

# Basys MX3™ Board Reference Manual

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This manual applies to the Basys MX3 rev. B

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## Table of Contents

<b>Table of Contents</b> .....	<b>1</b>
<b>Overview</b> .....	<b>5</b>
Software Support .....	6
Coursework and Additional Materials .....	6
<b>1 Programming the Board</b> .....	<b>7</b>
1.1 Programming Tools .....	7
1.2 Programming Basics .....	8
1.3 Digital Inputs and Outputs .....	9
1.4 Remappable Pins .....	10
1.5 CPU Clock Source .....	11
<b>2 Power Supplies</b> .....	<b>12</b>
<b>3 User LEDs</b> .....	<b>13</b>
3.1 Connectivity.....	14
3.2 Functionality.....	14
<b>4 User Switches</b> .....	<b>14</b>
4.1 Connectivity.....	15
4.2 Functionality.....	16
4.3 Shared Pins.....	16

<b>5</b>	<b>User Buttons</b> .....	<b>16</b>
5.1	Connectivity.....	17
5.2	Functionality.....	17
5.3	Shared Pins .....	18
<b>6</b>	<b>RGB LED</b> .....	<b>18</b>
6.1	Connectivity.....	19
6.2	Functionality.....	19
6.2.1	RGB LED Implemented Using PWM .....	19
6.2.2	RGB LED Implemented Using PDM .....	20
<b>7</b>	<b>Seven-segment Display</b> .....	<b>20</b>
7.1	Connectivity.....	22
7.2	Functionality.....	23
<b>8</b>	<b>LCD Module</b> .....	<b>24</b>
8.1	Connectivity.....	25
8.2	Functionality.....	26
<b>9</b>	<b>I<sup>2</sup>C Interface</b> .....	<b>27</b>
<b>10</b>	<b>Accelerometer</b> .....	<b>28</b>
10.1	Connectivity .....	28
10.2	Functionality .....	28
10.3	Shared Pins .....	29
<b>11</b>	<b>Serial Peripheral Interface</b> .....	<b>29</b>
11.1	SPI1 .....	29
11.2	SPI2 .....	29
<b>12</b>	<b>Flash Memory</b> .....	<b>30</b>
12.1	Connectivity .....	30

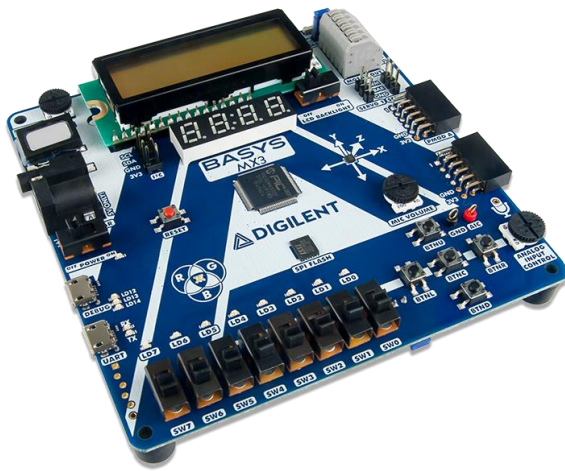
12.2	Functionality .....	31
<b>13</b>	<b>UART .....</b>	<b>31</b>
13.1	Connectivity .....	32
13.2	Functionality .....	32
<b>14</b>	<b>Motor Driver .....</b>	<b>32</b>
14.1	Connectivity .....	33
14.2	Functionality .....	35
<b>15</b>	<b>Servo Headers .....</b>	<b>35</b>
15.1	Connectivity .....	36
15.2	Functionality .....	36
15.3	Shared Pins .....	37
<b>16</b>	<b>IrDA Module .....</b>	<b>37</b>
16.1	Connectivity .....	37
16.2	Functionality .....	38
<b>17</b>	<b>Audio Out .....</b>	<b>39</b>
17.2	Connectivity .....	39
17.2	Functionality .....	40
<b>18</b>	<b>Microphone .....</b>	<b>40</b>
18.1	Connectivity .....	41
18.2	Functionality .....	41
<b>19</b>	<b>Analog Input Control .....</b>	<b>42</b>
19.1	Connectivity .....	42
19.2	Functionality .....	43
<b>20</b>	<b>Pmod Connectors .....</b>	<b>43</b>

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<b>21</b>	<b>Analog Discovery Debug Header.....</b>	<b>45</b>
	<b>Appendix 1: Remappable Input Pins .....</b>	<b>47</b>
	<b>Appendix 2: Remappable Output Pins.....</b>	<b>49</b>
	<b>Appendix 3: Basys MX3 Pinout .....</b>	<b>53</b>

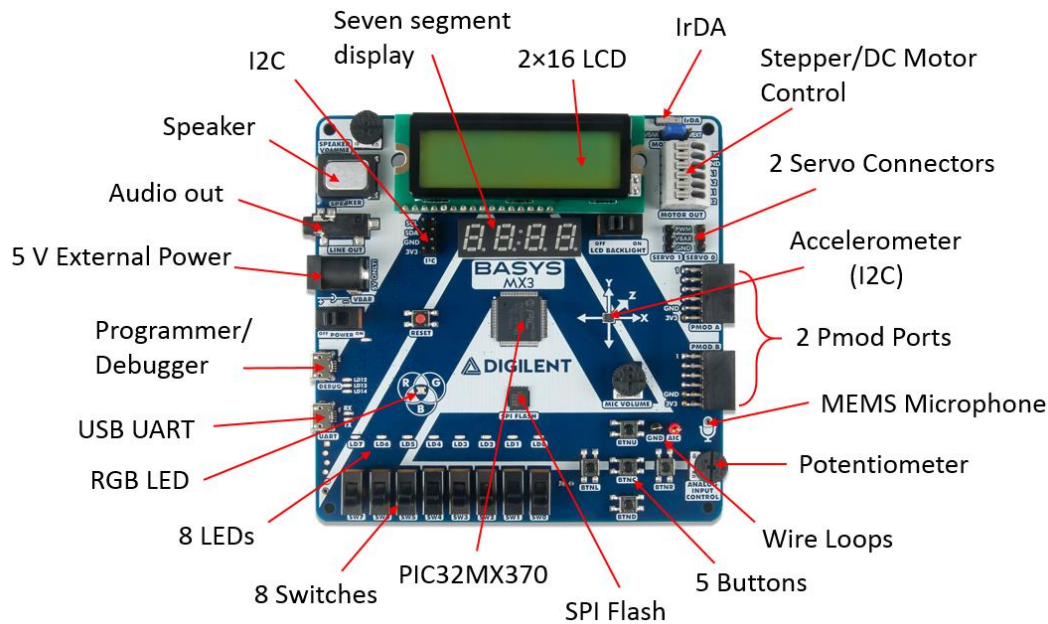
## Overview

The Basys MX3 is a true MCU trainer board designed from the ground up around the teaching experience. Basys MX3 features the PIC32MX370 from Microchip and was designed to be used with the MPLAB® X IDE. With an exhaustive set of peripherals, students gain exposure to a wide range of embedded systems related concepts while using a professional grade tool set. Accompanied by free and open source coursework, including seven in-depth teaching units and 15 complete labs, the Basys MX3 is a versatile MCU trainer board ideal for teaching introductory embedded systems courses.



The Basys MX3.

- **PIC32MX370F512L Microcontroller**
  - MIPS32® M4K® core runs up to 96 MHz using onboard 8 MHz oscillator
  - 512 KB of Program Flash Memory, 12 KB of Boot Flash Memory
  - 128 KB of SRAM
  - Four Direct Memory Access (DMA) Modules
  - Two SPI, Two I<sup>2</sup>C, and Five UART serial interfaces
  - Parallel Master Port (PMP) for graphics interfaces
  - Five 16-bit Timers/Counters
  - Five Input Capture Modules
  - Five Output Compare Modules
  - 85 I/O pins
    - 54 pins support Peripheral Pin Select (PPS) for function remapping
- **Power:**
  - Powered from USB or any 5V external power source
- **USB and Debugging:**
  - USB-UART Bridge
  - USB programmer/debugger
  - 30-pin Analog Discovery 2 connector
- **Switches, Push-buttons, LEDs, and Displays:**
  - 5 Push-buttons
  - 1 Reset button
  - 8 Slide switches
  - 8 LEDs
  - 1 RGB LED
  - 4-digit 7-segment display
  - LCD character display
- **Expansion Connectors:**
  - Two standard Pmod ports
    - 16 Total microcontroller I/O
  - One I2C Connector
    - 2 Total microcontroller I/O
- **Audio, Motor Control, and Other Devices:**
  - Speaker with Audio Output Jack and volume control
  - Microphone with volume control
  - Dual H-Bridge Motor Driver for up to two 1.5 A Brushed DC Motors or one stepper motor
  - 2 Servo Connectors
  - FIR-compatible IrDA Module
  - Potentiometer
  - 3-axis, 12-bit accelerometer
  - 4 MB SPI Flash



## Software Support

The Basys MX3 is fully supported by Microchip's MPLAB X IDE. See section 1 on [Programming the Board](#) for more information on using the Basys MX3 in MPLAB X IDE. Digilent provides a set of libraries called the Basys MX3 Library Pack that adds support for all onboard peripherals. This library pack can be downloaded from the [Basys MX3 Resource Center](#).

The Basys MX3 can also be used in Arduino IDE once the Digilent Core for Arduino IDE has been installed. Instructions for installing the Digilent Core for Arduino IDE can be found on the Basys MX3 Resource Center.

## Coursework and Additional Materials

Basys MX3 comes with a complete set of coursework designed to give teaching professionals flexibility in designing embedded systems and other microprocessor courses. With almost 300 pages of material, "Embedded Systems Basys MX3 and PIC32MX370" covers topics from toggling LEDs, motor control, and introduction to digital signal processing. Access to the full coursework is available on the Basys MX3 Resource Center.

Links to additional materials from Digilent and Microchip, including the Basys MX3 schematic and the PIC32MX370F512L datasheet, can also be found on the Basys MX3 Resource Center.

The Basys MX3 uses a lot of devices to implement all of the functionality it provides (accelerometer, flash memory, motor driver, IRDA, etc.). The manufacturers of each of these devices provide detailed descriptions of their functionality in their datasheets.

# 1 Programming the Board

## 1.1 Programming Tools

The Basys MX3 can be used with Microchip’s standard MPLAB X IDE. This software suite can be downloaded for free from the Microchip website and includes a free evaluation copy of the XC32 compiler for use with the PIC32 microcontroller family.

MPLAB X IDE is the tool used to write, compile, program, and debug code running on the Basys MX3 board. Programming and debugging a program on the Basys MX3 using the MPLAB X IDE is possible using the DEBUG USB connector. The board contains all the required circuitry for MPLAB X to communicate with the onboard PIC32, so no additional programming tools need to be purchased.

When creating a new project in MPLAB X, a wizard allows you to setup the environment and device specific tools. The steps for this include the following:

1. Select Microchip Embedded / Standalone Project, then use the “Select Device” option to specify the PIC32 microcontroller being used: PIC32MX370F512L.
2. Select the programming tool named Basys MX3 corresponding to the board you want to program, under Licensed Debugger group.

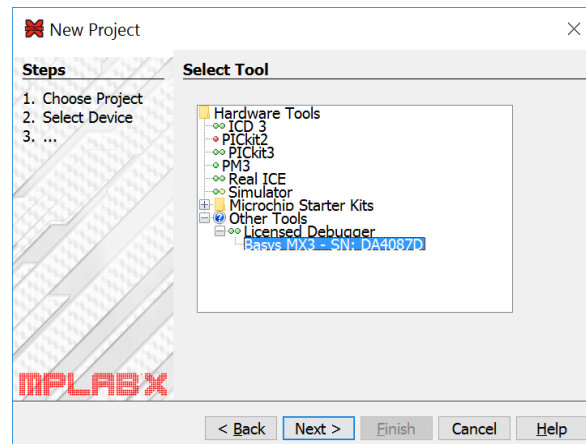


Figure 1.1. MPLAB X tool selection.

3. Select the compiler you want to use.

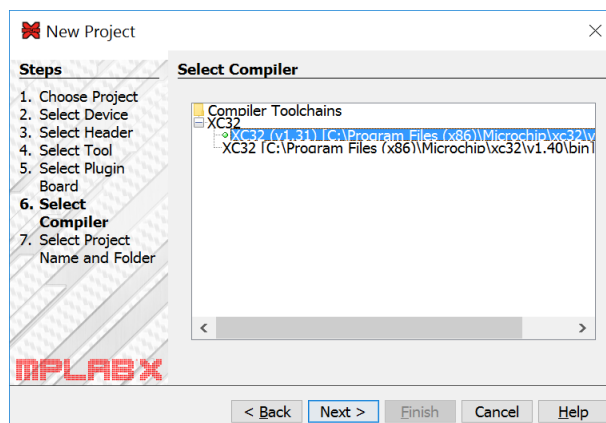


Figure 1.2. MPLAB X compiler selection.

Another useful tool included with MPLAB X is MPLAB X IPE. This tool allows the direct programming/erasing of the microcontroller, but it does not provide an environment for writing, compiling, or debugging the code. Please see Microchip documentation for instructions on using this tool.

## 1.2 Programming Basics

It is often very helpful to include the xc.h header when writing code for the Basys MX3:

```
#include <xc.h>
```

This further provides the inclusion of another header (p32mx370f512l.h) into the project that provides useful definitions such as:

- Register names
  - example (register LATA is set to 0):  
`LATA = 0;`
- Specific register bits that can be accessed using a structure having the name of the register suffixed by “bits”.
  - example (bit LATA1 of the register LATA is set to 1):  
`LATAbits.LATA1 = 1;`

Digilent provides a set of libraries called the Basys MX3 Library Pack that addresses much of the functionality on the Basys MX3:

- ACL (accelerometer)
- ADC (analog-to-digital converter)
- AUDIO
- BTN (buttons)
- IRDA
- LCD
- LED
- MIC (microphone)
- MOT (motors)
- PMODS
- RGBLED
- SPIFLASH
- SSD
- SWT (switches)
- UART

These libraries are wrappers over the lower level functions that access the registers, allowing the user to call the functionality using functions like:

```
LED_Init();  
  
LED_SetValue(4, 1); //turn on LED4
```



This set of libraries comes with the user documentation, but this is what you must do in order to use them:

- Include in your project the .c and .h files corresponding to the module you want to use (for example led.c and led.h).
- In your code, include the header of the module:

```
#include "led.h"
```

- In your code, call the needed functions

## 1.3 Digital Inputs and Outputs

The PIC32MX370F512L microcontroller offers access to all the board resources through its pins, so understanding how to access their features is very important. The list that describes each pin functionality is included in [Appendix 3](#). You can see that each pin may have multiple functions, but all pins have one feature in common: they have an associated digital I/O (input/output) bit. On PIC32 microcontrollers, the I/O pins are grouped into I/O Ports and are accessed via peripheral registers in the microcontroller. There are seven I/O Ports numbered A–G and each is 16 bits wide. Depending on the PIC32 microcontroller, some of the I/O Ports are not present, and not all 16 bits are accessible in all I/O Ports.

Each I/O Port has the following control registers: TRIS, LAT, PORT, ANSEL, CNPU, CNPD, and ODC. The registers for each I/O Port are named after it: TRISx, LATx, PORTx, ANSELx, CNPUx, CNPDx and ODCx. For example, port A will have the following assigned registers: TRISA, LATA, etc.

The TRIS register is used to set the pin direction. Setting a TRIS bit to 0 makes the corresponding pin an output. Setting the TRIS bit to 1 makes the pin an input.

The LAT register is used to write to the I/O Port. Writing to the LAT register sets any pins configured as outputs. Reading from the LAT register returns the last value written.

The PORT register is used to read from the I/O Port. Reading from the PORT register returns the current state of all the pins in the I/O Port. Writing to the PORT register may not produce the expected result, therefore writing to LAT register is recommended.

To summarize: write using LAT, read using PORT.

PIC32 microcontrollers allow any pin set as an output to be configured as either a normal digital output or as an open-drain output. The ODC register is used to control the output type. Setting an ODC bit to 0 makes the pin a normal output and setting it to 1 makes the pin an open-drain output.

The multifunction pins that include analog input functionality need to be configured in order to be used as digital pins by clearing the corresponding bit from ANSEL register. These pins will include ANx in their name. For example: AN11/PMA12/RB11 for RB11.

This microcontroller has a weak pull-up and a weak pull-down connected to each pin. These pull-ups and pull-downs are enabled/disabled by setting the corresponding bits from CNPU and CNPD registers to 1/0. The default setting is 0 (pull-ups and pull-downs disabled).

You can see a typical example of I/O pin configuration as output and digital output operations in the [User LEDs](#) section.

