode. PSEL.RXD, PSEL.RTS, PSEL.RTS, and PSEL.TXD must only be configured when the UARTE is disabled.

To secure correct signal levels on the pins by the UARTE when the system is in OFF mode, the pins must be configured in the GPIO peripheral as described in the following table.

Only one peripheral can be assigned to drive a particular GPIO pin at a time. Failing to do so may result in unpredictable behavior.

Table 98: GPIO configuration before enabling peripheral

6.19.9 Registers

Table 99: Instances

Table 100: Register overview

6.19.9.1 TASKS_STARTRX

Address offset: 0x000

Start UART receiver

6.19.9.2 TASKS_STOPRX

Address offset: 0x004

Stop UART receiver

6.19.9.3 TASKS_STARTTX

Address offset: 0x008

Start UART transmitter

6.19.9.4 TASKS_STOPTX

Address offset: 0x00C

Stop UART transmitter

6.19.9.5 TASKS_FLUSHRX

Address offset: 0x02C

Flush RX FIFO into RX buffer

6.19.9.6 SUBSCRIBE_STARTRX

Subscribe configuration for task [STARTRX](#page-336-0)

6.19.9.7 SUBSCRIBE_STOPRX

Address offset: 0x084

Subscribe configuration for task [STOPRX](#page-337-0)

6.19.9.8 SUBSCRIBE_STARTTX

Address offset: 0x088

Subscribe configuration for task [STARTTX](#page-337-1)

6.19.9.9 SUBSCRIBE_STOPTX

Address offset: 0x08C

Subscribe configuration for task [STOPTX](#page-337-2)

6.19.9.10 SUBSCRIBE_FLUSHRX

Address offset: 0x0AC

Subscribe configuration for task [FLUSHRX](#page-337-3)

6.19.9.11 EVENTS_CTS

Address offset: 0x100

CTS is activated (set low). Clear To Send.

6.19.9.12 EVENTS_NCTS

Address offset: 0x104

CTS is deactivated (set high). Not Clear To Send.

6.19.9.13 EVENTS_RXDRDY

Data received in RXD (but potentially not yet transferred to Data RAM)

6.19.9.14 EVENTS_ENDRX

Address offset: 0x110

Receive buffer is filled up

6.19.9.15 EVENTS_TXDRDY

Address offset: 0x11C

Data sent from TXD

6.19.9.16 EVENTS_ENDTX

Address offset: 0x120

Last TX byte transmitted

6.19.9.17 EVENTS_ERROR

Error detected

6.19.9.18 EVENTS_RXTO

Address offset: 0x144

Receiver timeout

6.19.9.19 EVENTS_RXSTARTED

Address offset: 0x14C

UART receiver has started

6.19.9.20 EVENTS_TXSTARTED

Address offset: 0x150

UART transmitter has started

6.19.9.21 EVENTS_TXSTOPPED

Transmitter stopped

6.19.9.22 PUBLISH_CTS

Address offset: 0x180

Publish configuration for event [CTS](#page-339-1)

6.19.9.23 PUBLISH_NCTS

Address offset: 0x184

Publish configuration for event [NCTS](#page-339-2)

6.19.9.24 PUBLISH_RXDRDY

Address offset: 0x188

Publish configuration for event [RXDRDY](#page-339-3)

6.19.9.25 PUBLISH_ENDRX

Address offset: 0x190

Publish configuration for event [ENDRX](#page-340-0)

6.19.9.26 PUBLISH_TXDRDY

Address offset: 0x19C

Publish configuration for event [TXDRDY](#page-340-1)

6.19.9.27 PUBLISH_ENDTX

Address offset: 0x1A0

Publish configuration for event [ENDTX](#page-340-2)

6.19.9.28 PUBLISH_ERROR

Address offset: 0x1A4

Publish configuration for event [ERROR](#page-340-3)

6.19.9.29 PUBLISH_RXTO

Address offset: 0x1C4

Publish configuration for event [RXTO](#page-341-0)

6.19.9.30 PUBLISH_RXSTARTED

Address offset: 0x1CC

Publish configuration for event [RXSTARTED](#page-341-1)

6.19.9.31 PUBLISH_TXSTARTED

Address offset: 0x1D0

Publish configuration for event [TXSTARTED](#page-341-2)

6.19.9.32 PUBLISH_TXSTOPPED

Address offset: 0x1D8

Publish configuration for event [TXSTOPPED](#page-341-3)

6.19.9.33 SHORTS

Address offset: 0x200

Shortcuts between local events and tasks

6.19.9.34 INTEN

Address offset: 0x300

Enable or disable interrupt

6.19.9.35 INTENSET

Address offset: 0x304

Enable interrupt

6.19.9.36 INTENCLR

Address offset: 0x308

Disable interrupt

6.19.9.37 ERRORSRC

Address offset: 0x480

Error source

This register is read/write one to clear.

