

OPTO16X16

16 Optically Isolated Inputs, 16 Optically Isolated Outputs

**All Form Factors
...-OPTO16X16**

Linux Driver User Manual

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Preface

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1. Introduction

1.1. Purpose

The purpose of this document is to describe the interface to the OPTO16X16 API Library and to the underlying Linux device driver. The API Library software provides the interface between "Application Software" and the device driver. The driver software provides the interface between the API Library and the actual OPTO16X16 hardware. The API Library and driver interfaces are based on the board's functionality.

1.2. Acronyms

The following is a list of commonly occurring acronyms which may appear throughout this document.

Acronyms	Description
API	Application Programming Interface
COS	Change of State
CPCI	Compact PCI
DIO	Digital I/O
GSC	General Standards Corporation
PCI	Peripheral Component Interconnect
PCIe	PCI Express
PMC	PCI Mezzanine Card

1.3. Definitions

The following is a list of commonly occurring terms which may appear throughout this document.

Term	Definition
...	This is a shortcut representation of the OPTO16X16 installation directory or any of its subdirectories.
API Library	This is a library that provides application-level access to OPTO16X16 hardware.
Application	This is a user mode process, which runs in user space with user mode privileges.
Driver	This is the OPTO16X16 device driver, which runs in kernel space with kernel mode privileges.
Library	This is usually a general reference to the API Library.
OPTO16X16	This is used as a general reference to any device supported by this driver.

1.4. Software Overview

1.4.1. Basic Software Architecture

This section describes the general architecture for the basic components that comprise OPTO16X16 applications. The overall architecture is illustrated in Figure 1 below.

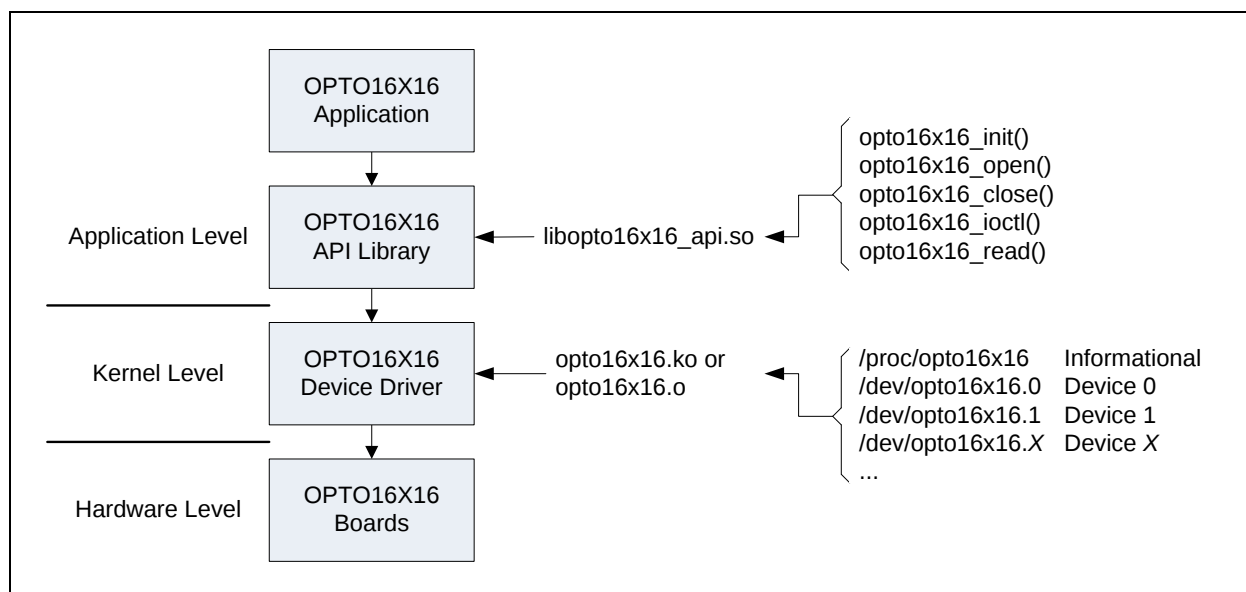


Figure 1 Basic architectural representation.

1.4.2. API Library

The primary means of accessing OPTO16X16 boards is via the OPTO16X16 API Library. This library forms a layer between the application and the driver. Additional information is given in section 4 (page 16). With the library, applications are able to open and close a device and, while open, perform I/O control and read operations.

1.4.3. Device Driver

The device driver is the host software that provides a means of communicating directly with OPTO16X16 hardware. The driver executes under control of the operating system and runs in Kernel Mode as a Kernel Mode device driver. The driver is implemented as a standard dynamically loadable Linux device driver written in the C programming language. While applications can access the driver directly without use of the API Library, it is recommended that all access is made through the library.