You can see a typical example of I/O pin configuration as input (including analog disable) and digital input operations in the [User Buttons](#) section.

Refer to the PIC32MX3XX/4XX Family Datasheet, and the PIC32 Family Reference Manual, Section 12, IO Ports, for more detailed information about the operation of the I/O Ports in the microcontroller.

## 1.4 Remappable Pins

Users may independently map the input and/or output of most digital peripherals to a fixed subset of digital I/O pins. Pins that support the peripheral pin select feature include the designation “RPN” in their full pin designation, where “RP” designates a remappable peripheral and “n” is the remappable port number.

The available peripherals to be mapped are digital-only. These include general serial communications (UART and SPI), general purpose timer clock inputs, timer-related peripherals (input capture and output compare), and interrupt-on-change inputs.

On the other hand, some peripheral modules cannot be included in the peripheral pin select feature because it requires special I/O circuitry on a specific port and it cannot be easily connected to multiple pins. These modules include I2C and analog-to-digital converters (ADC), among others.

Peripheral pin select features are controlled using two sets of Special Function Registers (SFRs): one to map peripheral inputs, and one to map peripheral outputs.

The peripheral inputs are mapped and named from the peripheral perspective (based on the peripheral). The [pin name]R registers, where [pin name] refers to the specific peripheral pins, are used to configure peripheral input mapping. TABLE 12-1 in the PIC32MX370F512L datasheet from Microchip (and Appendix 1 in this document) shows the different pins and their values available to assign to a peripheral pin.

The following example shows how different I/Os, such as pin RF4, can be assigned to U1RX input pin of the UART1 peripheral:

```
U1RXR = 0x02; // 0010 corresponds to RF4
```

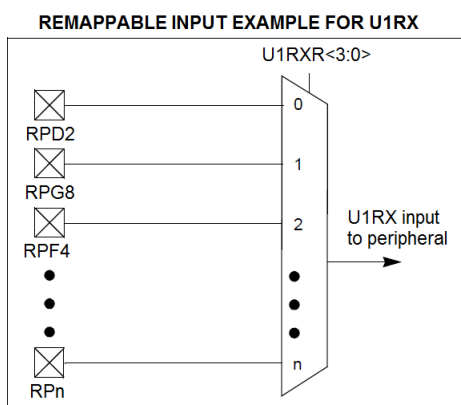


Figure 1.3. Remappable input example.

The peripheral outputs are mapped and named from the pin perspective (on the basis of the pin). The RPNR registers (Register 12-2) are used to control output mapping. The PIC32MX370F512L datasheet details in TABLE 12-2 (and Appendix 2 in this document) the values corresponding to each IO pin, associated to each available peripheral pin.

The following example shows how different peripheral outputs, such as U3TX, can be assigned to pin RF4:

```
RPF4R = 0x01; // 0001 corresponds to U3TX
```

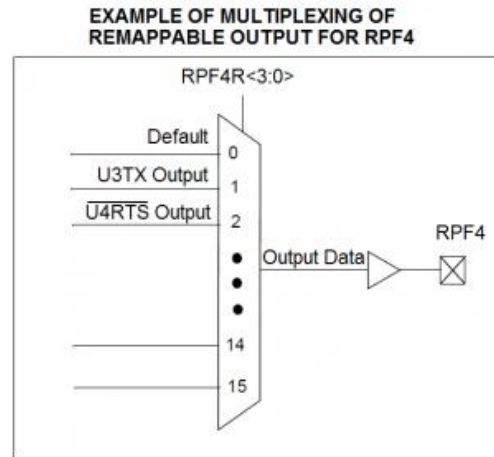


Figure 1.4. Remappable output example.

Input and output remapping is illustrated in the SPI2 section, where the SPI2 pins are mapped over the pins of PMOD A connector.

## 1.5 CPU Clock Source

The PIC32 microcontroller supports numerous clock source options for the main processor operating clock. The Basys MX3 uses an 8 MHz external crystal for use with the XT oscillator option. Oscillator options are selected via the configuration settings specified using the `#pragma config` statement. Use `#pragma config POSCMOD=XT` to select the XT option.

Using the internal system clock phase-locked loop (PLL), it is possible to select numerous multiples or divisions of the 8 MHz oscillator to produce CPU operating frequencies up to 80 MHz. The clock circuit PLL provides an input divider, multiplier, and output divider. The external clock frequency (8 MHz) is first divided by the input divider value selected. This is multiplied by the selected multiplier value and then finally divided by the selected output divider. The result is the system clock, `SYSCLK`, frequency. The `SYSCLK` frequency is used by the CPU, DMA controller, interrupt controller, and pre-fetch cache.

The values controlling the operating frequency are specified using the PIC32MX370 configuration variables. These are set using the `#pragma config` statement. Use `#pragma config FPLLIDIV` to set the input divider, `#pragma config FPLLMUL` to set the multiplication factor, and `#pragma config FPLLODIV` to set the output divider. Refer to the PIC32MX3XX/4XX Family Datasheet and the PIC32MX Family Reference Manual, Section Oscillators, for information on how to choose the correct values, as not all combinations of multiplication and division factors will work.

In addition to configuring the `SYSCLK` frequency, the peripheral bus clock, `PBCLK`, frequency is also configurable. The peripheral bus clock is used for most peripheral devices; particularly the clock used by the timers and serial controllers (UART, SPI, I2C). The `PBCLK` frequency is a division of the `SYSCLK` frequency selected using `#pragma config FPBDIV`. The `PBCLK` divider can be set to divide by 1, 2, 4, or 8.

The following example will set up the Basys MX3 for operation with a `SYSCLK` frequency of 80 MHz and a `PBCLK` frequency of 80 MHz.

```
#pragma config FNOSC = FRCPLL
#pragma config FSOSCEN = OFF
#pragma config POSCMOD = XT
#pragma config OSCIOFNC = ON
```

```
#pragma config FPBDIV =      DIV_1

#pragma config FPLLIDIV =    DIV_2
#pragma config FPLLMUL =     MUL_20
#pragma config FPLLODIV =    DIV_1
```

## 2 Power Supplies

The Basys MX3 requires a 5V power source to operate. This power source can come from the Programming / Debugging USB port (J12), the USB-UART (J10), or from an external 5V DC power supply that's connected to Power Jack (J11). These three power inputs are connected through Schottky diodes to form the primary input power network, VIN, which is used to power the onboard regulators and the majority of the onboard peripherals. No jumper is required to select the input power source. The board will automatically power on while the Power Switch (SW8) is in the on position and power is present on any of the power inputs.

A power-good LED (LD11), driven by the output of the 3.3V regulator (LMR10515), indicates that the board is receiving power and that the onboard supplies are functioning as expected. An overview of the Basys MX3 power circuit is shown in Fig 2.1.

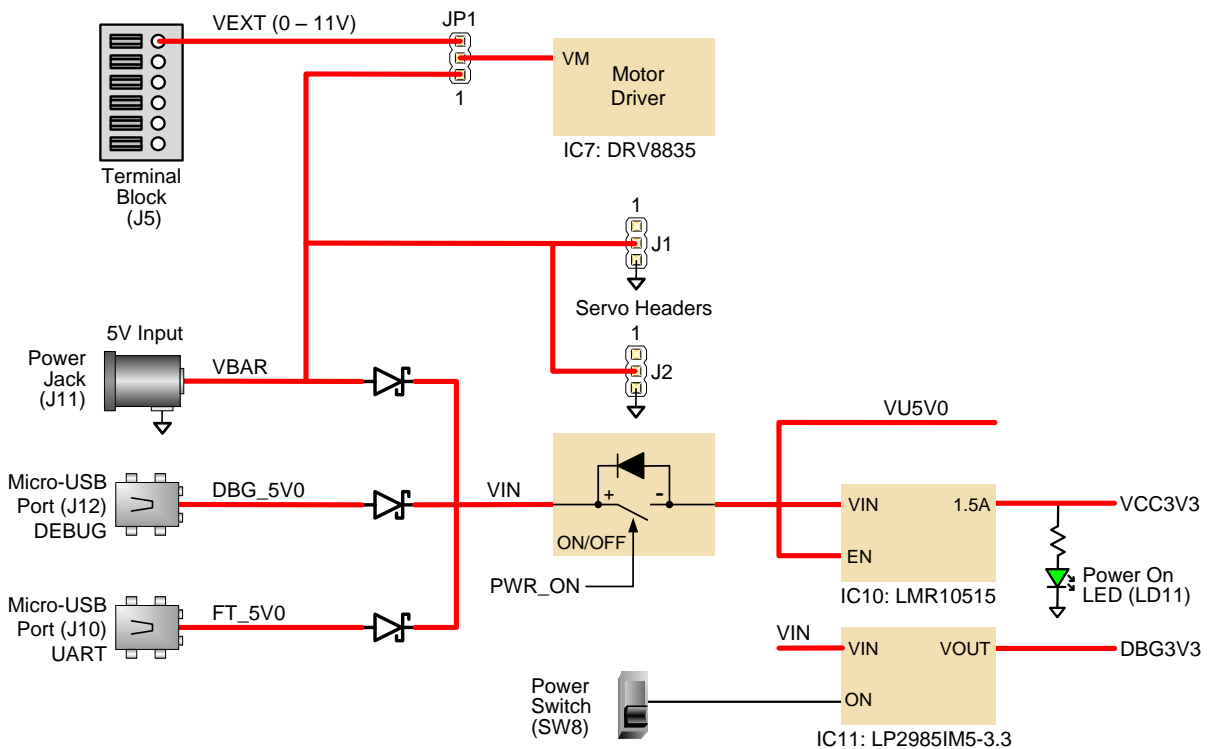


Figure 2.1. Power supply circuit.

The USB port(s) can deliver enough power for most designs; however, a few demanding applications, including any that drive multiple peripheral boards, may require more power than a USB port can provide. In these instances, an external power supply can be used. Due to their high current demands, motors and servos cannot be powered through either of the USB ports, and may only be powered through an external supply.

An external power supply can be used by plugging into Power Jack J11. The supply must use a coaxial, center-positive 2.0 mm internal-diameter plug, and provide a voltage of 5V DC (4.75V minimum, 5.5V maximum). The

supply should provide a minimum current of 2A if servos are to be used. Ideally, the supply should be capable of provide 20 Watts of power (5V DC, 4A). Many suitable supplies can be purchased from Digilent or other catalog vendors.

The onboard motor driver (Texas Instruments DRV8835) may be powered by a 5V supply connected to Power Jack J11, or by an external supply (0V-11V) connected to pins 1 and 2 of Terminal Block J5. Jumper JP1 is used to select which power source is used by the motor driver.

Supply	Circuits	Device	Current (max/typical)
3.3V (VCC3V3)	PIC32MX370, PMODs, and all onboard peripherals excluding the LCD backlight, RGB LED, IrDA LED, Servos, and Motors	IC10: Texas Instruments LMR10515	1.5A/NA
3.3V (DBG3V3)	Onboard Microchip Programmer/Debugger	IC11: Texas Instruments LP2985IM5-3.3	150mA/NA

Table 2.1. Power rail characteristics.

### 3 User LEDs

Eight LEDs are provided, labeled LD0 – LD7 on the board (and LED0 – LED7 on the schematic), attached to eight digital I/O pins. Controlling the LEDs is done by basic access to an output I/O pin. Read more details in the [Digital Inputs and Outputs](#) section.

Figure 3.1 shows the way the LEDs are electrically connected on the Basys MX3.

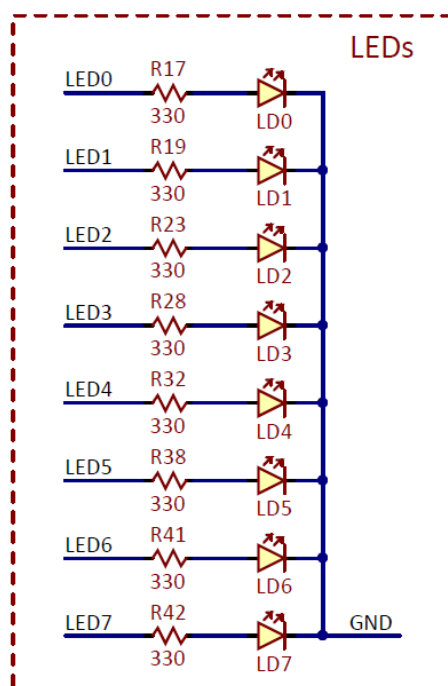


Figure 3.1. LED schematic diagram.

## 3.1 Connectivity

Label	Schematic name	PIC32 pin	Description
LD0	LED0	TMS/CTED1/RA0	Led 0
LD1	LED1	TCK/CTED2/RA1	Led 1
LD2	LED2	SCL2/RA2	Led 2
LD3	LED3	SDA2/RA3	Led 3
LD4	LED4	TDI/CTED9/RA4	Led 4
LD5	LED5	TDO/RA5	Led 5
LD6	LED6	TRCLK/RA6	Led 6
LD7	LED7	TRD3/CTED8/RA7	Led 7

Table 3.1. LED connectivity.

All the pins must be defined as digital output (their corresponding TRIS bit must be set to 0):

```
TRISAbits.TRISA<0-7> = 0; // LED<0-7> configured as output
```

## 3.2 Functionality

To turn an LED on or off, turn the corresponding digital output pin high or low by writing 1 or 0 to the corresponding LATA register bit.

```
LATABits.LATA<0-7> = 1; // turn led on
```

or

```
LATABits.LATA<0-7> = 0; // turn led off
```

Library functions for using the LEDs are contained in the Basys MX3 library pack, LED library; however, the user can easily use the LEDs without the LED library, as presented above.

## 4 User Switches

Eight switches are provided, labeled SW0 – SW7 on the board and in the schematic, attached to eight digital I/O pins of the PIC32. Reading the switches is done by basic access to an input I/O pin. Read more details in [Digital Inputs and Outputs](#) section.

Figure 4.1 shows the way the switches are electrically connected on the Basys MX3.

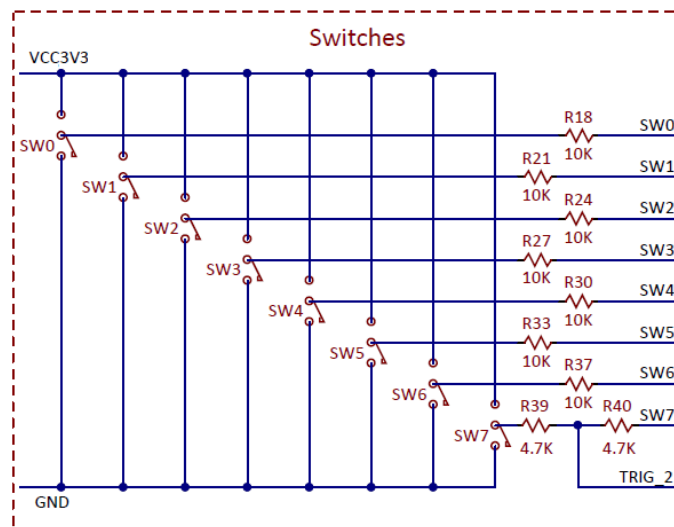


Figure 4.1. Switches schematic diagram.

## 4.1 Connectivity

Label	Schematic Name	PIC32 Pin	Pin Shared With	Description
SW0	SW0	RPF3/RF3		Switch 0
SW1	SW1	RPF5/PMA8/RF5		Switch 1
SW2	SW2	RPF4/PMA9/RF4		Switch 2
SW3	SW3	RPD15/RD15		Switch 3
SW4	SW4	RPD14/RD14		Switch 4
SW5	SW5	AN11/PMA12/RB11		Switch 5
SW6	SW6	CVREFOUT/AN10/RPB10/CTED11/PMA13/RB10		Switch 6
SW7	SW7	AN9/RPB9/CTED4/RB9	TRIG_2	Switch 7

Table 4.1. Switches connectivity.

All the pins must be defined as digital input: their corresponding TRIS bit must be set to 1, and analog function must be disabled for pins routed to SW5, SW6, and SW7.

```

TRISFbits.TRISF3 = 1; // RF3 (SW0) configured as input
TRISFbits.TRISF5 = 1; // RF5 (SW1) configured as input
TRISFbits.TRISF4 = 1; // RF4 (SW2) configured as input
TRISDbits.TRISD15 = 1; // RD15 (SW3) configured as input
TRISDbits.TRISD14 = 1; // RD14 (SW4) configured as input
TRISBbits.TRISB11 = 1; // RB11 (SW5) configured as input
ANSELBbits.ANSB11 = 0; // RB11 (SW5) disabled analog
TRISBbits.TRISB10 = 1; // RB10 (SW6) configured as input
ANSELBbits.ANSB10 = 0; // RB10 (SW6) disabled analog
    
```

```
TRISBbits.TRISB9 = 1;    // RB9 (SW7) configured as input
ANSELBbits.ANSB9 = 0;    // RB9 (SW7) disabled analog
```

## 4.2 Functionality

In order to read the switches, the user needs to read the corresponding digital input pin. A value of 1 indicates the switch as being on (high) or 0 indicates the switch as being off (low).

```
val = PORTFbits.RF3;    // read SW0
val = PORTFbits.RF5;    // read SW1
val = PORTFbits.RF4;    // read SW2
val = PORTDbits.RD15;   // read SW3
val = PORTDbits.RD14;   // read SW4
val = PORTBbits.RB11;   // read SW5
val = PORTBbits.RB10;   // read SW6
val = PORTBbits.RB9;    // read SW7
```

Library functions for using the switches are contained in the Basys MX3 library pack, SWT library; however, the user can easily use the switches without the SWT library, as presented above.