6.19.9.38 ENABLE

Address offset: 0x500

Enable UART

6.19.9.39 PSEL.RTS

Address offset: 0x508 Pin select for RTS signal

6.19.9.40 PSEL.TXD

Address offset: 0x50C

Pin select for TXD signal

6.19.9.41 PSEL.CTS

Address offset: 0x510

Pin select for CTS signal

6.19.9.42 PSEL.RXD

Address offset: 0x514

Pin select for RXD signal

6.19.9.43 BAUDRATE

Address offset: 0x524

Baud rate. Accuracy depends on the HFCLK source selected.

6.19.9.44 RXD.PTR

Address offset: 0x534

Data pointer

See the memory chapter for details about which memories are available for EasyDMA.

6.19.9.45 RXD.MAXCNT

Address offset: 0x538

Maximum number of bytes in receive buffer

6.19.9.46 RXD.AMOUNT

Address offset: 0x53C

Number of bytes transferred in the last transaction

6.19.9.47 TXD.PTR

Address offset: 0x544

Data pointer

See the memory chapter for details about which memories are available for EasyDMA.

6.19.9.48 TXD.MAXCNT

Address offset: 0x548

Maximum number of bytes in transmit buffer

6.19.9.49 TXD.AMOUNT

Address offset: 0x54C

Number of bytes transferred in the last transaction

6.19.9.50 CONFIG

Address offset: 0x56C

Configuration of parity and hardware flow control

6.19.10 Electrical specification

6.19.10.1 UARTE electrical specification

6.20 WDT — Watchdog timer

A countdown watchdog timer using the low-frequency clock source (LFCLK) offers configurable and robust protection against application lock-up.

The watchdog timer is started by triggering the START task.

The watchdog can be paused during long CPU sleep periods for low power applications and when the debugger has halted the CPU. The watchdog is implemented as a down-counter that generates a TIMEOUT event when it wraps over after counting down to 0. When the watchdog timer is started through the START task, the watchdog counter is loaded with the value specified in the CRV register. This counter is also reloaded with the value specified in the CRV register when a reload request is granted.

The watchdog's timeout period is given by:

```
timeout [s] = ( CRV + 1 ) / 32768
```
When started, the watchdog will automatically force the 32.768 kHz RC oscillator on as long as no other 32.768 kHz clock source is running and generating the 32.768 kHz system clock, see chapter [CLOCK —](#page-69-0) [Clock control](#page-69-0) on page 70.

6.20.1 Reload criteria

The watchdog has eight separate reload request registers, which shall be used to request the watchdog to reload its counter with the value specified in the CRV register. To reload the watchdog counter, the special value 0x6E524635 needs to be written to all enabled reload registers.

One or more RR registers can be individually enabled through the RREN register.

²⁰ High baud rates may require GPIOs to be set as High Drive, see GPIO chapter for more details.

6.20.2 Temporarily pausing the watchdog

By default, the watchdog will be active counting down the down-counter while the CPU is sleeping and when it is halted by the debugger. It is however possible to configure the watchdog to automatically pause while the CPU is sleeping as well as when it is halted by the debugger.

6.20.3 Watchdog reset

A TIMEOUT event will automatically lead to a watchdog reset.

See [Reset](#page-55-0) on page 56 for more information about reset sources. If the watchdog is configured to generate an interrupt on the TIMEOUT event, the watchdog reset will be postponed with two 32.768 kHz clock cycles after the TIMEOUT event has been generated. Once the TIMEOUT event has been generated, the impending watchdog reset will always be effectuated.

The watchdog must be configured before it is started. After it is started, the watchdog's configuration registers, which comprise registers CRV, RREN, and CONFIG, will be blocked for further configuration.

The watchdog can be reset from several reset sources, see [Reset behavior](#page-56-0) on page 57.

When the device starts running again, after a reset, or waking up from OFF mode, the watchdog configuration registers will be available for configuration again.

6.20.4 Registers

Table 101: Instances

Table 102: Register overview

6.20.4.1 TASKS_START

Address offset: 0x000

Start the watchdog

6.20.4.2 SUBSCRIBE_START

Address offset: 0x080

Subscribe configuration for task [START](#page-354-0)

6.20.4.3 EVENTS_TIMEOUT

Address offset: 0x100

Watchdog timeout

6.20.4.4 PUBLISH_TIMEOUT

Address offset: 0x180

Publish configuration for event [TIMEOUT](#page-355-1)

6.20.4.5 INTENSET

Address offset: 0x304

Enable interrupt

6.20.4.6 INTENCLR

Address offset: 0x308

Disable interrupt

6.20.4.7 RUNSTATUS

Address offset: 0x400

Run status

6.20.4.8 REQSTATUS

Address offset: 0x404

Request status

6.20.4.9 CRV

Counter reload value

6.20.4.10 RREN

Address offset: 0x508

Enable register for reload request registers

6.20.4.11 CONFIG

Address offset: 0x50C

Configuration register

6.20.4.12 RR[n] (n=0..7)

Address offset: 0x600 + (n × 0x4)

Reload request n

6.20.5 Electrical specification

6.20.5.1 Watchdog Timer Electrical Specification

LTE modem

7.1 Introduction

The long term evolution (LTE) modem consists of baseband processing and RF parts, which together implement a complete 3GPP LTE release 13 (Rel-13) Cat-M1 and Cat-NB1 and LTE release 14 (Rel-14) Cat-NB1 and Cat-NB2 capable product.