1.5. Hardware Overview

The OPTO16X16 is a high-performance discrete digital I/O board with 16 optically isolated inputs and 16 optically isolated outputs. The host side connection is PCI based and the form factor is according to the model ordered. The board features a programmable Change-of-State debounce period that is configurable from 200ns to over four seconds, in 200ns increments. The board also features a polarity configurable interrupt option on each of the 16 inputs. An interrupt can also be generated in response to a specified number of low-to-high transitions on the D15 input.

1.6. Reference Material

The following reference material may be of particular benefit in using the OPTO16X16. The specifications provide the information necessary for an in depth understanding of the specialized features implemented on this board.

- The *OPTO16X16 Driver Reference Manual* from General Standards Corporation.
- The applicable *OPTO16X16 User Manual* from General Standards Corporation.
- The *PCI9056 PCI Bus Master Interface Chip* data handbook from PLX Technology, Inc.

PLX Technology Inc.
870 Maude Avenue
Sunnyvale, California 94085 USA
Phone: 1-800-759-3735
WEB: <http://www.plxtech.com>

1.7. Licensing

For licensing information please refer to the text file `LICENSE.txt` in the root installation directory.

2. Installation

2.1. CPU and Kernel Support

The driver is designed to operate with Linux kernel versions 6.x, 5.x, 4.x, 3.x, 2.6, 2.4 and 2.2 running on a PC system with one or more x86 processors. This release of the driver supports the below listed kernels.

Kernel	Distribution
6.8.5	Red Hat Fedora Core 40
6.5.6	Red Hat Fedora Core 39
6.2.9	Red Hat Fedora Core 38
6.0.7	Red Hat Fedora Core 37
5.17.5	Red Hat Fedora Core 36
5.14.10	Red Hat Fedora Core 35
5.11.12	Red Hat Fedora Core 34
5.8.15	Red Hat Fedora Core 33
5.6.6	Red Hat Fedora Core 32
5.3.7	Red Hat Fedora Core 31
5.0.9	Red Hat Fedora Core 30
4.18.16	Red Hat Fedora Core 29
4.16.3	Red Hat Fedora Core 28
4.13.9	Red Hat Fedora Core 27
4.11.8	Red Hat Fedora Core 26
4.8.6	Red Hat Fedora Core 25
4.5.5	Red Hat Fedora Core 24
4.2.3	Red Hat Fedora Core 23
4.0.4	Red Hat Fedora Core 22
3.17.4	Red Hat Fedora Core 21
3.11.10	Red Hat Fedora Core 20
3.9.5	Red Hat Fedora Core 19
3.6.10	Red Hat Fedora Core 18
3.3.4	Red Hat Fedora Core 17
3.1.0	Red Hat Fedora Core 16
2.6.38	Red Hat Fedora Core 15
2.6.35	Red Hat Fedora Core 14
2.6.33	Red Hat Fedora Core 13
2.6.31	Red Hat Fedora Core 12
2.6.29	Red Hat Fedora Core 11
2.6.27	Red Hat Fedora Core 10
2.6.25	Red Hat Fedora Core 9
2.6.23	Red Hat Fedora Core 8
2.6.21	Red Hat Fedora Core 7
2.6.18	Red Hat Fedora Core 6
2.6.15	Red Hat Fedora Core 5
2.6.11	Red Hat Fedora Core 4
2.6.9	Red Hat Fedora Core 3
2.4.18	Red Hat 8.0

NOTE: Some older kernel versions are supported (the sources are maintained), but are not tested.

NOTE: While only Red Hat Fedora distributions are listed, numerous other distributions are supported and have been tested on an as needed basis.

NOTE: The driver will have to be built before being used as it is provided in source form only.

NOTE: The driver has not been tested with a non-versioned kernel.

NOTE: The driver is designed for SMP support, but has not undergone SMP specific testing.

2.1.1. 32-bit Support Under 64-bit Environments

This driver supports 32-bit applications under 64-bit environments. The availability of this feature in the kernel depends on a 64-bit kernel being configured to support 32-bit application compatibility. Additionally, 2.6 kernels prior to 2.6.11 implemented 32-bit compatibility in a way that resulted in some drivers not being able to take advantage of the feature. (In these kernels a driver's IOCTL command codes must be globally unique. Beginning with 2.6.11 this requirement has been lifted.) If the driver is not able to provide 32-bit support under a 64-bit kernel, the "32-bit support" field in the `/proc/opto16x16` file will be "no".