## 4.3 Shared Pins

As shown in the connectivity table above, SW7 driving signal is shared with the TRIG\_2 signal in 2x15 pins [Debug Header](#).

# 5 User Buttons

There are five buttons on the board, labeled BTNU, BTNL, BTNC, BTNR, BTND both on the board and in the schematic, attached to five digital I/O pins of PIC32. Reading the buttons is done by basic access to an input I/O pin. Read more details in [Digital Inputs and Outputs](#) section.

Figure 5.1 shows the way the buttons are electrically connected on the Basys MX3.



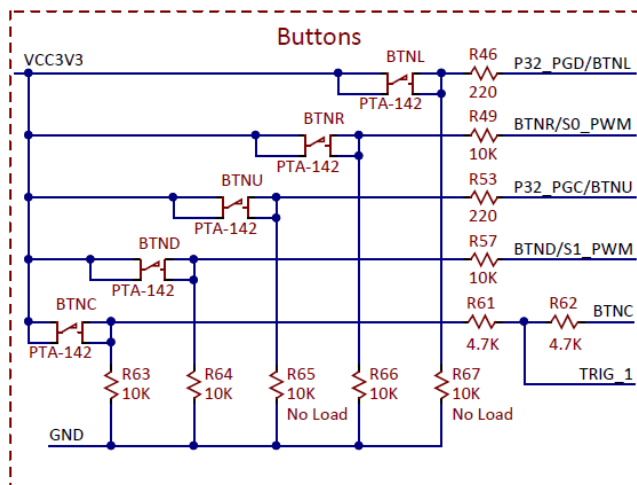


Figure 5.1. Button schematic diagram.

The Basys MX3 also has a red button labeled RESET. This button is connected directly to the MCLR pin of the PIC32 and will trigger it to be reset.

## 5.1 Connectivity

Label	Schematic Name	PIC32 Pin	Pin Shared With	Description
BTNU	BTNU	PGEC1/AN1/RPB1/CTED12/RB1	PGC	Button up
BTNL	BTNL	PGED1/AN0/RPB0/RB0	PGD	Button left
BTNC	BTNC	RPF0/PMD11/RF0	TRIG_1	Button center
BTNR	BTNR	AN8/RPB8/CTED10/RB8	SO_PWM	Button right
BTND	BTND	RPA15/RA15	S1_PWM	Button down

Table 5.1. Button connectivity.

All the pins must be defined as digital input: their corresponding TRIS bit must be set to 1, and analog function must be disabled for pins corresponding to BTNU, BTNL, BTNR, BTND.

```

TRISBbits.TRISB1 = 1; // RB1 (BTNU) configured as input
ANSELBbits.ANSB1 = 0; // RB1 (BTNU) disabled analog
TRISBbits.TRISB0 = 1; // RB1 (BTNL) configured as input
ANSELBbits.ANSB0 = 0; // RB1 (BTNL) disabled analog
TRISFbits.TRISF4 = 1; // RF0 (BTNC) configured as input
TRISBbits.TRISB8 = 1; // RB8 (BTNR) configured as input
ANSELBbits.ANSB8 = 0; // RB8 (BTNR) disabled analog
TRISAbits.TRISA15 = 1; // RA15 (BTND) configured as input
    
```

## 5.2 Functionality

To read the buttons, the user needs to read the corresponding digital input pin, a value of 1 indicating the button is pressed or 0 indicating the button is released:

```

val = PORTBbits.RB1;           // read BTNU
val = PORTBbits.RB0;           // read BTNL
val = PORTFbits.RF0;           // read BTNC
val = PORTBbits.RB8;           // read BTNR
val = PORTAbits.RA15;          // read BTND

```

Please note that if you want the buttons to trigger a specific functionality, proper software debouncing is required.

Library functions for using the buttons are contained in the Basys MX3 library pack, BTN library; however, the user can easily use the buttons without the BTN library, as presented above.

## 5.3 Shared Pins

As shown in the connectivity Table 5.1 above, some pins are shared:

- Buttons BTNL and BTNU share functions with PGD and PGC signals used for programming. Therefore, the following line should be inserted in the code, to disable their programming function.  

```
#pragma config JTAGEN = OFF
```
- Buttons BTNR and BTND share the pins with S0\_PWM and S1\_PWM, explained in [Servo headers](#) section, so these resources should be used exclusively.
- BTNC is shared with TRIG\_1 signal in [2x15 Pins Debug Header](#), so it can be used to trigger events in an Analog Discovery board experiment.

## 6 RGB LED

The Basys MX3 board contains one tri-color (RGB) LED. The LED allows the user to obtain any RGB color by configuring the R, G and B color components.

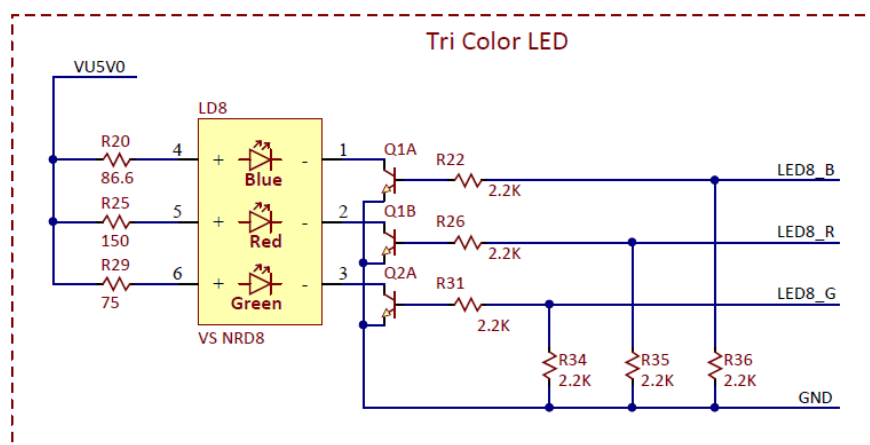


Figure 6.1. RGB LED schematic diagram.

The usage of the RGB LED is the same as controlling three separate LEDs, one for each color. Figure 6.1 shows the way the RGB LED is electrically connected on the Basys MX3.

There is one digital signal to control each color component. Using either 0 or 1 values for these signals will only give the user a limited number of colors (two colors for each component), so most of the time this is not enough in applications using the RGB feature. The solution is to send a sequence of 1 and 0 values on these digital lines, switched rapidly with a frequency higher than human perception. The “duty factor” will finally determine the color, as the human eye will “integrate” the discrete illumination values into the final color sensation.

The most used approach in solving this problem is the use of pulse-width modulation (PWM) signals. Another approach is the use of pulse-density modulation (PDM). These methods are explained in the [RGB LED Implemented Using PWM](#) and [RGB LED Implemented Using PDM](#) sections.

## 6.1 Connectivity

Label	Schematic Name	PIC32 Pin	Description
R	LED8_R	AN25/RPD2/RD2	Signal corresponding to the R component of the RGB
G	LED8_G	RPD12/PMD12/RD12	Signal corresponding to the G component of the RGB
B	LED8_B	AN26/RPD3/RD3	Signal corresponding to the R component of the RGB

Table 6.1. RGB LED connectivity.

## 6.2 Functionality

### 6.2.1 RGB LED Implemented Using PWM

The percentage of each period that the pulse is high determines the signals “duty cycle”. Figure 6.2 shows how different duty cycles are implemented using PWM.

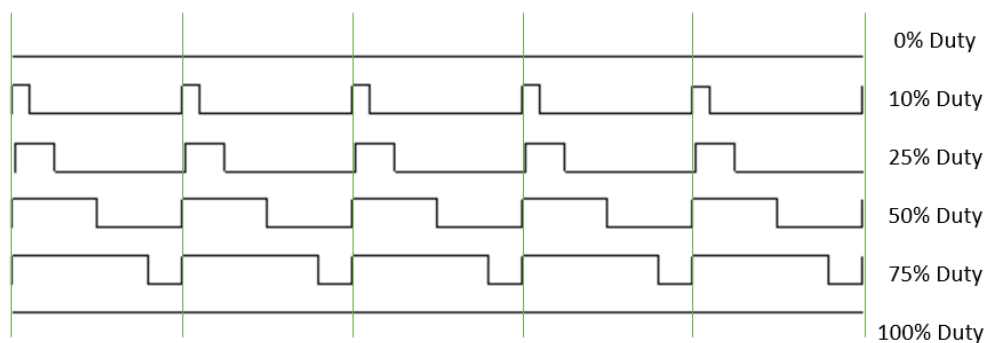


Figure 6.2. PWM duty cycle.

Using this method, the intensity of each component of the RGB LED is determined by the duty cycle being applied. PWM is most often implemented in the microcontroller using the output compare (OC) peripheral modules along with a timer.

One timer (Timer y) is assigned to the OC module. Setting the PRy register of the timer will set the PWM period. Setting the OCxRS register of the OC module will set the actual duty cycle.

The PIC32 datasheet displayed in Fig. 6.3 below explains how one period of the PWM is generated.

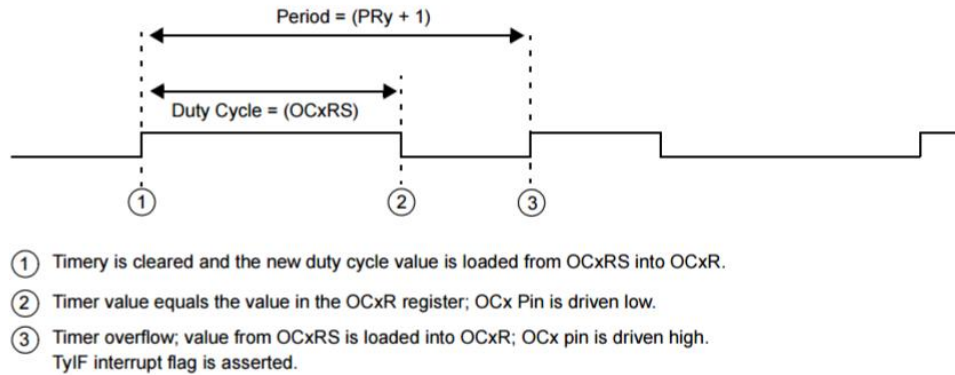


Figure 6.3. PIC32 PWM generation.

The RGBLED library from the Basys MX3 library pack contains a commented example of PWM implementation with the following features:

- LED8\_R, LED8\_G, and LED8\_B are mapped to OC3, OC5, and OC4.
- OC3, OC5, and OC4 are properly configured, together with assigned Timer 2.
- When a new color is set, its components (R, G, and B) are assigned to OC3RS, OC5RS, and OC4RS.

## 6.2.2 RGB LED Implemented Using PDM

PDM method adjusts both the frequency and length of the “High” pulses in the modulated signal.

A PDM is implemented using a register and an accumulator adder with carry output. The n-bit register can store any binary value from 0 to  $2^n - 1$ . In each clock period, the register content is added to the accumulator. The carry bit (overflow of the n-bit accumulator) is the output. It is “High” as often as the accumulator overflows, so that when large values are added, carry will occur often. The “High” pulse is only 1 clock period long, but more “High” pulses can succeed when the register content is close to maximum.

The RGBLED library from the Basys MX3 library pack contains an example of PDM implementation, with the following features:

- LED8\_R, LED8\_G, and LED8\_B are configured as simple digital outputs.
- Timer 5 is configured to generate an interrupt every approx. x us.
- Three 16-bit accumulators are used, one for each color.
- In the interrupt service routine, for each color, the 8-bit color value is added to the corresponding 16-bit accumulator.
- For each color, the 9<sup>th</sup> bit of the accumulator is considered the carry bit. The resulted carry bits are assigned to LED8\_R, LED8\_G, and LED8\_B.
- For each color, the accumulator is masked so that it only contains an 8-bit value (carry is cleared).

## 7 Seven-segment Display

The Basys MX3 board contains a four-digit common anode seven-segment LED display. Each of the four digits is composed of seven segments displaying a “figure 8” pattern and a decimal point with an LED embedded in each segment. Segment LEDs can be individually illuminated. Of the number of possible patterns, the ten corresponding to the decimal digits are the most useful.

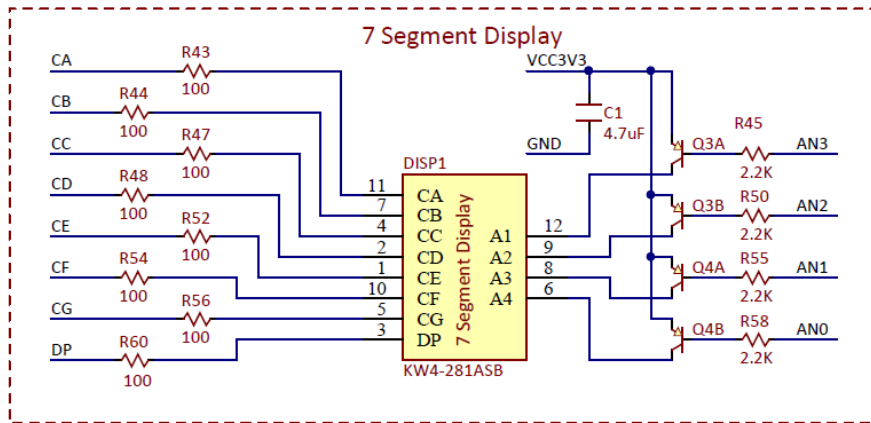


Figure 7.1. Seven-segment schematic diagram.

The anodes of the seven LEDs forming each digit are tied together into one “common anode” circuit node, but the LED cathodes remain separate, as shown in Fig. 7.2. The common anode signals are available as four “digit enable” input signals to the 4-digit display. The cathodes of similar segments on all four displays are connected into seven circuit nodes labeled CA through CG (so, for example, the four “D” cathodes from the four digits are grouped together into a single circuit node called “CD”). These seven cathode signals are available as inputs to the 4-digit display. This signal connection scheme creates a multiplexed display, where the cathode signals are common to all digits but they can only illuminate the segments of the digit whose corresponding anode signal is asserted.

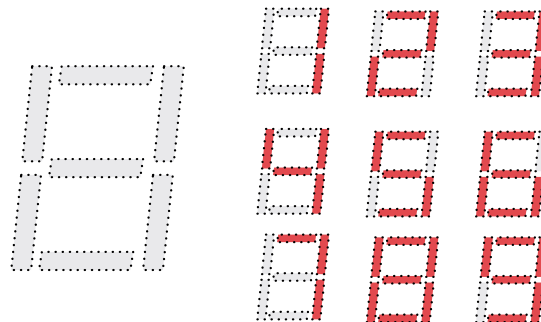


Figure 7.2. Seven-segment digits.

To illuminate a segment, the anode should be driven high while the cathode is driven low; however, since the Basys MX3 uses transistors to drive enough current into the common anode point, the anode enables are inverted. Therefore, both the AN0 ... AN3 and the CA ... G/DP signals are driven low when active.

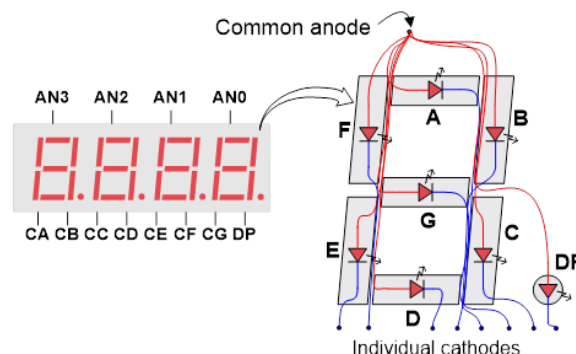


Figure 7.3. Common anode circuit node.

A scanning display controller circuit can be used to show a 4-digit number on this display. This circuit drives the anode signals and corresponding cathode patterns of each digit in a repeating, continuous succession at an update rate that is faster than the human eye can detect. Each digit is illuminated just one-fourth of the time, but because the eye cannot perceive the darkening of a digit before it is illuminated again, the digit appears continuously illuminated. If the update, or “refresh”, rate is slowed to around 45Hz, a flicker can be noticed on the display.