Note: Cat-NB2 is supported in LTE modem HW, but needs modem firmware support to get enabled. Please refer to *nRF9160 modem firmware release notes* found under nRF91 FW binaries downloads concerning availability of Cat-NB2 feature support".

As illustrated in the image below, the following is a part of the LTE modem:

- RF transceiver
- Modem baseband (BB)
- Embedded flash/RAM
- Modem host processor and peripherals

The modem baseband and host processor provide functions for the LTE L1, L2 and L3 (layer 1, 2 and 3 respectively) as well as IP communication layers. Modem peripherals provide hardware services for modem operating system and for modem secure execution environment.

Figure 108: LTE modem within the nRF91

Application and modem domains are interacting through interprocessor communication (IPC) mechanism. LTE modem is accessible to user through the modem API.

The application processor is the master in the system and responsible for starting and stopping of the modem. LTE modem enables the clocks and power required for its own operation. Shared resources, such as e.g. clocks, are handled within the platform and require no user involvement. In cases where a hard fault is detected in the modem, the application domain will perform a hard reset for the modem.

Note: For details regarding the modem API, please refer to *nRF Connect SDK* document and *nRF91 AT Commands, Command Reference Guide* document.

Key features of the LTE modem are:

- Complete modem with baseband and RF transceiver
- 3GPP release 13 compliant LTE categories:
	- Cat-M1 (eMTC enhanced machine type communication)
	- Cat-NB1 (NB-IoT narrowband internet of things (IoT))
- 3GPP release 14 compliant LTE categories:
	- Cat-NB1 (NB-IoT)
	- Cat-NB2 (NB-IoT)
- Power saving modes
- Supporting LTE bands from 700 MHz to 2.2 GHz through a single typical 50 Ω antenna pin.
	- ANT antenna pin is DC grounded
- RX sensitivity: -108 dBm for Cat-M1 and -114 dBm for Cat-NB1 and Cat-NB2
	- As defined in 3GPP conformance test specification TS 36.521-1
- 1.8 V MIPI RFFE (RF front-end) digital control interface and MAGPIO control interface for external RF applications.
- An LTE modem internal ADC that is also used for some AT command interface services e.g. for battery monitoring.
- 1.8 V UICC (universal integrated circuit card) interface, based on ISO/IEC 7816-3 and compliant with:
	- ICC (ETSI TS 102 221)
	- eUICC (ETSI TS 103 383)

Note: nRF9160 is able to run different modem FW builds that define the final modem feature set in a specific nRF9160 based application.

Note: For details regarding the services provided by modem AT command interface, please refer to *nRF Connect SDK* document and *nRF91 AT Commands, Command Reference Guide* document.

7.2 SIM card interface

LTE modem supports the UICC (universal integrated circuit card) interface.

Only the UICCs with the electrical interface specified in ISO/IEC 7816-3 are supported, meaning that the UICCs with IC-USB, CLF or MMC interfaces are not supported.

The supported UICC/eUICC interface is compliant with:

- ETSI TS 102 221: Smart Cards; UICC-Terminal interface; Physical and logical characteristics
- ETSI TS 103 383: Smart Cards; Embedded UICC; Requirements Specification

The physical interface towards the eUICC is the same as towards the removable UICC.

Only the class C (supply voltage 1.8 V nominal) operation is supported. Support for the legacy class B (supply voltage 3.0 V nominal) operation must be built with external components, including the external power supply and the level shifters towards the LTE modem UICC interface.

LTE modem supports powering down the UICC during PSM and eDRX idle mode, when the UICC supports this feature as specified in 3GPP TS 24.301. To reach the lowest total power consumption of the complete

cellular IoT product, only UICCs supporting power down mode during PSM and eDRX idle mode sleep intervals should be considered.

LTE modem controls the physical interfaces towards the UICC and implements the transport protocol over the four-pin ISO/IEC 7816-3 interface:

- VCC (power supply): LTE modem drives this
- CLK (clock signal): LTE modem drives this
- RST (reset signal): LTE modem drives this
- I/O (input/output serial data): Bi-directional

The interface and the connections between LTE modem, UICC connector, and the ESD device is shown in the figure below.

Figure 109: Connections between LTE modem, card connector, and the ESD device

Only standard transmission speeds are supported as specified in ETSI TS 102 221.