2.2. The `/proc/` File System

While the driver is running, the text file `/proc/opto16x16` can be read to obtain information about the driver and the boards it detects. Each file entry includes an entry name followed immediately by a colon, a space character, and the entry value. Below is an example of what appears in the file, followed by descriptions of each entry.

```
version: 2.7.113.50
32-bit support: yes
boards: 1
models: OPTO16X16
```

Entry	Description
version	This gives the driver version number in the form <code>x.x.x.x</code> .
32-bit support	This reports the driver's support for 32-bit applications. This will be either "yes" or "no" for 64-bit driver builds and "yes (native)" for 32-bit builds.
boards	This identifies the total number of boards the driver detected.
models	This gives a comma separated list of the basic model number for each board the driver detected. The model numbers are listed in the same order that the boards are accessed via the API Library's open function.

2.3. File List

This release consists of the below listed primary files. The archive content is described in following subsections.

File	Description
<code>opto16x16.linux.tar.gz</code>	This archive contains the driver, the API Library and all related files.
<code>opto16x16_api_rm.pdf</code>	This is a PDF version of the OPTO16X16 API Library Reference Manual.
<code>opto16x16_linux_um.pdf</code>	This is a PDF version of this user manual, which is included in the archive.

2.4. Directory Structure

The following table describes the directory structure utilized by the installed files. During installation the directory structure is created and populated with the respective files.

Directory	Description
<code>opto16x16/</code>	This is the driver root directory. It contains the documentation, the Overall Make Script (section 2.7, page 11) and the below listed subdirectories.
<code>.../api/</code>	This directory contains the API Library source files (section 4, page 16).
<code>.../docsrc/</code>	This directory contains the source files for the code samples given in the Reference Manual

	(section 6, page 22).
.../driver/	This directory contains the device driver source files (section 5, page 18).
.../include/	This directory contains the header files for the various libraries.
.../lib/	This directory contains all of the libraries built from the installed sources.
.../samples/	This directory contains the sample application subdirectories and all of their corresponding source files (section 9, page 25).
.../utils/	This directory contains the source files for the utility libraries used by the sample applications (section 7, page 23).

2.5. Installation

Perform installation following the below listed steps. This installs the device driver, the API Library and all related sources and documentation.

1. Create and change to the directory where the files are to be installed, such as `/usr/src/linux/drivers/`. (The path name may vary among distributions and kernel versions.)
2. Copy the archive file `opto16x16.linux.tar.gz` into the current directory.
3. Issue the following command to decompress and extract the files from the provided archive. This creates the directory `opto16x16` in the current directory, and then copies all of the archive's files into this new directory.

```
tar -xzvf opto16x16.linux.tar.gz
```

2.6. Removal

Perform removal following the below listed steps. This removes the device driver, the API Library and all related sources and documentation.

NOTE: The following steps may require elevated privileges.

1. Shutdown the driver as described in section 5.6 (page 21).
2. Change to the directory where the driver archive was installed, which may have been `/usr/src/linux/drivers/`. (The path name may vary among distributions and kernel versions.)
3. Issue the below command to remove the driver archive and all of the installed driver files.

```
rm -rf opto16x16.linux.tar.gz opto16x16
```

4. Issue the below command to remove all of the installed device nodes.

```
rm -f /dev/opto16x16.*
```

5. If the automatic startup procedure was adopted (section 5.3.2, page 19), then edit the system startup script `rc.local` and remove the line that invokes the OPTO16X16's start script. The file `rc.local` should be located in the `/etc/rc.d/` directory.

2.7. Overall Make Script

An Overall Make Script is included in the root installation directory. Executing this script will perform a make for all build targets included in the release. The script also loads the driver and copies the API Library to `/usr/lib/`. The script is named `make_all`. Follow the below steps to perform an overall make and to load the driver.

NOTE: The following steps may require elevated privileges.

1. Change to the driver root directory (.../opto16x16/).
2. Remove existing build targets using the below command. This does not unload the driver.

```
./make_all clean
```

3. Issue the following command to make all archive targets and to load the driver.

```
./make_all
```

2.8. Environment Variables

Some build environments may require compiler or linker options not present in the provided make files. To accommodate local environment specific requirements, the provided make files incorporate support for the following set of GSC specific environment variables.

2.8.1. GSC_API_COMP_FLAGS

This environment variable accommodates adding compiler command line options when compiling source files for the API Library. The compiler used by the API Library make file is “gcc”. The content of this environment variable is noted in the make file’s output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling any other distributed source files or linking of any object files.

Undefined or Empty	== Compiling: init.c == Compiling: ioctl.c == Compiling: open.c
Defined and Not Empty	== Compiling: init.c (added 'xxx') == Compiling: ioctl.c (added 'xxx') == Compiling: open.c (added 'xxx')

2.8.2. GSC_API_LINK_FLAGS

This environment variable accommodates adding linker command line options when linking object files for the API Library. The linker used by the API Library make file is “ld”. The content of this environment variable is noted in the make file’s output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling of any source files or linking of any other object files.