To make each of the four digits appear bright and continuously illuminated, all should be driven once every 1 to 16ms, with a refresh frequency of about 1kHz to 60Hz. For example, if every digit is refreshed every 3ms, corresponding to a frequency of 333Hz, the entire display will be refreshed every 12ms. The controller must drive low the cathodes with the correct pattern when the corresponding anode signal is driven high.

To illustrate the process:

1. If AN0 is asserted while CB and CC are asserted, then a “1” will be displayed in digit position 1.
2. If AN1 is asserted while CA, CB, and CC are asserted, a “7” will be displayed in digit position 2.
3. If AN0, CB, and CC are driven for 4ms, and then AN1, CA, CB, and CC are driven for 4ms in an endless succession, the display will show “71” in the first two digits. An example timing diagram for a four-digit controller is shown in Fig. 7.4.

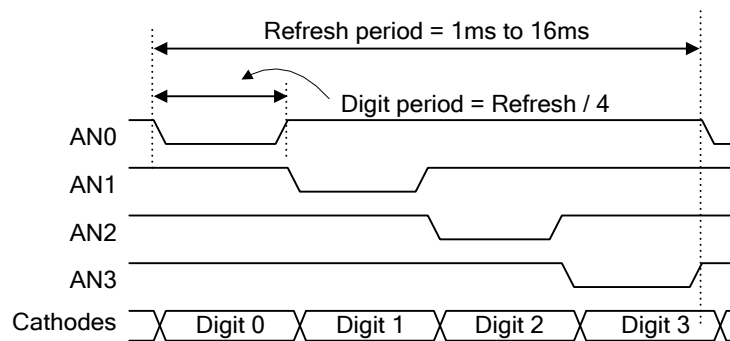


Figure 7.4. 4-digit scanning display controller timing diagram.

Please note that the two dots (situated between the middle digits) are not connected.

## 7.1 Connectivity

Name	PIC32 Pin	Description
AN0	AN12/PMA11/RB12	Anode 0 pin
AN1	AN13/PMA10/RB13	Anode 1 pin
AN2	VREF-/CVREF-/PMA7/RA9	Anode 2 pin
AN3	VREF+/CVREF+/PMA6/RA10	Anode 3 pin
CA	TRD1/RG12	Cathode A pin
CB	RPA14/RA14	Cathode B pin
CC	PMD14/RD6	Cathode C pin
CD	TRD0/RG13	Cathode D pin
CE	RG15	Cathode E pin
CF	PMD15/RD7	Cathode F pin
CG	PMD13/RD13	Cathode G pin
DP	TRD2/RG14	Cathode DP (decimal point) pin

Table 7.1. Seven-segment connectivity.

All the pins (AN0-3, CA-CG and DP) must be configured as digital output and Anode 0 and Anode 1 must have the analog functionality disabled:

```
TRISBbits.TRISB12 = 0; //RB12 set as output
ANSELBbits.ANSB12 = 0; //RB12 analog functionality disabled
TRISBbits.TRISB13 = 0; //RB13 set as output
ANSELBbits.ANSB13 = 0; //RB13 analog functionality disabled
TRISAbits.TRISA9 = 0; //RA9 set as output
TRISAbits.TRISA10 = 0; //RA10 set as output
TRISGbits.TRISG12 = 0; //RG12 set as output
TRISAbits.TRISA14 = 0; //RA14 set as output
TRISDbits.TRISD6 = 0; //RD6 set as output
TRISGbits.TRISG13 = 0; //RG13 set as output
TRISGbits.TRISG15 = 0; //RG15 set as output
TRISDbits.TRISD7 = 0; //RD7 set as output
TRISDbits.TRISD13 = 0; //RD13 set as output
TRISGbits.TRISG14 = 0; //RG14 set as output
```

## 7.2 Functionality

A seven-segment display controller is implemented in the SSD library of the Basys MX3 library pack. Here are some details on the implementation of the library:

- One array contains constant values for the segment's configurations (one bit for each segment) corresponding to various digits (0-9, A-F).
- When the user selects the values to be displayed, they are used as index into this segment's configuration table and the resulting configuration bytes are stored in global variables.
- Timer1 is used to generate interrupts every 3ms (corresponding to the period register PR1 = 3750).
- Every time the interrupt handler routine is called, the following operations are performed:
  - The next digit becomes the current digit, in a circular approach (thus each digit will be addressed once after 4 calls of the interrupt handler routine).
  - All digits are deactivated by outputting 1 to their corresponding anodes.
  - The cathodes are outputted according to the segment's information corresponding to the current digit.
  - The current digit is activated (0 is outputted to its corresponding anode).

## 8 LCD Module

The Basys MX3 features a basic LCD module, the Sunlike Display SD1602H. It displays two rows of 16 characters. It is controlled using a set of command signals (DISP\_RS, DISP\_R/W, DISP\_EN) and 8 data signals (DB0 - DB7). These signals make up a parallel port for communicating with the display.

The board also provides a switch to turn on and off the LCD display backlight, situated on the bottom right corner of the LCD display.

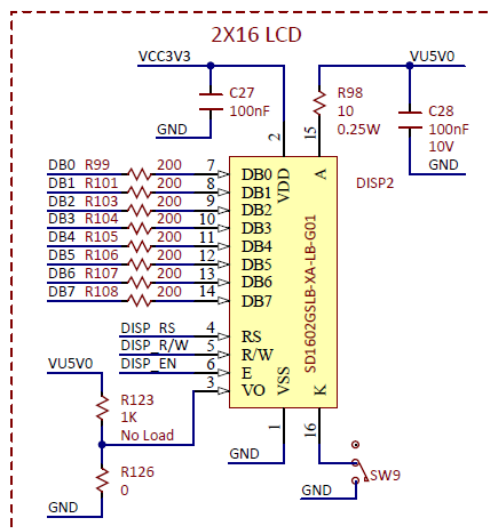


Figure 8.1. LCD schematic diagram.

The LCD display is controlled by a set of commands written to the device. Also, read commands provide the ability to read status and data. Please read the SD1602H datasheet for a detailed list of read and write commands. The LCD display requires a specific initialization sequence, also detailed in the datasheet.

The device features two types of memory: CGRAM and DDRAM.

The LCD controller contains a character-generator ROM (CGROM) with 192 preset 5×8 character patterns, a character-generator RAM (CGRAM) that can hold 8 user-defined 5×8 characters, and a display data RAM (DDRAM) that can hold 80 character codes. Character codes written into the DDRAM serve as indexes into the CGROM (or CGRAM). Writing a character code into a particular DDRAM location will cause the associated character to appear at the corresponding display location. Display positions can be shifted left or right by setting a bit in the instruction register (IR). The write-only IR directs display operations (such as clear display, shift left or right, set DDRAM address, etc.). A busy flag shows whether the display has completed the last requested operation; prior to initiating a new operation, the flag can be checked to see if the previous operation has been completed.

The display has more DDRAM locations than can be displayed at any given time. DDRAM locations 00H to 27H map to the first display row, and locations 40H to 67H map to the second row. Normally, DDRAM location 00H maps to the upper left display corner (the “home” location), and 40H to the lower left. Shifting the display left or right can change this mapping. The display uses a temporary data register (DR) to hold data during DDRAM /CGRAM reads or writes, and an internal address register to select the RAM location. Address register contents, set via the instruction register, are automatically incremented after each read or write operation. The LCD display uses ASCII character codes. Codes up through 7F are standard ASCII (which includes all “normal” alphanumeric characters). Codes above 7F produce various international characters.



The following timing diagrams detail how write and read processes must be implemented. The essential difference is the polarity of the DISP\_RW signal (0 for write and 1 for read). For more detailed timing information, refer to the SD1602H datasheet.

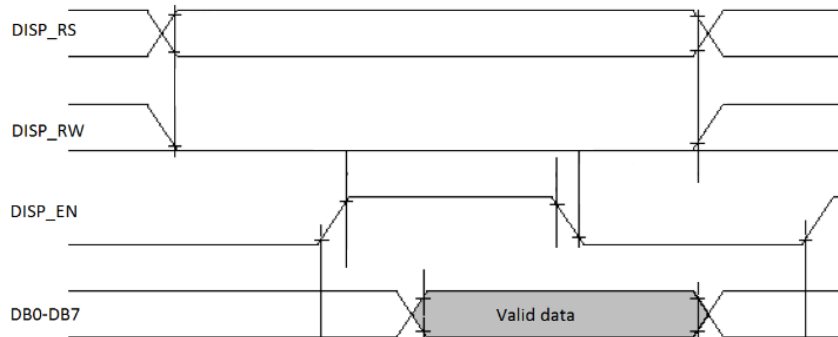


Figure 8.2. LCD write timing.

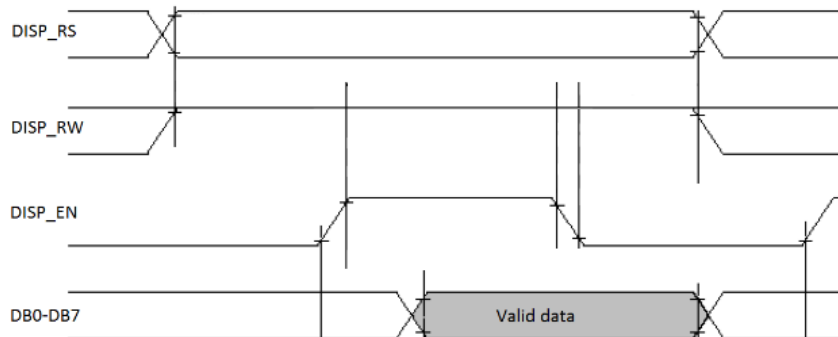


Figure 8.3. LCD read timing.

## 8.1 Connectivity

Name	PIC32 Pin	Description
DISP_RS	AN15/RPB15/OCFB/CTED6/PMA0/RB15	Register Select: High for Data Transfer, Low for Instruction Transfer.
DISP_RW	RPD5/PMRD/RD5	Read/Write signal: High for Read mode, Low for Write mode.
DISP_EN	RPD4/PMWR/RD4	Read/Write Enable: High for Read, falling edge writes data
DB0	PMD0/RE0	Data bits 0 -7.
DB1	PMD1/RE1	
DB2	AN20/PMD2/RE2	
DB3	RPE3/CTPLS/PMD3/RE3	
DB4	AN21/PMD4/RE4	
DB5	AN22/RPE5/PMD5/RE5	
DB6	AN23/PMD6/RE6	
DB7	AN27/PMD7/RE7	

Table 8.1. LCD connectivity.

The command pins (DISP\_RS, DISP\_RW and DISP\_EN) must be defined as digital output with analog functionality disabled for DISP\_RS:

```
TRISBbits.TRISB15 = 0; // RB15 (DISP_RS) set as an output
ANSELBbits.ANSB15 = 0; // disable analog functionality on RB15
(DISP_RS)
TRISDbits.TRISD5 = 0; // RD5 (DISP_RW) set as an output
TRISDbits.TRISD4 = 0; // RD4 (DISP_EN) set as an output
```

The data pins (DB0 – DB7) must be set as digital pins, with the direction according to the type of operation (read / write). The analog functionality should also be disabled for DB2, DB4, DB5, DB6, and DB7.

```
TRISEbits.TRISE0 = 1; // RE0 (DB0) set as input (change 1 to 0 for
output/write functionality)
TRISEbits.TRISE1 = 1; // RE1 (DB1) set as input (change 1 to 0 for
output/write functionality)
TRISEbits.TRISE2 = 1; // RE2 (DB2) set as input (change 1 to 0 for
output/write functionality)
ANSELEbits.ANSE20 = 0; // disable analog functionality on RE2 (DB2)
TRISEbits.TRISE3 = 1; // RE3 (DB3) set as input (change 1 to 0 for
output/write functionality)
TRISEbits.TRISE4 = 1; // RE4 (DB4) set as input (change 1 to 0 for
output/write functionality)
ANSELEbits.ANSE21 = 0; // disable analog functionality on RE4 (DB4)
TRISEbits.TRISE5 = 1; // RE5 (DB5) set as input (change 1 to 0 for
output/write functionality)
ANSELEbits.ANSE22 = 0; // disable analog functionality on RE5 (DB5)
TRISEbits.TRISE6 = 1; // RE6 (DB6) set as input (change 1 to 0 for
output/write functionality)
ANSELEbits.ANSE23 = 0; // disable analog functionality on RE6 (DB6)
TRISEbits.TRISE7 = 1; // RE7 (DB7) set as input (change 1 to 0 for
output/write functionality)
ANSELEbits.ANSE27 = 0; // disable analog functionality on RE7 (DB7)
```

## 8.2 Functionality

The recommended approach to controlling the LCD module is to use the LCD library of the Basys MX3 library pack. Features implemented:

- Low level read and write functionality are implemented using command / data pins, according to the parallel port approach described above.

- Basic commands are implemented using the low level read and write functions.
- The initialization sequence is implemented according to the implemented commands.
- Other functions include
  - Write to LCD screen.
  - Access the CGRAM and DDRAM memories.

## 9 I<sup>2</sup>C Interface

The inter-integrated circuit (I<sup>2</sup>C) interface provides a medium speed (100K or 400Kbps) synchronous serial communications bus. The I<sup>2</sup>C interface allows master and slave operation using either 7-bit or 10-bit device addressing. Each device is given a unique address, and the protocol can address packets to a specific device or to broadcast packets to all devices on the bus. Refer to the Microchip PIC32MX3XX/4XX Family Datasheet and the PIC32 Family Reference Manual for detailed information on configuring and using the I<sup>2</sup>C interface.

The PIC32MX370F512L microcontroller provides two independent I<sup>2</sup>C interfaces. The Basys MX3 is designed to offer dedicated access to one of these interfaces, I<sup>2</sup>C1 (pins SCL1 and SDA1), using the I<sup>2</sup>C daisy chain connector labeled I<sup>2</sup>C situated under the LCD. The other I<sup>2</sup>C interface, I<sup>2</sup>C2, is not available on the Basys MX3 board, since its pins (SCL2 and SDA2) are not wired to external connectors.

As mentioned in Section 1.4 [Remappable pins](#), I<sup>2</sup>C interfaces are not involved in pin remapping. The SCL1 and SDA1 don't need to be configured or managed, they are properly accessed through the I<sup>2</sup>C1 interface.

The I<sup>2</sup>C daisy chain connector provides two positions each for connecting to the I<sup>2</sup>C signals, power and ground. By using two-wire or four-wire MTE cables (available separately from Digilent) a daisy chain of multiple I<sup>2</sup>C-capable devices can be created.

One onboard I<sup>2</sup>C device is connected on the I<sup>2</sup>C1 interface: the accelerometer. See the [Accelerometer](#) section for more information on its use.

The I<sup>2</sup>C bus is an open-collector bus. Devices on the bus actively drive the signals low. The high state of the I<sup>2</sup>C signals is achieved by pull-up resistors when no device is driving the lines low. One device on the I<sup>2</sup>C bus must provide the pull-up resistors. On the Basys MX3, I<sup>2</sup>C1 has pull-up resistors attached to it. Generally, only one device on the bus will need to have the pull-ups enabled.

Detailed information about the operation of the I<sup>2</sup>C peripherals can be found in the PIC32 Family Reference Manual, Section 24, Inter-Integrated Circuit.

The following table details the content of the I<sup>2</sup>C connector (the col1 and col2 columns correspond to the two parallel rows of pins):

Label on the Board	Left Column	Right Column	PIC32 Pin
SCL	SCL	SCL	SCL1/RG2
SDA	SDA	SDA	SDA1/RG3
GND	GND	GND	GND
V	3V3	3V3	VCC3V3

Table 9.1. I<sup>2</sup>C connector pinout.

## 10 Accelerometer

Basys MX3 provides an onboard accelerometer: NXP’s MMA8652FCR1. It is a 3-axis, 12-bit digital accelerometer, exposing an I<sup>2</sup>C digital interface. It is possible to use its ACL\_INT2 pin for raising a programmable interrupt.

The accelerometer is located on the top of the board; you can recognize the arrows that show the directions of the three axes.

The Fig. 10.1 shows the way Accelerometer is controlled using digital signals.

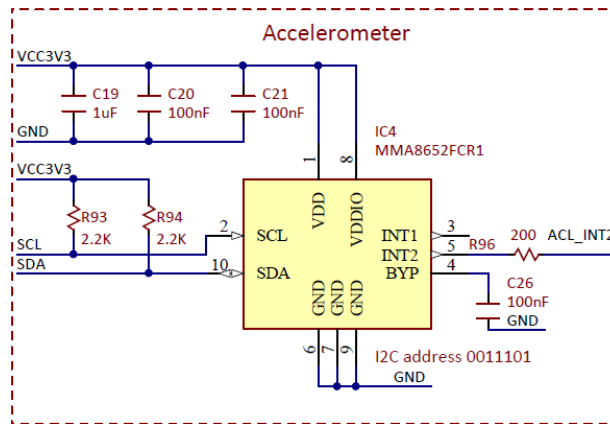


Figure 10.1. Accelerometer schematic diagram.