Important: LTE modem must be stopped through the modem API, before removing the UICC.

An ESD (electrostatic discharge) protection device compatible with UICC cards must be used between the removable card and the LTE modem, to protect LTE modem against a harmful electrostatic discharge from the card connector.

7.3 LTE modem coexistence interface

LTE modem uses a dedicated three-pin interface for RF interference avoidance towards a companion radio device e.g. an external positioning device or Bluetooth Low Energy device.

The inputs and outputs for this interface:

- COEX0: Input to the LTE modem from the external device. When active high, indicates that the external device transceiver is turned on.
	- When internal GPS is used, COEX0 can be used as active high control for the external LNA component.
- COEX1: Output from the LTE modem to the external device. Active high time mark pulse, which is synchronous to LTE system time.
	- When internal GPS is used, COEX1 delivers the GPS 1PPS (one pulse per second) time mark pulse.
- COEX2: Output from the LTE modem to the external device. When active high, indicates that the LTE modem transceiver is turned on.
	- COEX2 can also be treated as active low grant from LTE modem to the external device, indicating grant to transmit and receive.

Note: COEX2 pin requires an external pull-down resistor in 100 kΩ size range to be used.

Note: Please refer to *nRF9160 modem firmware release notes* found under nRF91 FW binaries downloads concerning availability of COEX signaling feature support".

COEX interface timing in relation to modem state is shown in the figure below.

Figure 110: COEX interface timing

7.4 LTE modem RF control external interface

LTE modem provides dedicated 1.8 V digital interfaces for controlling external RF applications, such as antenna tuner devices:

- MIPI RFFE interface pins: VIO, SCLK, SDATA.
- MAGPIO interface pins: MAGPIO0, MAGPIO1, MAGPIO2.

LTE modem drives these outputs timing accurately according to LTE protocol timing to set e.g. the correct antenna tuner settings per used frequency. User needs to inform the LTE modem through the modem API about the particular RF application e.g. antenna tuner device configuration, so that LTE modem knows how to drive it.

Note: For details regarding the modem API and supported RF external control features, please refer to *nRF91 AT Commands, Command Reference Guide* document.

Note: MIPI RFFE capacitive load at SCLK or SDATA pins shall not exceed 15 pF.

MIPI RFFE interface timing in relation to modem state is shown in the figure below.

Figure 111: MIPI RFFE interface timing

MAGPIO interface timing in relation to modem state is shown in the figure below.

Figure 112: MAGPIO interface timing

7.5 RF front-end interface

nRF9160 has a single-ended (SE) 50 Ω antenna interface to connect directly to antenna.

7.6 Registers

7.7 Electrical specification

7.7.1 Key RF parameters for Cat-M1

Note: For certification status, please refer to [Regulatory information](#page-397-0) on page 398.

bandwidth

7.7.2 Key RF parameters for Cat-NB1 and Cat-NB2

Note: For certification status, please refer to [Regulatory information](#page-397-0) on page 398.

Note: There is no foreseen NB-IoT network deployment for FCC bands closer than 200 kHz from band edge, hence our device will not transmit in FCC bands on channels that are closer than 200kHz to band edge.

7.7.3 Receiver parameters for Cat-M1

7.7.4 Receiver parameters for Cat-NB1 and Cat-NB2

7.7.5 Transmitter parameters for Cat-M1

7.7.6 Transmitter parameters for Cat-NB1 and Cat-NB2

GPS receiver

The GPS receiver supports GPS L1 C/A reception. Operation is time multiplexed with LTE modem, and it is possible to obtain the GPS position either while the LTE is in RRC Idle mode or power saving mode (PSM), or when the LTE modem is completely deactivated.

The application processor is the master in the system and responsible for starting and stopping of the GPS receiver. GPS receiver is accessible to user through the GPS API.

Note: For details regarding the modem API, please refer to *nRF Connect SDK* document and *nRF91 AT Commands, Command Reference Guide* document.

Key features of the GPS receiver are:

- GPS L1 C/A supported
- Optimized for low-power and low-cost IoT applications
- Modes of operation:
	- Single shot (cold start mode by default)
	- Position fix per fixed interval, configurable between 10 s 0.5 hour: first start with cold start, sequential fixes with hot start
	- Continuous tracking
- Power saving mode:
	- Duty-cycled continuous tracking operation
- Antenna interface:
	- External low-noise amplifier (LNA) with SAW filter recommended on the GPS antenna input
	- Dedicated GPS antenna, or shared antenna with LTE
	- GPS antenna pin is DC grounded

Note: There must be minumum 27dB attenuation to out of band power to avoid blocking high power RF signals to GPS receiver input. This can be achieved for example by a SAW filter at the output of the external LNA.

8.1 Electrical specification

Table below summarises GPS receiver performance parameters.

Table 103: GPS electrical specification

Debug and trace

9.1 Overview

The debug and trace system offers a flexible and powerful mechanism for non-intrusive debugging.