### 10.1 Connectivity

The accelerometer is connected to SCL1 and SDA1 lines of the I<sup>2</sup>C1 interface. A general I/O signal is connected to INT2 pin.

Schematic Name	PIC32 pin	Description
SCL	SCL1/RG2	I2C Clock signal
SDA	SDA1/RG3	I2C Data signal
ACL_INT2	RPG0/PMD8/RG0	Programmable Interrupt

Table 10.1. Accelerometer connectivity.

### 10.2 Functionality

To use the accelerometer, proper I<sup>2</sup>C communication (read, write) must be implemented over I<sup>2</sup>C1. The I<sup>2</sup>C1 interface must be initialized, and then accessed through read and write functions. The I<sup>2</sup>C device address of the accelerometer is 0x1D.

Communication over the I<sup>2</sup>C is implemented in the ACL library of the Basys MX3 library pack. If the user wants to use the accelerometer without the ACL library, they must implement their own I<sup>2</sup>C functions.

The accelerometer has a set of registers that can be written to configure the device and read to access the data collected by the accelerometer.

Note that you can visualize the communication with the accelerometer by attaching a logic analyzer to the 8-pin I<sup>2</sup>C connector, located on the top of the board.

Please read the MMA8652FCR1 documentation for more details.

## 10.3 Shared Pins

The Accelerometer shares the I<sup>2</sup>C1 pins with other devices that can be connected using the interface connector (detailed in the [I<sup>2</sup>C Interface](#) section).

# 11 Serial Peripheral Interface

Serial peripheral interface (SPI) is a four-wire synchronous serial interface and devices can operate as either an SPI master device or as an SPI slave device. The four SPI signals are generally called Slave Select (SS), Master Out Slave In (MOSI), Master In Slave Out (MISO), and Serial Clock (SCK). The master device generates MOSI, SS, and SCK. The SS signal is used to enable the slave device. It is only necessary to use a dedicated \_SS signal when using the PIC32's SPI controller in slave mode, because in master mode any general purpose I/O pin can be used to generate SS.

The PIC32MX370F512L microcontroller provides two serial peripheral interfaces: SPI1 and SPI2 (see [SPI1](#) and [SPI2](#) sections). These hardware interfaces implement the MOSI, MISO, and SCK behavior and leave SS to be handled by the user.

The PIC32 microcontroller labels the SPI signals as: Slave Select (SS), Serial Data Out (SDO), Serial Data In (SDI), and Serial Clock (SCK). When the PIC32 microcontroller is enabled as a master device, SDO serves the purpose of MOSI and SDI serves the purpose of MISO. When the PIC32 microcontroller is operating as an SPI slave device, SDI serves the purpose of MOSI and SDO serves the purpose of MISO.

Detailed information about the operation of the SPI peripherals can be found in the PIC32 Family Reference Manual, Section Serial Peripheral Interface.

## 11.1 SPI1

SPI1 is used for the onboard [Flash memory](#).

There is also a connector labeled SPI (J6) on the bottom that exposes the SPI1 signals. Assuming that another digital output pin is used for slave select, SPI1 signals can be used in order to connect another slave SPI device using this connector. Please read the Flash memory section for details about connecting to SPI1.

## 11.2 SPI2

It is possible to configure SPI2 to be accessed using the pins of PMOD A. The SPI2\_SS, SPI2\_SCK, and SPI2\_SI pins should be configured as digital output, while the SPI2\_SO pin must be configured as digital input.

Note that RC1(SPI2\_SI) and RC4 (SPI2\_SO) need to be remapped to perform SDO2 and SDI2 functions. Also, note that the naming of the signals is reversed, as SPI2\_SI and SPI2\_SO are named from slave perspective, while SDO2 and SDI2 are named from the microcontroller perspective.

PMODA pin	Function	PIC32 pin	Needed mapping for SPI2
JA1	SPI2_SS	RPC2/RC2	
JA2	SPI2_SI	RPC1/RC1	RPC1R = 0x06; // SDO2 – RC1
JA3	SPI2_SO	RPC4/CTED7/RC4	SDI2R = 0x0A; // SDI2 – RC4

PMODA pin	Function	PIC32 pin	Needed mapping for SPI2
JA4	SPI2_SCK	AN16/C1IND/RPG6/SCK2/PMA5/RG6	

Table 11.1. SPI connectivity.

Communication over the SPI2 interface is implemented in the SPIJA library of the Basys MX3 library pack. If the user wants to use the SPI2 without the SPIJA library, they must define their own SPI functions.

## 12 Flash Memory

The Basys MX3 comes with 4 MB of onboard flash memory. The part used is the Spansion S25FL132 and is an SPI memory. More information about the SPI interface is found in the [Serial Peripheral Interface](#) section.

Figure 12.1 depicts the way the Flash memory is controlled by digital signals.

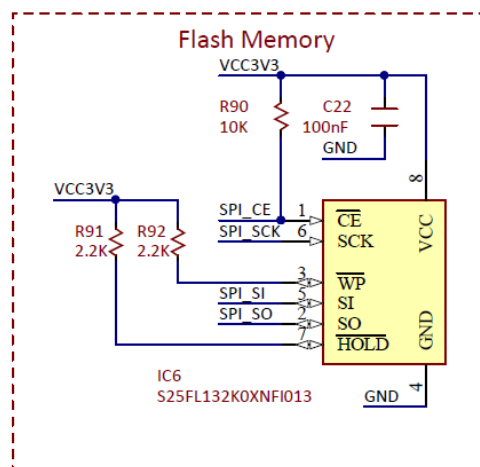


Figure 12.1. Flash memory schematic diagram.

It contains 1024 sectors of 4 KB, making the total capacity 4MB. The following table, shown in Table 12.1 extracted from the S25FL132K datasheet, shows the main memory address map.

Sector Size	Sector Count	Sector Range	Address Range (Byte Address)	Notes
4	1024	SA0	000000h-000FFFh	Sector Starting Address
		:		--
		SA1023	3FF000h-3FFFFFFh	Sector Ending Address

Table 12.1. Flash address map.

Please read the S25FL132K documentation for more details.

### 12.1 Connectivity

The flash memory is connected to the following pins that provide access to the SPI1 interface. Note that RF2 (SPI\_SI) and RF7 (SPI\_SO) need to be remapped to perform SDO1 and SDI1 functions.

The SPI\_CE, SPI\_SCK, and SPI\_SI pins should be configured as digital output, while the SPI\_SO pin must be configured as digital input.

Name	Label on J6	PIC32 pin	Needed mapping for SPI1
SPI_CE	CE	RPF8/RF8	
SPI_SI	SI	RPF2/RF2	RPF2R = 0x08; // SDO1 – RF2
SPI_SO	SO	RPF7/RF7	SDI1R = 0x0F; // SDI1 – RF7
SPI_SCK	SCK	RPF6/SCK1/INT0/RF6	

Table 12.2. Flash connectivity.

## 12.2 Functionality

To use the flash memory, the SPI pins must be properly configured to implement SPI1 functions (see [Section 12.1](#) above). Then, proper SPI communication (read, write) must be implemented over SPI1. The SPI1 interface must be initialized and then accessed through read and write functions.

Flash communication is implemented in the SPIFLASH library of the Basys MX3 library pack. If a user wants to use the SPI flash without the SPIFLASH library, they must implement their own SPI functions.

Note that users can visualize the communication with the SPI flash using a connector labeled SPI (J6), located on the back of the board under PMOD A connector.

## 13 UART

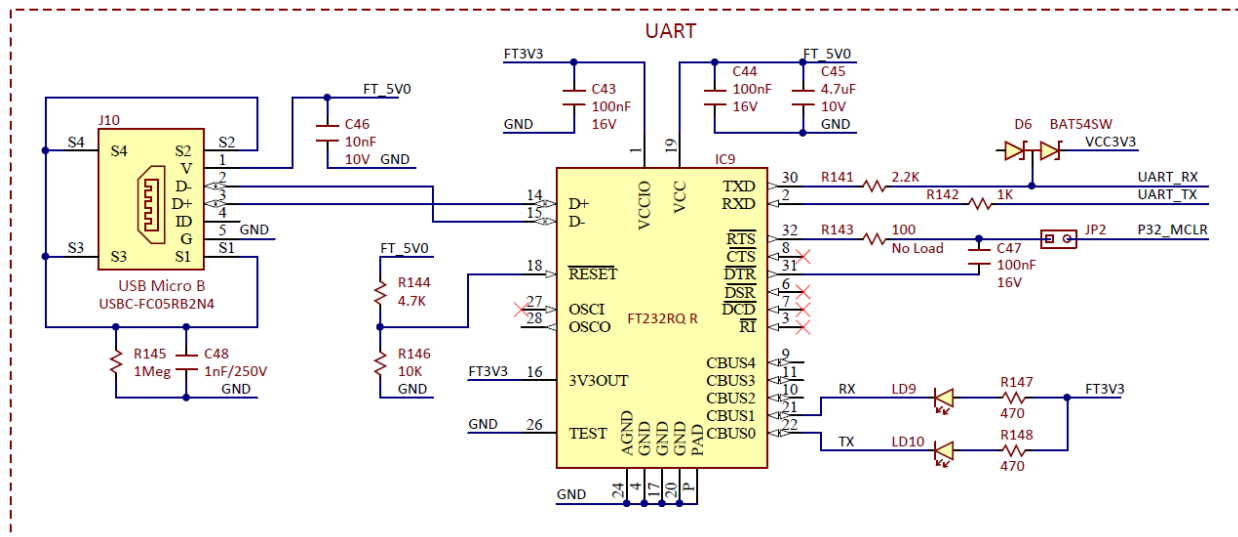


Figure 13.1. UART schematic diagram.

The PIC32MX370F512L microcontroller provides five UART interfaces: UART1, UART2, ..., UART5. Each UART can provide either a 2-wire or a 4-wire asynchronous serial interface. The 2-wire interface uses only receive (RX) and transmit (TX) signals. The 4-wire interface includes request-to-send (RTS) and clear-to-send (CTS) in addition to receive and transmit signals.

The Basys MX3 provides a USB to UART serial converter, via a micro-USB connector and uses UART\_TX and UART\_RX pins of the PIC32. These 2 pins can be mapped to implement UART4 or UART5 functionality. See [Remappable pins](#) section for more details about remapping.

Besides the UART port mapped to the USB\_UART interface, other UART interfaces can be mapped to the Pmod's pins, depending on the remappable functionality available. See [Pmod Connectors](#) for more details.

## 13.1 Connectivity

The following table shows the signals that go to the USB-Serial module from PIC32.

Name	PIC32 pin
UART_TX	RPF12/RF12
UART_RX	RPF13/RF13

Table 13.1. UART connectivity.

The UART\_TX must be defined as digital output and the UART\_RX as a digital input:

```
TRISFbits.TRISF12 = 0; //RF12 (UART_TX) set as an output
TRISFbits.TRISF13 = 1; //RF13 (UART_RX) set as an input
```

## 13.2 Functionality

The USB-UART converter module functionality is implemented in the UART library of the Basys MX3 library pack. Implementation features:

- USB-UART converter signals are mapped over the UART4 communication signals:
  - U4RXR = 0x09; // UART\_RX (RF13) -> U4RX
  - RPF12R = 0x02; // UART\_TX (RF12) -> U4TX
- Send and receive functions over UART are implemented in the library.

If the users want to use the UART module without the UART library, they need to implement their own UART functionality.

## 14 Motor Driver

The Basys MX3 features a Dual H-Bridge Motor Driver. The part used is the Texas Instruments DRV8835. It supports up to two 1.5A brushed DC motors or one stepper motor.

The PIC32 uses 5 signals: MODE, AIN1, AIN2, BIN1, BIN2, to connect to the motor driver MODE, AIN1/APHASE, AIN2/AENBL, BIN1/BPHASE, BIN2/BENBL control pins.

The Basys MX3 board provides a 6-pin wire-to-board terminal block that allows firm contact to the motor driver pins using a screwless, tension clamped connector labeled MOTOR OUT (J5 on the schematic). The control signals are labeled A1, A2, B1, B2, and they correspond to AOUT1, AOUT2, BOUT1, BOUT2 signals of motor driver.



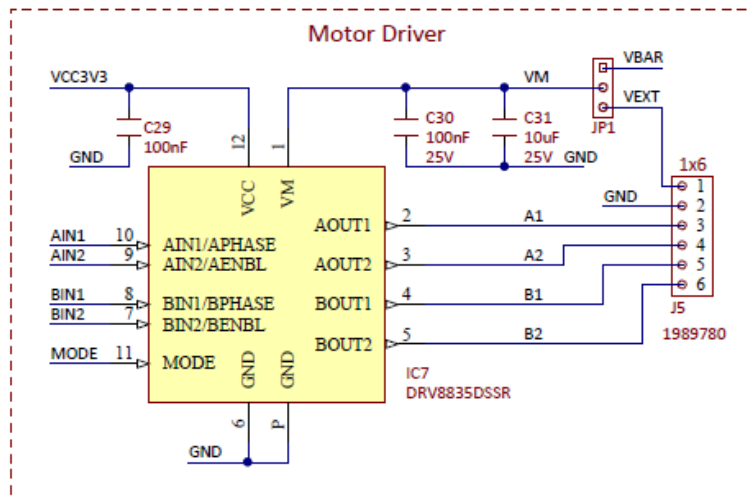


Figure 14.1. Motor driver schematic diagram.

The MODE signal selects one of the two operating modes: logic low selects IN/IN mode, while logic high selects PH/EN mode.

When using IN/IN mode, the logical values of AIN1, AIN2, BIN1, BIN2 control the 4 command signals of a stepper motor: A1, A2, B1, B2.

When using PH/EN mode:

- AIN1, AIN2 signals (through their APHASE, AENABLE functions) control the Phase (direction) and Enable of the H Bridge - the DC motor A (outputs A1, A2) driver
- BIN1, BIN2 signals (through their BPHASE, BENABLE function) control the Phase (direction) and Enable of the H Bridge - the DC motor B (outputs B1, B2) driver.

The voltage on the output pins A1, A2, B1, B2 is dependent of the motor supply power applied to the motor controller. It is possible to use the VBAR power pin (5V - the power from the external barrel), or an external power supplied by the user using the VEXT / GND pins of the MOTOR OUT connector block (0V to 11V). These two options are selectable using the MOTOR PWR jumper block (situated just above the MOTOR OUT connector).

Using the motors with the jumper on the VBAR position requires external power source connected to the barrel power connector.

The Table 14.1 details the usage of the MOTOR PWR jumper block:

Jumper position	Description
VBAR	The power provided from the external power supply (using the barrel connector) is used for motors.
VEXT	The power VEXT provided from an external supply (using the VEXT pin of the MOTOR OUT connector block) is used for motors.

Table 14.1. Motor power selection.

Please read the Texas Instruments DRV8835 datasheet for more details about the motor controller.

## 14.1 Connectivity

Table 14.2 shows the signals connecting the Motor Driver to the PIC32.

Name	PIC32 pin	Motor Driver pin	Description
MODE	RPF1/PMD10/RF1	MODE	logic low selects IN/IN mode logic high selects PH/EN mode
AIN1	PGED3/AN3/C2INA/RPB3/RB3	AIN1/APHASE	IN/IN mode: Logic high sets AOUT1 high PH/EN mode: Sets direction of H-bridge A
AIN2	RPE8/RE8	AIN2/AENBL	IN/IN mode: Logic high sets AOUT2 high PH/EN mode: Logic high enables H-bridge A
BIN1	RPE9/RE9	BIN1/BPHASE	IN/IN mode: Logic high sets BOUT1 high PH/EN mode: Sets direction of H-bridge B
BIN2	AN5/C1INA/RPB5/RB5	BIN2/BENBL	IN/IN mode: Logic high sets BOUT2 high PH/EN mode: Logic high enables H-bridge B

Table 14.2. Motor connectivity.

The command pins (MODE, AIN1, AIN2, BIN1, BIN2) must be defined as digital output and the analog functionality for AIN1 and BIN2 disabled:

```
TRISFbits.TRISF1 = 0; //set RF1 (MODE) to be an output
TRISBbits.TRISB3 = 0; //set RB3 (AIN1) to be an output
ANSELBbits.ANSB3 = 0; //disable analog functionality for RB3 (AIN1)
TRISEbits.TRISE8 = 0; //set RE8 (AIN2) to be an output
TRISEbits.TRISE9 = 0; //set RE9 (BIN1) to be an output
TRISBbits.TRISB5 = 0; //set RB5 (BIN2) to be an output
ANSELBbits.ANSB5 = 0; //disable analog functionality for RB5 (BIN2)
```

The following signals are routed to the MOTOR\_OUT board to wire connector:

Connector Label	Motor Driver pin	Description
VEXT	-	The external power that can be applied to the motors, selected using MOTOR PWR jumper block (0 to 11 Volts)
GND	-	The GND for the external power applied on VEXT
A1	AOUT1	IN/IN mode: Signal 1 of the stepper motor PH/EN mode: Signal 1 of the DC motor A
A2	AOUT2	IN/IN mode: Signal 2 of the stepper motor PH/EN mode: Signal 2 of the DC motor A
B1	BOUT1	IN/IN mode: Signal 3 of the stepper motor PH/EN mode: Signal 1 of the DC motor B
B2	AOUT2	IN/IN mode: Signal 4 of the stepper motor PH/EN mode: Signal 2 of the DC motor B

Table 14.3. Motor connector pinout.

## 14.2 Functionality

The control of Motor module is implemented in the MOT library of the Basys MX3 library pack. Features of the implementation:

- Mode selection is implemented by setting the digital output MODE pin.
- Separate functionalities are implemented, corresponding to the two modes: IN/IN and PH/EN.
- in IN/IN mode, the 4 control pins AIN1, AIN2, BIN1, BIN2 are used as digital outputs, in this manner:
  - They are initialized in a (1, 1, 0, 0) configuration, considered an unsigned hexadecimal value 0x0C.
  - To perform stepper motor steps, the configuration value is rotated left or right (according to the motor’s direction) with the desired number of steps.
- In PH/EN mode, the AIN1 and BIN1 are used as outputs, while the AIN2 and BIN2 are mapped to OC2 and OC3 modules, which are configured to generate PWM signals. The control of the 2 DC motors is done like this:
  - The direction is set to digital output AIN1 (DC motor A) or BIN1 (DC motor B)
  - The speed of the motor is implemented by loading the OC2RS (DC motor A) or OC3RS (DC motor B) registers with the desired values

If the user wants to use the Motor driver module without the MOT library, they must implement their own Motor driver control functionality and can use the code in the library as a reference.

## 15 Servo Headers

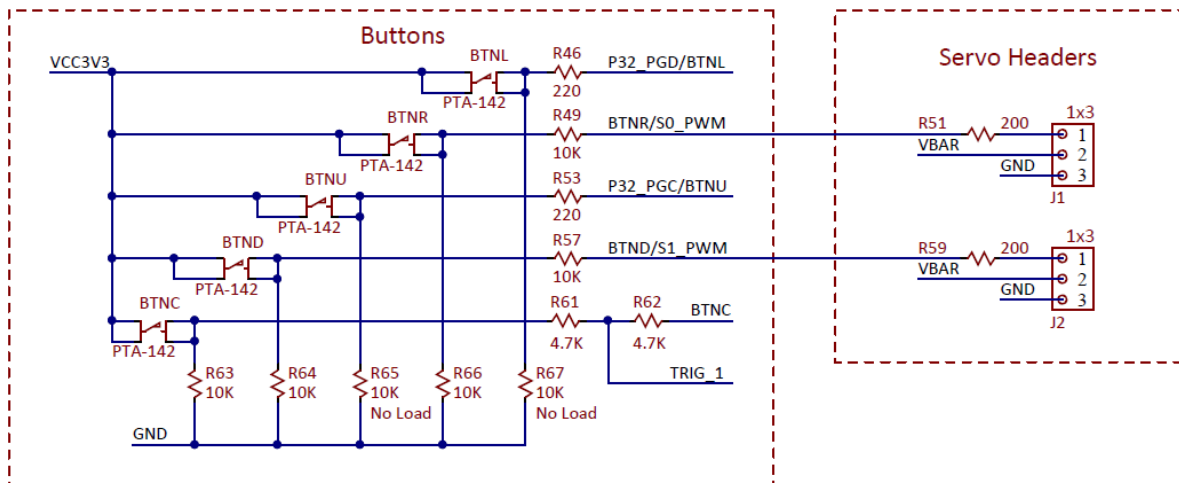


Figure 15.1. Servo header schematic diagram.

The Basys MX3 provides two 3-pin servo headers, labeled SERVO 0 and SERVO 1.

Servo motors are designed to move to a precise desired position and then stop, and are composed of a control board, motor, sense potentiometer, and gears that connect the motor and output shaft. A digital signal is sent to the control board which then drives the motor until the sense potentiometer verifies that the output shaft is in the correct position.

All servos come with three wires: power, ground, and control. Pulses are sent via the control wire and a pulse-width modulation signal controls the direction and degree of rotation. Usually servos are designed with limited rotation angles like 60°, 90°, 180°, and so on.

Using the control signals exposed by the two servo connectors, called S0\_PWM and S1\_PWM, the PIC32 can command the servos attached to the two connectors. Since the control should use the PWM functionality, these pins need to be mapped over output compare modules OC5 and OC4.

Each servo motor connector exposes the barrel voltage (5V) together with the GND. This means using the servo headers requires that an external power supply is connected to the barrel power connector.

## 15.1 Connectivity

Table 15.1 below shows the content of the two servo headers, providing details on S0\_PWM and S1\_PWM signals.

Connector	Label on the Servo Connector	Signal Name	PIC32 pin	Description
SERVO 0	PWM	S0_PWM	AN8/RPB8/CTED10/RB8	The control signal for servo 0
	VBAR	VBAR		The power VBAR (5V) and GND provided from the external power supply (using the barrel connector), to be used for servo 0
	GND	GND		
SERVO 1	PWM	S1_PWM	RPA15/RA15	The control signal for servo 1
	VBAR	VBAR		The power VBAR (5V) and GND provided from the external power supply (using the barrel connector), to be used for servo 1
	GND	GND		

Table 15.1. Servo header connectivity.

The S0\_PWM and S1\_PWM pins will be used as digital output pins:

- The corresponding TRIS bit must be set to 0:
 

```
TRISBbits.TRISB8 = 0;
TRISAbits.TRISA15 = 0;
```
- The ANSEL bit corresponding to S0\_PWM should be set to 0:
 

```
ANSELBbits.ANSB8 = 0;
```

## 15.2 Functionality

Servo motor driver functionality is implemented in the SRV library of the Basys MX3 library pack. Implementation features include:

- RB8 is mapped to OC5
 

```
RPB8R = 0x0B; // 1011 = OC5
```
- RA15 is mapped to OC4
 

```
RPA15R = 0x0B; // 1011 = OC4
```
- OC5 and OC4 are properly configured, together with associated Timer 3

- Configuration functions are implemented for each servo. These functions configure OC5RS or OC4RS according to the desired duty.

If users want to control the servos without the SRV library, they must implement their own servo control functionality.

### 15.3 Shared Pins

As you can see from the schematic, the S0\_PWM signal shares the same PIC32 pin with BTNR and the S1\_PWM signals shares the same PIC32 pin with BTND (see [User Buttons](#)). These buttons should not be used in designs that are also using servos.

## 16 IrDA Module

Basys MX3 features an onboard FIR-compatible IrDA module. The part used is the ROHM Semiconductor RPM973-H11. The RPM973-H11 is a high-performance IrDA module that integrates an infrared remote control transmission function and a high-speed (4Mbps) FIR-compatible IrDA module. It features an LED for transmitting and a PIN photo diode for receiving.

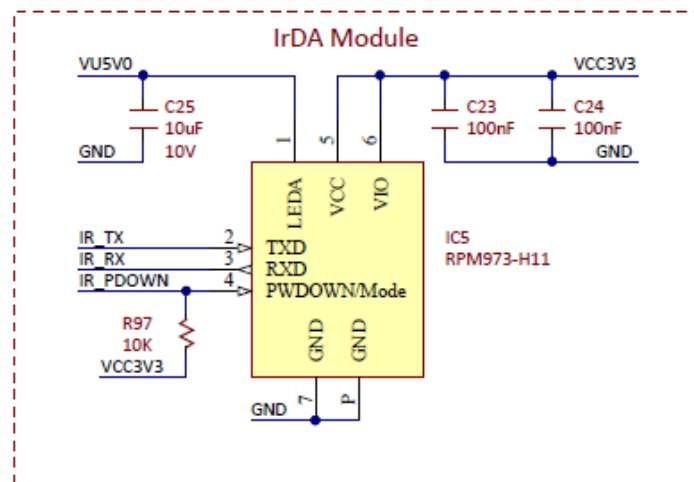


Figure 16.1. IrDA schematic diagram.

The PIC32 communicates with the IrDA module via two pins (named from PIC32 perspective): IR\_TX, connected to the TXD pin of the RPM973 and used for transmitting over IRDA, and IR\_RX, connected to the RXD pin of the RPM973 and used for receiving data over IrDA. Also, an IR\_PDOWN signal, connected to the PWDOWN pin of the RPM973, is used by the microcontroller to enable (0 value) or disable (1 value) the module.

When TXD (IR\_TX) is 1, the transmitting LED of the RPM973 module is lit. When the PIN photo diode detects light, it outputs 1 on RXD (IR\_RX).

### 16.1 Connectivity

The following table shows the signals connecting the IRDA module to the PIC32:

Name	PIC32 pin	IRDA module pin
IRDA_PDOWN	RPG1/PMD9/RG1	PWDOWN/Mode

Name	PIC32 pin	IRDA module pin
IR_TX	PGED2/AN7/RPB7/CTED3/RB7	TXD
IR_RX	PGEC2/AN6/RPB6/RB6	RXD

Table 16.1. IrDA connectivity.

The IRDA\_PDOWN and IR\_TX must be defined as digital outputs and disable the analog functionality on IR\_TX:

```
TRISGbits.TRISG1 = 0; //set RG1 (IRDA_PDOWN) as an output
```

```
TRISBbits.TRISB7 = 0; //set RB7 (IR_TX) as an output
```

```
ANSELBbits.ANSB7 = 0; //disable analog functionality on RB7 (IR_TX)
```

The IR\_RX must be defined as digital input and the analog functionality disabled:

```
TRISBbits.TRISB6 = 1; //set RB6 (IR_RX) as an input
```

```
ANSELBbits.ANSB6 = 0; //disable analog functionality on RB6 (IR_RX)
```

## 16.2 Functionality

The control of the IrDA module is implemented in the IrDA library of the Basys MX3 library pack. Library features include:

- IRDA\_PDOWN is used as a basic digital output pin.
- IRDA communication signals are mapped over the UART5 communication signals:
  - U5RXR = 0x05; // IR\_RX (RB6) -> U5RX
  - RPB7R = 0x04; // IR\_TX (RB7) -> U5TX
- UART5 interface is configured in the IrDA mode (the IREN bit is set) with 9600 baud and used for sending and receiving data to IrDA module.

If the users want to use the IrDA module without the IrDA library, they need to implement their own IrDA functionality.

# 17 Audio Out

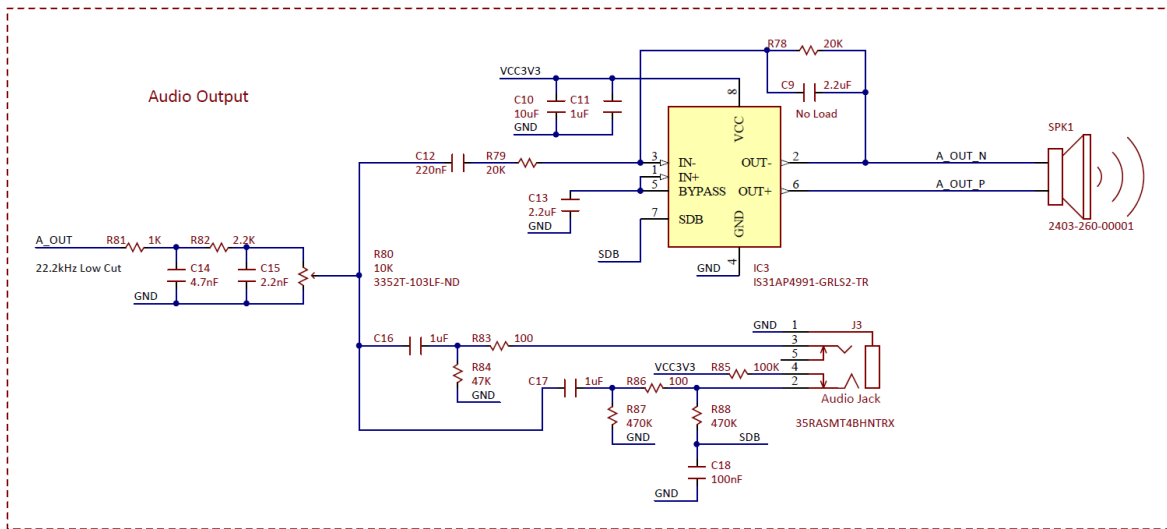


Figure 17.1. Audio out schematic diagram.

The Basys MX3 contains an audio out module, controlled by the PIC32 using the digital signal A\_OUT. This digital signal is PWM controlled to generate multiple values between 0 and 3.3V. A PWM signal is a chain of pulses generated at fixed frequency, with each pulse potentially having a different width. This digital signal can be passed through a simple low-pass filter that integrates the digital waveform to produce an analog voltage proportional to the average pulse-width over some interval (the interval is determined by the cut-off frequency of the low-pass filter and the pulse frequency). For example, if the pulses are high for an average of 10% of the available pulse period, then an integrator will produce an analog value that is 10% of the Vdd voltage, in this case .33V. Figure 17.2 shows a waveform represented as a PWM signal.

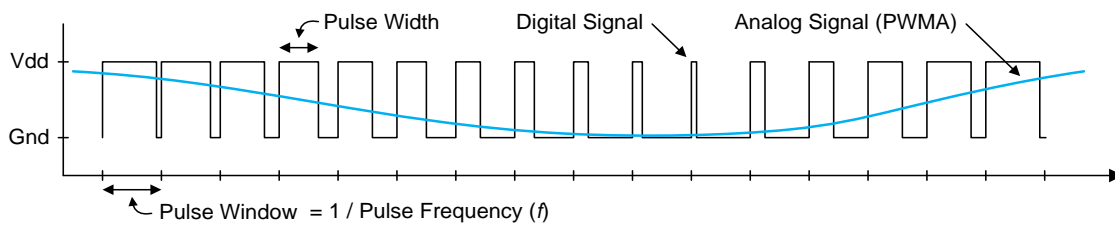


Figure 17.2. Waveform represented as a PWM signal.

The volume of the output audio signal can be adjusted using a thumbwheel potentiometer labeled SPEAKER VOLUME, situated in the top left corner of the board.

The generated audio out signal is outputted to an onboard speaker through a 1.2W audio power amplifier (IS31AP4991) and to an onboard headphones connector, labeled LINE OUT. When headphones are connected to the LINE OUT port, the onboard speaker is automatically muted.

## 17.2 Connectivity

Table 17.1 shows the details about the A\_OUT signal connecting the audio module to the PIC32.

Name	PIC32 pin
A_OUT	AN14/RPB14/CTED5/PMA1/RB14

Table 17.1. Audio out connectivity.

The A\_OUT pin will be used as a digital output pin:

- The corresponding TRIS bit must be set to 0:  
`TRISBbits.TRISB14 = 0;`
- The corresponding ANSEL bit should be set to 0:  
`ANSELBbits.ANSB14 = 0;`

## 17.2 Functionality

Functionality for access to the audio module is implemented in the AUDIO library of the Basys MX3 library pack. These are the features of the implementation:

- The RB14 is mapped to OC1  
`RPB14R = 0x0C; // OC1`
- OC1 is properly configured, together with associated Timer 3
- Every time the timer 3 interrupt handler routine is called, the OC1RS register gets the value of the audio sample that needs to be represented using PWM.

If the user wants to use the audio out module without the AUDIO library, they must implement their own audio functionality.