Figure 113: Debug and trace overview

The main features of the debug and trace system include:

- Two-pin serial wire debug (SWD) interface, protocol version 1
- Access port connection
	- Breakpoint unit (BPU) supports eight hardware breakpoint comparators
	- Data watchpoint and trace (DWT) unit supports four watchpoint comparators
	- Instrumentation trace macrocell (ITM)
	- Embedded trace macrocell (ETM)
	- Access protection through APPROTECT, ERASEPROTECT and SECUREAPPROTECT
- Trace port interface unit (TPIU)
	- 4-bit parallel trace of ITM and ETM trace data

Note: When a system contains multiple CPU domains, it is important to notice that if one domain (subsystem A) has master rights on another domain (subsystem B), the master subsystem can have access to data from the slave subsytem. In this example, even if subsystem B is locked by APPROTECT or ERASEPROTECT, subsystem A can access some data for subsystem B. Consequently, even if the security permissions are managed per subsystem, it is mandatory to have a global approach to the protection. Protecting a slave subsystem does not guarantee system security if the master subsystem is not protected.

9.1.1 Special consideration regarding debugger access

A debugger, if desired, can be restricted to debug non-secure code only, and access non-secure memory regions and peripherals using register [SECUREAPPROTECT](#page-41-0) on page 42. Register [APPROTECT](#page-40-0) on page 41 will block all debugger access.

Debugger accesses are controlled as described in table below.

Table 104: Debugger access control

If a RAM or flash region has its permission set to allow code execution, the content of this region will be visible to the debugger even if the read permission is not set. This allows a debugger to display the content of the code being executed. For more about how to configure permissions, please refer to [SPU —](#page-258-0) [System protection unit](#page-258-0) on page 259.

9.1.2 DAP - Debug access port

An external debugger can access the device via the debug access port (DAP).

The DAP implements a standard ARM CoreSight serial wire debug port (SW-DP). The SW-DP implements the serial wire debug (SWD) protocol that is a two-pin serial interface, see SWDCLK and SWDIO illustrated in figure [Debug and trace overview](#page-368-0) on page 369.

In addition to the default access port in the application CPU (AHB-AP), the DAP includes a custom control access port (CTRL-AP), described in more detail in [CTRL-AP - Control access port](#page-371-0) on page 372.

Note:

- The SWDIO line has an internal pull-up resistor.
- The SWDCLK line has an internal pull-down resistor.

There are several access ports that connect to different parts of the system. An overview is given in the table below.

Table 105: Access port overview

The standard ARM components are documented in *ARM CoreSight SoC-400 Technical Reference Manual, revision r3p2*. The control access port (CTRL-AP) is proprietary, and described in more detail in [CTRL-AP -](#page-371-0) [Control access port](#page-371-0) on page 372.

9.1.3 Debug interface mode

Before the external debugger can access the CPU's access port (AHB-AP) or the control access port (CTRL-AP), the debugger must first request the device to power up via CxxxPWRUPREQ in the SWJ-DP.

As long as the debugger is requesting power via CxxxPWRUPREQ, the device will be in debug interface mode. Otherwise, the device is in normal mode. When a debug session is over, the external debugger must make sure to put the device back into normal mode and then a pin reset should be performed. The reason is that the overall power consumption is higher in debug interface mode compared to normal mode.

Some peripherals behave differently in debug interface mode compared to normal mode. The differences are described in more detail in the chapters of the affected peripherals.

For details on how to use the debug capabilities, please read the debug documentation of your IDE.

If the device is in System OFF when power is requested via CxxxPWRUPREQ, the system will wake up and the DIF flag in [RESETREAS](#page-67-0) on page 68 will be set.

9.1.4 Real-time debug

The device supports real-time debugging, which allows interrupts to execute to completion in real time when breakpoints are set in thread mode or lower priority interrupts.

Real-time debugging thus enables the developer to set a breakpoint and single-step through their code without a failure of the real-time event-driven threads running at higher priority. For example, this enables the device to continue to service the high-priority interrupts of an external controller or sensor without failure or loss of state synchronization while the developer steps through code in a low-priority thread.

9.1.5 Trace

The device supports ETM and ITM trace.

Trace data from the ETM and the ITM is sent to an external debugger via a 4-bit wide parallel trace port (TPIU), see TRACEDATA[0] through TRACEDATA[3], and TRACECLK in [Debug and trace overview](#page-368-0) on page 369.

For details on how to use the trace capabilities, please read the debug documentation of your IDE.

TPIU's trace pins are multiplexed with GPIOs, see [Pin assignments](#page-384-0) on page 385 for more information.

Note: To configure the trace data delivery to the device trace port, use the MDK system start-up file included as of MDK version 8.26.0.

Trace speed is configured in the [TRACEPORTSPEED \(Retained\)](#page-382-0) on page 383 register. The speed of the trace pins depends on the DRIVE setting of the GPIOs that the trace pins are multiplexed with. See GPIO – [General purpose input/output](#page-96-0) on page 97 for information about how to set drive settings. Only S0S1 and H0H1 drives are suitable for debugging. S0S1 is the default DRIVE at reset. If parallel or serial trace port signals are not fast enough in the debugging conditions, all GPIOs in use for tracing should be set to high drive (H0H1). The user shall make sure that DRIVE setting for these GPIOs is not overwritten by software during the debugging session.

9.1.6 Registers

Table 106: Register overview

9.1.6.1 TARGETID

Address offset: 0x042

The TARGETID register provides information about the target when the host is connected to a single device.

The TARGETID register is accessed by a read of DP register 0x4 when the DPBANKSEL bit in the SELECT register is set to 0x2.

9.1.7 Electrical specification

9.1.7.1 Trace port

9.2 CTRL-AP - Control access port

The control access port (CTRL-AP) is a custom access port that enables control of the device when other debug access ports (DAP) have been disabled by the access port protection.

For an overview of the other debug access ports, see [DAP - Debug access port](#page-369-0) on page 370.

Figure 114: Control access port details

Access port protection (APPROTECT) blocks the debugger access to the AHB-AP, and prevents read and write access to all CPU registers and memory-mapped addresses. To enable port protection access for both secure and non-secure modes, use the registers [SECUREAPPROTECT](#page-41-0) on page 42 and [APPROTECT](#page-40-0) on

page 41 respectively. The debugger can use the register [APPROTECT.STATUS](#page-375-0) on page 376 to read the status of secure and non-secure access port protection.

CTRL-AP has the following features:

- Soft reset
- Erase all
- Mailbox interface
- Debug of protected devices

9.2.1 Reset request

The debugger can request the device to perform a soft reset.

Use the register [RESET](#page-374-0) on page 375 to request a soft reset. Once the soft reset is performed, the reset reason is accessible on the on-chip firmware through the RESETREAS register. For more information about the soft reset, see [Reset](#page-55-0) on page 56.

9.2.2 Erase all

The Erase all function lets the debugger trigger an erase of flash, user information configuration registers (UICR), RAM, all peripheral settings, and also removes the access port protection.

To trigger an erase all function, the debugger writes to the register [ERASEALL](#page-374-1) on page 375. The register [ERASEALLSTATUS](#page-374-2) on page 375 will read as busy for the duration of the operation. After the next reset, the access port protection is removed.

If the debugger performs an erase all function on a slave MCU, the erase sequence will always erase the application MCU first, independently of how the application is protected, before erasing the slave MCU.

Erase all protection

It is possible to prevent the debugger from performing an erase all operation by writing to the [UICR.ERASEPROTECT](#page-42-0) register. Once the register is configured and the device is reset, the CTRL-AP [ERASEALL](#page-374-1) operation is disabled, and all flash write and erase operations are restricted to the firmware. In addition, it is still possible to write/erase from the debugger as long as the [UICR.APPROTECT](#page-40-0) register is not set.

Note: Setting the [UICR.ERASEPROTECT](#page-42-0) register only affects the erase all operation and not the debugger access.

The register [ERASEPROTECT.STATUS](#page-375-1) on page 376 holds the status for erase protection.

9.2.3 Mailbox interface

CTRL-AP implements a mailbox interface which enables the CPU to communicate with a debugger over the SWD interface.

The mailbox interface consists of a transmit register [MAILBOX.TXDATA](#page-376-0) on page 377 with its corresponding status register [MAILBOX.TXSTATUS](#page-376-1) on page 377, and a receive register [MAILBOX.RXDATA](#page-376-2) on page 377 with its corresponding status register [MAILBOX.RXSTATUS](#page-376-3) on page 377. Status bits in the TXSTATUS/RXSTATUS registers are set and cleared automatically when the TXDATA/RXDATA registers are written to and read from, independently of the direction.

Figure 115: Mailbox register interface

Mailbox transfer sequence

- **1.** Sender writes TXDATA.
- **2.** Hardware sets sender's TXSTATUS to DataPending.
- **3.** Hardware sets receiver's RXSTATUS to DataPending.
- **4.** Receiver reads RXDATA.
- **5.** Hardware sets receiver's RXSTATUS to NoDataPending.
- **6.** Hardware sets sender's TXSTATUS to NoDataPending.

9.2.4 Disabling erase protection

The erase protection mechanism can be disabled to return a device to factory default settings on next reset.

The debugger can read the erase protection status in the register [ERASEPROTECT.STATUS](#page-375-1) on page 376.

If ERASEPROTECT has been enabled, both the debugger and on-chip firmware must write the same non-zero 32-bit KEY value into their respective ERASEPROTECT.DISABLE registers to disable the erase protection. When both registers have been written with the same non-zero 32-bit KEY value, the device is automatically erased as described in [Erase all](#page-372-0) on page 373. The access ports will be re-enabled on the next reset once the secure erase sequence has completed.