## 18 Microphone

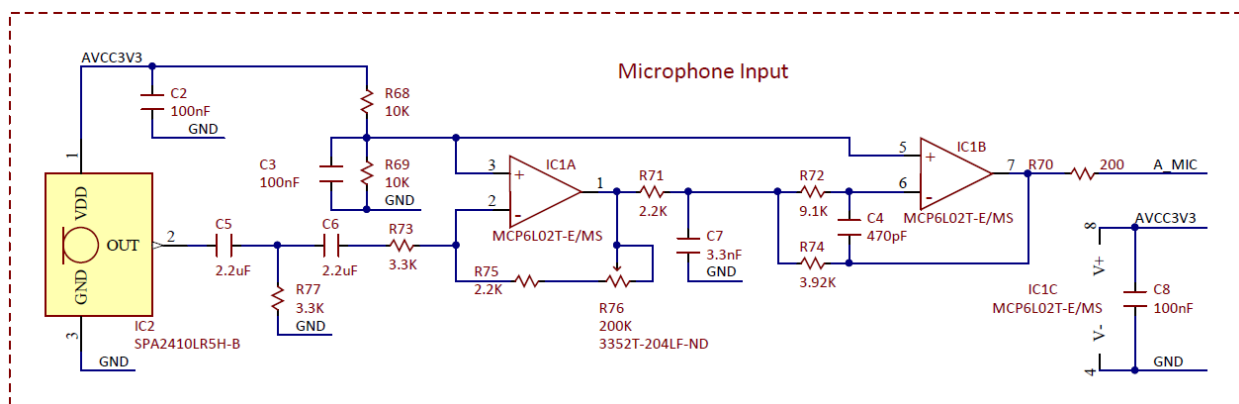


Figure 18.1. Microphone schematic diagram.

The Basys MX3 provides a basic microphone module. It is based on the Knowles Acoustics SPA2410LR5H-B MEMS microphone that has a high signal-to-noise ratio (SNR) of 94 dB SPL at 1 kHz.



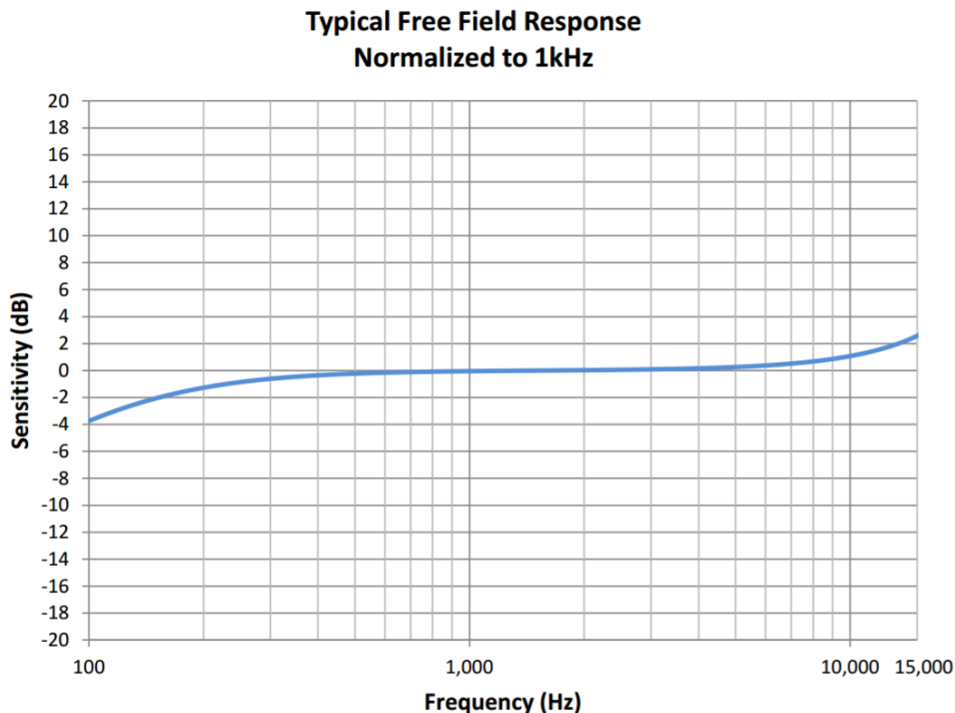


Figure 18.2. Microphone frequency response.

The output of the microphone module is an analog signal A\_MIC, connected to an analog input pin of PIC32. This analog pin must be sampled using the PIC32’s ADC functionality to get a digital value. The PIC32 provides 10-bit data ADC sampling. Read more on the PIC32’s ADC functionality in the Analog-To-Digital Converter (ADC) section of the PIC32 documentation.

The microphone on the Basys MX3 also features adjustable gain that is controlled using a thumbwheel potentiometer labeled MIC VOLUME. This dial directly controls the gain of the A\_MIC signal going into the PIC32.

## 18.1 Connectivity

Table 18.1 below shows the details about the A\_MIC signal connecting the microphone module to the PIC32.

Name	PIC32 pin	SPA2410LR5H-B pin
A_MIC	AN4/C11NB/RB4	OUT

Table 18.1. Microphone connectivity.

The A\_MIC pin will be used as analog input pin:

- The corresponding TRIS bit must be set to 1:  
`TRISBbits.TRISB4 = 1;`
- The corresponding ANSEL bit should be set to 1:  
`ANSELBbits.ANSB4 = 1;`

## 18.2 Functionality

The microphone usage is described through library functions in the MIC and ADC libraries of the Basys MX3 library pack. Implementation features include:

- The ADC module is initialized.
- Channel 4 is read (corresponding to AN4).

If the user wants to acquire data from microphone module without the MIC and ADC libraries, they must implement their own ADC functionality.

## 19 Analog Input Control

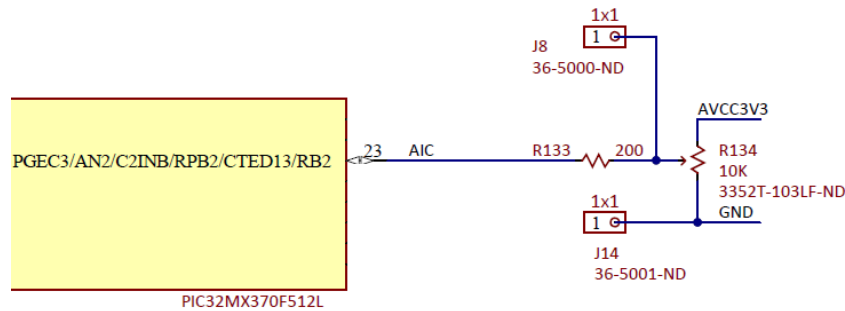


Figure 19.1. Analog input control schematic diagram.

The Basys MX3 provides a basic analog input module. This module exposes an analog input signal called AIC to the PIC32. The user can provide an analog value between 0 and 3.3V using a thumbwheel potentiometer labeled ANALOG INPUT CONTROL.

A pair of wire loops on the Basys MX3, labeled AIC and GND (J8 and J14 on the schematics), can be used to measure the voltage across the potentiometer using an external tool like a multimeter or oscilloscope.

The AIC analog signal must be sampled using the PIC32’s ADC functionality to get a digital value. The PIC32 provides 10-bit data ADC sampling. Read more on the PIC32’s ADC functionality in the Analog-To-Digital Converter (ADC) section of the PIC32 documentation.

### 19.1 Connectivity

Table 19.1 shows the details about the AIC signal connecting the analog input module to the PIC32.

Name	PIC32 pin
AIC	PGEC3/AN2/C2INB/RPB2/CTED13/RB2

Figure 19.1. Analog input control connectivity.

The AIC pin will be used as an analog input pin:

- The corresponding TRIS bit must be set to 1:  
`TRISBbits.TRISB2 = 1;`
- The corresponding ANSEL bit should be set to 1:  
`ANSELBbits.ANSB2 = 1;`

## 19.2 Functionality

The Analog Input module is implemented in the ADC library of the Basys MX3 library pack. Implementation features include:

- The ADC module is properly initialized.
- Channel 2 is read (corresponding to AN2).

If the users want to acquire data using the Analog Input module without the ADC library, they need to implement their own ADC functionality.

## 20 Pmod Connectors

The Basys MX3 provides two host connectors for Digilent Pmods. The Pmod connectors, labeled PMOD A and PMOD B, are 2x6 right-angle, female pin header connectors.

The schematic diagram in Fig. 20.1 depicts the signals routed to the two connectors.

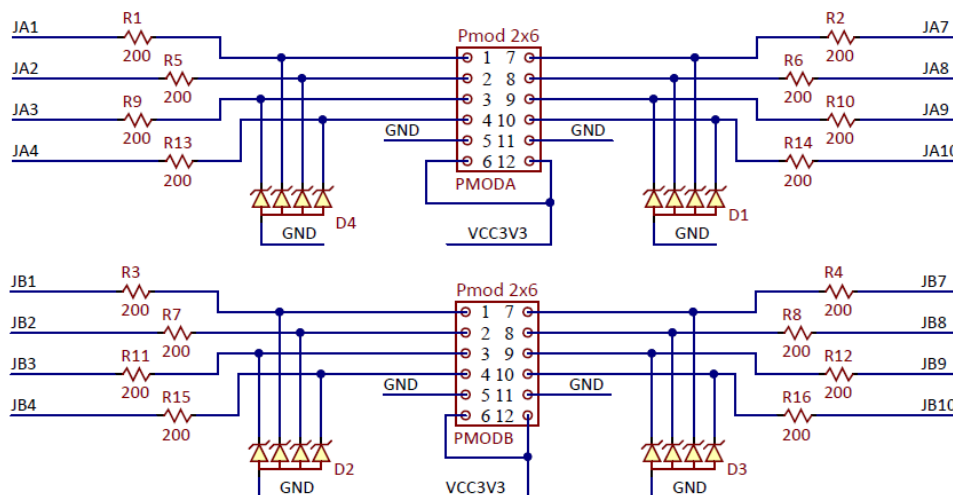


Figure 20.1. Pmod schematic diagram.

The pin numbering that Digilent uses on the twelve-pin Pmod connectors may not seem typical. In the upper row the pins are numbered 1–6, left to right (when viewed from the top, middle of the board), and the pins in the lower row are numbered 7–12, left to right. This complies with the convention that the upper and lower rows of pins can be considered as two stacked six-pin connectors. When viewed from the end of the connector, pin 1 is the upper right pin and pin 7 is immediately below. Pin 1 is labeled on the Basys MX3 board with “1” and can be recognized by its squared pad (both on the main board and on the Pmod device).

Each row of pins provides a pair of VCC (3.3V) and GND, as shown Fig. 20.2.

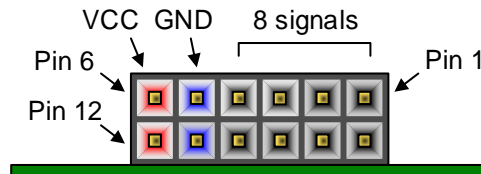


Figure 20.2. Pmod connectors: front view, as loaded on PCB.

Table 20.1 summarizes the content of PMODA connector.

Pmod pin	Schematic Label	PIC32 pin
PMODA_1	JA1	RPC2/RC2
PMODA_2	JA2	RPC1/RC1
PMODA_3	JA3	RPC4/CTED7/RC4
PMODA_4	JA4	AN16/C1IND/RPG6/SCK2/PMA5/RG6
PMODA_7	JA7	RPC3/RC3
PMODA_8	JA8	AN17/C1INC/RPG7/PMA4/RG7
PMODA_9	JA9	AN18/C2IND/RPG8/PMA3/RG8
PMODA_10	JA10	AN19/C2INC/RPG9/PMA2/RG9

Table 20.1. Pmod A pinout.

Table 20.2 summarizes the content of PMODB connector.

Pmod pin	Schematic Label	PIC32 pin
PMODB_1	JB1	RPD9/RD9
PMODB_2	JB2	RPD11/PMCS1/RD11
PMODB_3	JB3	RPD10/PMCS2/RD10
PMODB_4	JB4	RPD8/RTCC/RD8
PMODB_7	JB7	SOSCO/RPC14/T1CK/RC14
PMODB_8	JB8	RPD0/RD0
PMODB_9	JB9	AN24/RPD1/RD1
PMODB_10	JB10	SOSCI/RPC13/RC13

Table 20.2. Pmod B pinout.

The signals going to Pmod connectors are also connected to input/output pins on the PIC32 microcontroller. Review Section 1.3 [Digital Inputs and Outputs](#) for more details regarding digital I/Os.

Instead of using the Pmod pins as regular digital input/output pins, the pins can be mapped to several peripherals, as explained in Section 1.4 [Remappable pins](#). For example, the SPI2 interface is implemented over the PMODA pins, as explained in Section 11.2 [SPI2](#).

In the above tables, the highlighted pins are 5V tolerant pins. It is safe to apply 5V logic signals directly to these pins without risk of damage to the microcontroller. All other pins support 3.3V only.

Each pin has a 200-ohm series resistor and an ESD protection diode. The series resistor provides short circuit protection to prevent damaging the I/O block in the microcontroller if the pin is inadvertently shorted to VDD or GND, or two outputs are shorted together. The ESD protection diode protects the I/O block from damage due to electro-static discharge.

Although ESD protection is provided between the connector pins and the microcontroller pins, ESD safe handling procedures should be followed when handling the circuit board. The pins on the microcontroller and other circuits on the board are exposed and can be damaged through ESD when handling the board.

Digilent Pmods can either be plugged directly into the connectors on the Basys MX3 or attached via cables. Digilent has a variety of Pmod cables available.

You can read more details about the Digilent Pmod Interface Specification from the most recent specification document, available on the [Digilent Pmod Wiki](#).

## 21 Analog Discovery Debug Header

The Basys MX3 board provides a 2x15 Debug Header, exposing some pins that allow key onboard peripheral signals to be visualized with an oscilloscope or logic analyzer.

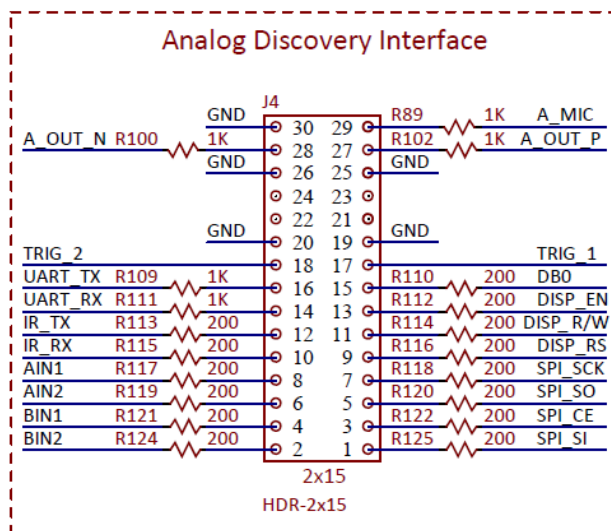


Figure 21.1. Debug header schematic diagram.

The connector is designed to match the Analog Discovery and OpenScope connectors, but the pins can be used with other tools as well.

Table 21.1 below shows the signals exposed by this connector.

Pin #	Silk Screen Name	Type	Connected to / Module	Analog Discovery pin
1	SPI_SI	RPF2/RF2	SPI_SI / <a href="#">Flash memory</a>	Digital IO 7
2	BIN2	AN5/C1INA/RPB5/RB5	BIN2 / <a href="#">Motor driver</a>	Digital IO 15
3	SPI_CE	RPF8/RF8	SPI_CE / Flash memory	Digital IO 6
4	BIN1	RPE9/RE9	BIN1 / Motor driver	Digital IO 14
5	SPI_SO	RPF7/RF7	SPI_SO / Flash memory	Digital IO 5
6	AIN2	RPE8/RE8	AIN2 / Motor driver	Digital IO 13
7	SPI_SCK	RPF6/SCK1/INT0/RF6	SPI_SCK / Flash memory	Digital IO 4
8	AIN1	PGED3/AN3/C2INA/RPB3/RB3	AIN1 / Motor driver	Digital IO 12
9	D_RS	AN15/RPB15/PMA0/CTED6/RB15	DISP_RS / <a href="#">LCD module</a>	Digital IO 3
10	IRRX	PGEC2/AN6/RPB6/RB6	IR_RX / <a href="#">IrDA module</a>	Digital IO 11

Pin #	Silk Screen Name	Type	Connected to / Module	Analog Discovery pin
11	DISP_R/W	RPD5/PMRD/RD5	DISP_R/W / LCD module	Digital IO 2
12	IRTX	PGED2/AN7/RPB7/CTED3/RB7	IR_TX / IrDA module	Digital IO 10
13	D_EN	RPD4/PMWR/RD4	DISP_EN / LCD module	Digital IO 1
14	URX	RPF13/RF13	UART_RX / <a href="#">UART</a>	Digital IO 9
15	DB0	PMD0/RE0	DB0 / LCD module	Digital IO 0
16	UTX	RPF12/RF12	UART_TX / UART	Digital IO 8
17	T1	RPF0/PMD11/RF0	BTNC / TRIG_1 / <a href="#">User Buttons</a>	T1
18	T2	AN9/RPB9/CTED4/RB9	SW7 / TRIG_2 / <a href="#">User Switches</a>	T2
19	GND	GND		GND
20	GND	GND		GND
25	GND	GND		GND
26	GND	GND		GND
27	AOP	analog pin	A_OUT_P / <a href="#">Audio out</a>	Scope 2+
28	AON	analog pin	A_OUT_N / Audio out	Scope 2-
29	AMIC	AN4/C1INB/RB4	A_MIC / <a href="#">Microphone</a>	Scope 1+
30	GND	GND		Scope 1-

Table 20.1. Debug header pinout.