The write-once register [ERASEPROTECT.LOCK](#page-378-0) on page 379 should be set to *Locked* as early as possible in the start-up sequence, preferably as soon as the on-chip firmware has determined it does not need to communicate with a debugger over the CTRL-AP mailbox interface. Once written, it will not be possible to remove the erase protection until the next reset.

9.2.5 Debugger registers

CTRL-AP has a set of registers that can only be accessed from the debugger over the SWD interface. These are not accessible from the CPU.

9.2.5.1 Registers

Table 107: Register overview

9.2.5.1.1 RESET

Address offset: 0x000

System reset request

This register is automatically deactivated by writing Erase to ERASEALL, it is then kept inactive until a reset source affecting the debug system is asserted. See [Reset behavior](#page-56-0) on page 57.

9.2.5.1.2 ERASEALL

Address offset: 0x004

Perform a secure erase of the device, where flash, SRAM and UICR will be erased in sequence. The device will be returned to factory default settings upon next reset.

9.2.5.1.3 ERASEALLSTATUS

Address offset: 0x008

This is the status register for the ERASEALL operation.

9.2.5.1.4 APPROTECT.STATUS

Address offset: 0x00C

This is the status register for the UICR access port protection.

9.2.5.1.5 ERASEPROTECT.STATUS

Address offset: 0x018

This is the status register for the UICR ERASEPROTECT configuration.

9.2.5.1.6 ERASEPROTECT.DISABLE

Address offset: 0x01C

This register disables ERASEPROTECT and performs ERASEALL.

9.2.5.1.7 MAILBOX.TXDATA

Address offset: 0x020

Data sent from the debugger to the CPU.

Writing to this register will automatically set a DataPending value in the TXSTATUS register.

9.2.5.1.8 MAILBOX.TXSTATUS

Address offset: 0x024

This register shows a status that indicates if data sent from the debugger to the CPU has been read.

9.2.5.1.9 MAILBOX.RXDATA

Address offset: 0x028

Data sent from the CPU to the debugger.

Reading from this register will automatically set a NoDataPending value in the RXSTATUS register.

9.2.5.1.10 MAILBOX.RXSTATUS

Address offset: 0x02C

This register shows a status that indicates if data sent from the CPU to the debugger has been read.

9.2.5.1.11 IDR

Address offset: 0x0FC

CTRL-AP Identification Register, IDR

9.2.6 Registers

Table 108: Instances

Table 109: Register overview

9.2.6.1 MAILBOX.RXDATA

Address offset: 0x400

Data sent from the debugger to the CPU.

Reading from this register will automatically set a NoDataPending value in the RXSTATUS register.

9.2.6.2 MAILBOX.RXSTATUS

Address offset: 0x404

This register shows a status that indicates if data sent from the debugger to the CPU has been read.

9.2.6.3 MAILBOX.TXDATA

Address offset: 0x480

Data sent from the CPU to the debugger.

Writing to this register will automatically set a DataPending value in the TXSTATUS register.

9.2.6.4 MAILBOX.TXSTATUS

Address offset: 0x484

This register shows a status that indicates if the data sent from the CPU to the debugger has been read.

9.2.6.5 ERASEPROTECT.LOCK

Address offset: 0x500

This register locks the ERASEPROTECT.DISABLE register from being written until next reset.

9.2.6.6 ERASEPROTECT.DISABLE

Address offset: 0x504

This register disables the ERASEPROTECT register and performs an ERASEALL operation.

9.3 TAD - Trace and debug control

Configuration interface for trace and debug

Please refer to the [Trace](#page-370-1) section for more information about how to configure the trace and debug interface.

Note: Although there are [PSEL](#page-381-0) registers for the trace port, each function can only be mapped to a single pin due to pin speed requirements. Setting the PIN field to anything else will not have any effect. See [Pin assignment chapter](#page-384-0) for more information

9.3.1 Registers

Table 110: Instances

This register is retained.

Table 111: Register overview

9.3.1.1 TASKS_CLOCKSTART

Address offset: 0x000

Start all trace and debug clocks.

9.3.1.2 TASKS_CLOCKSTOP

Address offset: 0x004

Stop all trace and debug clocks.

9.3.1.3 ENABLE

Address offset: 0x500

Enable debug domain and aquire selected GPIOs

9.3.1.4 PSEL.TRACECLK

Address offset: 0x504

Pin configuration for TRACECLK

9.3.1.5 PSEL.TRACEDATA0

Address offset: 0x508

Pin configuration for TRACEDATA[0]

9.3.1.6 PSEL.TRACEDATA1

Address offset: 0x50C

Pin configuration for TRACEDATA[1]

9.3.1.7 PSEL.TRACEDATA2

Address offset: 0x510

Pin configuration for TRACEDATA[2]

9.3.1.8 PSEL.TRACEDATA3

Address offset: 0x514

Pin configuration for TRACEDATA[3]

9.3.1.9 TRACEPORTSPEED (Retained)

Address offset: 0x518

Clocking options for the Trace Port debug interface

Reset behavior is the same as debug components

This register is retained.

10 Hardware and layout

10.1 Pin assignments

This section describes the pin assignment and the pin functions.

This device provides flexibility when it comes to routing and configuration of the GPIO pins. However, some pins have recommendations for how the pin should be configured or what it should be used for. See [LGA pin assignments](#page-384-1) on page 385 for more information about this.

10.1.1 LGA pin assignments

The pin assignment table and figure describe the assignments.

Figure 116: LGA pin assignments, top view

Hardware and layout

Hardware and layout

10.2 Mechanical specifications

The mechanical specifications for the packages show the dimensions in millimeters.

10.2.1 16.00 x 10.50 mm package

Dimensions in millimeters for the nRF9160 LGA 16.00 x 10.50 mm package.

10.3 Reference circuitry

To ensure good RF performance when designing PCBs, it is highly recommended using the PCB layouts and component values provided by Nordic Semiconductor.

Documentation for the different package reference circuits, including Altium Designer files, PCB layout files, and PCB production files can be downloaded from the product page at [www.nordicsemi.com.](http://www.nordicsemi.com)

In this section, there are reference circuits for SIxA to show the components and component values to support on-chip features in a design.

Note: This is not a complete list of configurations, but all required circuitry is shown for further configurations.

10.3.1 Schematic SIxA I GA127

Circuit configuration for SIxA LGA127, showing the schematic and the Bill of Materials (BOM) table.

Figure 118: Schematic SIxA with antenna details

Table 114: BOM for SIxA LGA127

For PCB reference layouts, see the product page for the nRF9160 at www.nordicsemi.com.

10.4 Reflow conditions

The recommended reflow profile is JEDEC J-STD-020D. The maximum amount of reflows is three.

11 Operating conditions

The operating conditions are the physical parameters that the chip can operate within.

Table 115: Operating conditions

Note: There can be excessive leakage at VDD and/or VDD_GPIO if any of these supply voltages is outside its range given in the table above.

Note: It is not recommended to use high voltage, high drive GPIO outputs (V_{OH,HDH} and V_{OH,HDL}) with high frequency, high capacitance loads unless needed, as this may increase noise level and affect radio receiver performance. High drive/high load should especially be avoided on GPIO pins close to the radio front end.

11.1 VDD GPIO considerations

VDD_GPIO is the supply to the general purpose I/O.

The following restrictions should be taken into considerations:

- VDD_GPIO should be applied after VDD has been supplied
- VDD_GPIO should be removed before removing VDD
- If VDD is supplied and VDD GPIO is grounded, an extra current consumption can be generated on VDD
- If ENABLE is low, VDD_GPIO should also be low

12 Absolute maximum ratings

Maximum ratings are the extreme limits to which the chip can be exposed for a limited amount of time without permanently damaging it. Exposure to absolute maximum ratings for prolonged periods of time may affect the reliability of the device.

Table 116: Absolute maximum ratings

 21 ATEX compliance requires a maximum of 5.0 V.

13 Ordering information

This chapter contains information on IC marking, ordering codes, and container sizes.

13.1 IC marking

The nRF9160 IC package is marked like described below.

Ν	9		6	0	
$\langle P \rangle$		P> <v v="" =""> <h> <p></p></h></v>			
$<$ Y	Y>		$\langle W \mid W \rangle$	<l< td=""><td>L></td></l<>	L>

Figure 119: Package marking

13.2 Box labels

Here are the box labels used for the nRF9160.

Figure 120: Inner box label

Figure 121: Outer box label

13.3 Order code

Here are the nRF9160 order codes and definitions.

Figure 122: Order code

Table 117: Abbreviations

13.4 Code ranges and values

Defined here are the nRF9160 code ranges and values.

Table 118: Package variant codes

Table 119: Function variant codes

Table 120: Hardware version codes

Table 121: Production configuration codes

Table 122: Production version codes

Table 123: Year codes

Table 124: Week codes

Table 125: Lot codes

Table 126: Container codes

13.5 Product options

Defined here are the nRF9160 product options.

Table 127: nRF9160 order codes

Table 128: Development tools order code

14 Regulatory information

The nRF9160 undergoes a number of regulatory certifications, ensuring both regional compliancies and compatibility with the LTE 3GPP specification.

For information about certified bands, and status for the ongoing certifications, see [nRF9160](https://www.nordicsemi.com/Products/Low-power-cellular-IoT/nRF9160-Certifications) [Certifications](https://www.nordicsemi.com/Products/Low-power-cellular-IoT/nRF9160-Certifications).

15 Legal notices

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