## Appendix 1: Remappable Input Pins

Peripheral Pin	[pin name]R SFR	[pin name]R bits	[pin name]R Value to RPn Pin Selection
INT3	INT3R	INT3R<3:0>	0000 = RPD2 0001 = RPG8 0010 = RPF4 0011 = RPD10 0100 = RPF1 0101 = RPB9 0110 = RPB10 0111 = RPC14 1000 = RPB5 1001 = Reserved 1010 = RPC1 1011 = RPD14 1100 = RPG1 1101 = RPA14 1110 = Reserved 1111 = RPF2
T2CK	T2CKR	T2CKR<3:0>	
IC3	IC3R	IC3R<3:0>	
U1RX	U1RXR	U1RXR<3:0>	
U2RX	U2RXR	U2RXR<3:0>	
U5CTS	U5CTSR	U5CTSR<3:0>	
REFCLKI	REFCLKIR	REFCLKIR<3:0>	
Peripheral Pin	[pin name]R SFR	[pin name]R bits	[pin name]R Value to RPn Pin Selection
INT4	INT4R	INT4R<3:0>	0000 = RPD3 0001 = RPG7 0010 = RPF5 0011 = RPD11 0100 = RPF0 0101 = RPB1 0110 = RPE5 0111 = RPC13 1000 = RPB3 1001 = Reserved 1010 = RPC4 1011 = RPD15 1100 = RPG0 1101 = RPA15 1110 = RPF2 1111 = RPF7
T5CK	T5CKR	T5CKR<3:0>	
IC4	IC4R	IC4R<3:0>	
U3RX	U3RXR	U3RXR<3:0>	
U4CTS	U4CTSR	U4CTSR<3:0>	
SDI1	SDI1R	SDI1R<3:0>	
SDI2	SDI2R	SDI2R<3:0>	
Peripheral Pin	[pin name]R SFR	[pin name]R bits	[pin name]R Value to RPn Pin Selection
INT2	INT2R	INT2R<3:0>	0000 = RPD9 0001 = RPG6

T4CK	T4CKR	T4CKR<3:0>	0010 = RPB8 0011 = RPB15 0100 = RPD4 0101 = RPB0 0110 = RPE3 0111 = RPB7 1000 = Reserved 1001 = RPF12 1010 = RPD12 1011 = RPF8 1100 = RPC3 1101 = RPE9 1110 = Reserved 1111 = RPB2
IC2	IC2R	IC2R<3:0>	
IC5	IC5R	IC5R<3:0>	
U1CTS	U1CTSR	U1CTSR<3:0>	
U2CTS	U2CTSR	U2CTSR<3:0>	
SS1	SS1R	SS1R<3:0>	
Peripheral Pin	[pin name]R SFR	[pin name]R bits	[pin name]R Value to RPN Pin Selection
INT1	INT1R	INT1R<3:0>	0000 = RPD1 0001 = RPG9 0010 = RPB14 0011 = RPD0 0100 = RPD8 0101 = RPB6 0110 = RPD5 0111 = RPB2 1000 = RPF3 1001 = RPF13 1010 = Reserved 1011 = RPF2 1100 = RPC2 1101 = RPE8 1110 = Reserved 1111 = Reserved
T3CK	T3CKR	T3CKR<3:0>	
IC1	IC1R	IC1R<3:0>	
U3CTS	U3CTSR	U3CTSR<3:0>	
U4RX	U4RXR	U4RXR<3:0>	
U5RX	U5RXR	U5RXR<3:0>	
SS2	SS2R	SS2R<3:0>	
OCFA	OCFAR	OCFAR<3:0>	



## Appendix 2: Remappable Output Pins

RPn Port Pin	RPnR SFR	RPnR Value to Peripheral Selection
RPD2	RPD2R	0000 = No Connect 0001 = U3TX 0010 = U4RTS 0011 = Reserved 0100 = Reserved 0101 = Reserved 0110 = SDO2 0111 = Reserved 1000 = Reserved 1001 = Reserved 1010 = Reserved 1011 = OC3 1100 = Reserved 1101 = C2OUT 1110 = Reserved 1111 = Reserved
RPG8	RPG8R	
RPF4	RPF4R	
RPD10	RPD10R	
RPF1	RPF1R	
RPB9	RPB9R	
RPB10	RPB10R	
RPC14	RPC14R	
RPB5	RPB5R	
RPC1	RPC1R	
RPD14	RPD14R	
RPG1	RPG1R	
RPA14	RPA14R	
RPn Port Pin	RPnR SFR	
RPD3	RPD3R	0000 = No Connect 0001 = U2TX 0010 = Reserved 0011 = U1TX 0100 = U5RTS 0101 = Reserved 0110 = SDO2 0111 = Reserved
RPG7	RPG7R	
RPF5	RPF5R	

RPD11	RPD11R	1000 = SDO1 1001 = Reserved 1010 = Reserved 1011 = OC4
RPF0	RPF0R	1100 = Reserved 1101 = Reserved 1110 = Reserved 1111 = Reserved
RPB1	RPB1R	
RPE5	RPE5R	
RPC13	RPC13R	
RPB3	RPB3R	
RPF3	RPF3R	
RPC4	RPC4R	
RPD15	RPD15R	
RPG0	RPG0R	
RPA15	RPA15R	
RPn Port Pin	RPnR SFR	RPnR Value to Peripheral Selection
RPD9	RPD9R	0000 = No Connect 0001 = U3RTS 0010 = U4TX 0011 = REFCLKO 0100 = U5TX 0101 = Reserved 0110 = Reserved 0111 = SS1
RPG6	RPG6R	1000 = SDO1 1001 = Reserved 1010 = Reserved 1011 = OC5
RPB8	RPB8R	1100 = Reserved 1101 = C1OUT 1110 = Reserved 1111 = Reserved
RPB15	RPB15R	
RPD4	RPD4R	
RPB0	RPB0R	
RPE3	RPE3R	

RPB7	RPB7R	
RPB2	RPB2R	
RPF12	RPF12R	
RPD12	RPD12R	
RPF8	RPF8R	
RPC3	RPC3R	
RPE9	RPE9R	
RPD9	RPD9R	
RPn Port Pin	RPnR SFR	RPnR Value to Peripheral Selection
RPD1	RPD1R	0000 = No Connect
		0001 = U2RTS
		0010 = Reserved
RPG9	RPG9R	0011 = U1RTS
		0100 = U5TX
		0101 = Reserved
RPB14	RPB14R	0110 = SS2
		0111 = Reserved
		1000 = SDO1
RPD0	RPD0R	1001 = Reserved
		1010 = Reserved
		1011 = OC2
RPD8	RPD8R	1100 = OC1
		1101 = Reserved
		1110 = Reserved
RPB6	RPB6R	1111 = Reserved"
RPD5	RPD5R	
RPF3	RPF3R	
RPF6	RPF6R	
RPF13	RPF13R	

RPC2	RPC2R	
RPE8	RPE8R	
RPF2	RPF2R	

## Appendix 3: Basys MX3 Pinout

The following table details the Basys MX3 pinout, showing the following information:

- Pin #, Full Pin Name: The number and the name of the microcontroller pin, as in the microcontroller datasheet pin.
- Peripheral: The Basys MX3 peripheral that uses this pin.
- Schematic Name: the name of the pin in the schematic.
- PPS: The PPS remapping function of this pin.
- Function: The available function(s) of this pin.

Pin #	Full Pin Name	Peripheral	Schematic Name	PPS	Function
1	RG15	SSD	CE		RG15
2	VDD	POWER	VCC3V3		
3	AN22/RPE5/PMD5/RE5	LCD	DB5	I/O	PMD5
4	AN23/PMD6/RE6	LCD	DB6		PMD6
5	AN27/PMD7/RE7	LCD	DB7		PMD7
6	RPC1/RC1	PMOD	JA2	I/O	SDO2/U3TX/IC3/T2CK/INT3/OC3
7	RPC2/RC2	PMOD	JA1	I/O	SS2/U3CTS/IC1/T3CK/INT1/OC1/OC2
8	RPC3/RC3	PMOD	JA7	I/O	INT2/U1CTS/U2CTS/IC2/IC5/T4CK/OC5
9	RPC4/CTED7/RC4	PMOD	JA3	I/O	SDI2/U3RX/IC4/T5CK/INT4/OC4
10	AN16/C1IND/RPG6/SCK2/PMA5/RG6	PMOD	JA4	I/O	SCK2/U3RTS/IC2/IC5/T4CK/INT2/OC5
11	AN17/C1INC/RPG7/PMA4/RG7	PMOD	JA8	I/O	INT4/U1TX/U2TX/IC4/T5CK/OC4
12	AN18/C2IND/RPG8/PMA3/RG8	PMOD	JA9	I/O	IC3/T2CK/INT3/U1RX/U2RX/OC3
13	MCLR	PROGRAM/DEBUG	PIC32_MCLR		
14	AN19/C2INC/RPG9/PMA2/RG9	PMOD	JA10	I/O	IC1/T3CK/INT1/U1RTS/U2RTS/OC1/OC2
15	VSS	POWER	GND		
16	VDD	POWER	VCC3V3		
17	TMS/CTED1/RA0	LEDS	LED0		RA0
18	RPE8/RE8	MOTOR	AIN2	I/O	OC2/RE8
19	RPE9/RE9	MOTOR	BIN1	I/O	OC5/RE9
20	AN5/C1INA/RPB5/RB5	MOTOR	BIN2	I/O	OC3/RB5
21	AN4/C1INB/RB4	MICROPHONE	A_MIC		AN4/C1INB
22	PGED3/AN3/C2INA/RPB3/RB3	MOTOR	AIN1	I/O	OC4/RB3
23	PGEC3/AN2/C2INB/RPB2/CTED13/RB2	POTENTIOMETER	AIC	I/O	AN2/C2INB

Pin #	Full Pin Name	Peripheral	Schematic Name	PPS	Function
24	PGEC1/AN1/RPB1/CTED12/RB1	PROGRAM/DEBUG/BUTTONS	P32_PGC/B TNU	I/O	RB1
25	PGED1/AN0/RPB0/RB0	PROGRAM/DEBUG/BUTTONS	P32_PGD/B TNL	I/O	RB0
26	PGEC2/AN6/RPB6/RB6	IRDA	IR_RX	I/O	U5RX
27	PGED2/AN7/RPB7/CTED3/RB7	IRDA	IR_TX	I/O	URTX
28	VREF-/CVREF-/PMA7/RA9	SSD	AN2		RA9
29	VREF+/CVREF+/PMA6/RA10	SSD	AN3		RA10
30	AVDD	POWER	VCC3V3		
31	AVSS	POWER	GND		
32	AN8/RPB8/CTED10/RB8	BUTTONS	BTNR/S0_PWM	I/O	RB8/OC5
33	AN9/RPB9/CTED4/RB9	SWITCHES	SW7	I/O	RB9
34	CVREFOUT/AN10/RPB10/CTED11/PMA13/RB10	SWITCHES	SW6	I/O	RB10
35	AN11/PMA12/RB11	SWITCHES	SW5		RB11
36	VSS	POWER	GND		
37	VDD	POWER	VCC3V3		
38	TCK/CTED2/RA1	LEDS	LED1		RA1
39	RPF13/RF13	FTDI	UART_RX	I/O	U4RX
40	RPF12/RF12	FTDI	UART_TX	I/O	U4TX
41	AN12/PMA11/RB12	SSD	AN0		RB12
42	AN13/PMA10/RB13	SSD	AN1		RB13
43	AN14/RPB14/CTED5/PMA1/RB14	AUDIO_OUT	A_OUT	I/O	OC1
44	AN15/RPB15/OCFB/CTED6/PMA0/RB15	LCD	DISP_RS	I/O	PMA0
45	VSS	POWER	GND		
46	VDD	POWER	VCC3V3		
47	RPD14/RD14	SWITCHES	SW4	I/O	RD14
48	RPD15/RD15	SWITCHES	SW3	I/O	RD15
49	RPF4/PMA9/RF4	SWITCHES	SW2	I/O	RF4
50	RPF5/PMA8/RF5	SWITCHES	SW1	I/O	RF5
51	RPF3/RF3	SWITCHES	SW0	I/O	RF3
52	RPF2/RF2	SPI_FLASH	SPI_SI	I/O	SDO1/U5TX/U4RX/U5RX/IC1/T3CK/INT1OC1/OC2
53	RPF8/RF8	SPI_FLASH	SPI_CE	I/O	SS1/U1CTS/U2CTS/IC2/IC5/T4CK/INT4/OC5
54	RPF7/RF7	SPI_FLASH	SPI_SO	I	SDI1/U3RX/IC4/T5CK/INT4

Pin #	Full Pin Name	Peripheral	Schematic Name	PPS	Function
55	RPF6/SCK1/INT0/RF6	SPI_FLASH	SPI_SCK	I/O	SCK1/U1RTS/U2RTS/OC1/OC2/INT0
56	SDA1/RG3	I2C	SDA		SDA1
57	SCL1/RG2	I2C	SCL		SCL1
58	SCL2/RA2	LEDS	LED2		RA2
59	SDA2/RA3	LEDS	LED3		RA3
60	TDI/CTED9/RA4	LEDS	LED4		RA4
61	TDO/RA5	LEDS	LED5		RA5
62	VDD	POWER	VCC3V3		
63	OSC1/CLKI/RC12	CLOCK	8MHZ		CRYSTAL
64	OSC2/CLKO/RC15	CLOCK	8MHZ		CRYSTAL
65	VSS	POWER	GND		
66	RPA14/RA14	SSD	CB	I/O	RA14
67	RPA15/RA15	BUTTONS	BTND/S1_PWM	I/O	RA15/OC4
68	RPD8/RTCC/RD8	PMOD	JB4	I/O	U1RTS/U2RTS/IC1/T3CK/INT1/OC1/OC2
69	RPD9/RD9	PMOD	JB1	I/O	U1CTS/U2CTS/IC2/IC5/T4CK/INT2/OC5
70	RPD10/PMCS2/RD10	PMOD	JB3	I/O	U1RX/U2RX/IC3/T2CK/INT3/OC3
71	RPD11/PMCS1/RD11	PMOD	JB2	I/O	U1TX/U2TX/IC4/T5CK/INT4/OC4
72	RPD0/RD0	PMOD	JB8	I/O	INT1/U5TX/IC1/T3CK/OC1/OC2
73	SOSCI/RPC13/RC13	PMOD	JB10	I/O	INT4/U5RTS/IC4/T5CK/OC4
74	SOSCO/RPC14/T1CK/RC14	PMOD	JB7	I/O	INT3/U5CTS/IC3/T2CK/OC3
75	VSS	POWER	GND		
76	AN24/RPD1/RD1	PMOD	JB9	I/O	INT1/U5RX/IC1/T3CK/OC1/OC2
77	AN25/RPD2/RD2	RGB_LED	LED8_R	I/O	OC3/RD2
78	AN26/RPD3/RD3	RGB_LED	LED8_B	I/O	OC4/RD3
79	RPD12/PMD12/RD12	RGB_LED	LED8_G	I/O	OC5/RD12
80	PMD13/RD13	SSD	CG		RD13
81	RPD4/PMWR/RD4	LCD	DISP_EN	I/O	PMENB
82	RPD5/PMRD/RD5	LCD	DISP_R/W	I/O	PMRD/PMWR
83	PMD14/RD6	SSD	CC		RD6
84	PMD15/RD7	SSD	CF		RD7
85	VCAP	POWER	CAPACITOR		
86	VDD	POWER	VCC3V3		
87	RPF0/PMD11/RF0	BUTTONS	BTNC	I/O	RF0
88	RPF1/PMD10/RF1	MOTOR	MODE	I/O	RF1
89	RPG1/PMD9/RG1	IRDA	IR_PDOWN	I/O	RG1
90	RPG0/PMD8/RG0	ACCELEROMETER	ACL_INT2	I/O	INT4

Pin #	Full Pin Name	Peripheral	Schematic Name	PPS	Function
91	TRCLK/RA6	LEDS	LED6		RA6
92	TRD3/CTED8/RA7	LEDS	LED7		RA7
93	PMD0/RE0	LCD	DB0		PMD0
94	PMD1/RE1	LCD	DB1		PMD1
95	TRD2/RG14	SSD	DP		RG14
96	TRD1/RG12	SSD	CA		RG12
97	TRD0/RG13	SSD	CD		RG13
98	AN20/PMD2/RE2	LCD	DB2		PMD2
99	RPE3/CTPLS/PMD3/RE3	LCD	DB3	I/O	PMD3
100	AN21/PMD4/RE4	LCD	DB4		PMD4