Undefined or Empty	==== Linking: ../lib/libopto16x16_api.so
Defined and Not Empty	==== Linking: ../lib/libopto16x16_api.so (added 'xxx')

2.8.3. GSC_LIB_COMP_FLAGS

This environment variable accommodates adding compiler command line options when compiling source files for the utility libraries. The compiler used by the utility library make files is “gcc”. The content of this environment variable is noted in the make files’ output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling any other distributed source files or linking of any object files.

Undefined or Empty	== Compiling: close.c == Compiling: init.c == Compiling: ioctl.c
Defined and Not Empty	== Compiling: close.c (added 'xxx') == Compiling: init.c (added 'xxx') == Compiling: ioctl.c (added 'xxx')

2.8.4. GSC_LIB_LINK_FLAGS

This environment variable accommodates adding linker command line options when linking object files for the utility libraries. The linker used by the utility library make files is “ld”. The content of this environment variable is noted in the make files’ output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling of any source files or linking of any other object files.

Undefined or Empty	==== Linking: ../lib/opto16x16_utils.a
Defined and Not Empty	==== Linking: ../lib/opto16x16_utils.a (added 'xxx')

2.8.5. GSC_APP_COMP_FLAGS

This environment variable accommodates adding compiler command line options when compiling source files for the sample applications. The compiler used by the sample application make files is “gcc”. The content of this environment variable is noted in the make files’ output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling any other distributed source files or linking of any object files.

Undefined or Empty	== Compiling: main.c == Compiling: perform.c
Defined and Not Empty	== Compiling: main.c (added 'xxx') == Compiling: perform.c (added 'xxx')

2.8.6. GSC_APP_LINK_FLAGS

This environment variable accommodates adding linker command line options when linking object files for the sample applications. The linker used by the sample application make files is “gcc”. The content of this environment variable is noted in the make files’ output to the screen. The table below shows a portion of the screen output. The “xxx” in the table refers to the contents of the environment variable. This environment variable has no effect on compiling of any source files or linking of any other object files.

Undefined or Empty	==== Linking: id
Defined and Not Empty	==== Linking: id (added 'xxx')

3. Main Interface Files

For additional information refer to the *OPTO16X16 API Library Reference Manual*.

3.1. Main Header File

Throughout the remainder of this document references are made to various header files included as part of the OPTO16X16 driver installation. For ease of use it is suggested that applications include only the single header file shown below rather than individually including those headers identified separately later in this document. Including this header file pulls in all other pertinent OPTO16X16 specific header files. Therefore, sources may include only this one OPTO16X16 header and make files may reference only this one OPTO16X16 include directory.

Description	File	Location
Header File	opto16x16_main.h	.../include/

3.2. Main Library File

Throughout the remainder of this document references are made to various statically linkable libraries included as part of the OPTO16X16 driver installation. For ease of use it is suggested that applications link only the single library file shown below rather than individually linking those libraries identified separately later in this document. Linking this library file pulls in all other static libraries included with the driver. Therefore, make files may reference only this one OPTO16X16 static library and only this one OPTO16X16 library directory.

Description	File	Location
Static Library	opto16x16_main.a	.../lib/
	opto16x16_multi.a	

NOTE: For applications using the OPTO16X16 and no other GSC devices, link the `opto16x16_main.a` library. For applications using multiple GSC device types, link the `xxxx_main.a` library for one of the devices and the `xxxx_multi.a` library for the others. Linking multiple `xxxx_main.a` libraries may likely produce link errors due to duplicate symbols being defined. While it may make little or no difference, it is recommended that one choose the `xxxx_main.a` library from the driver with the largest number in positions three (x.x.X.x.x) and/or four (x.x.x.X.x) in the driver release version number.

NOTE: The OPTO16X16 API Library is implemented as a shared library and is thus not linked with the OPTO16X16 Main Library. The API Library must be linked with applications by adding the argument `-lopto16x16_api` to the linker command line.

3.2.1. Build

The main library is built via the Overall Make Script (section 2.7, page 11). However, the main library can be built separately following the below steps.

1. Change to the directory where the main library resides (`.../lib/`).
2. Remove existing build targets using the below command.

```
make clean
```

3. Build the main library by issuing the below command.

```
make
```

3.2.2. System Libraries

In addition to linking the static library named above, as well as the API Library shared object file, applications may need to also link in additional system libraries as noted below.

Library	gcc Link Flag
Math	-lm
POSIX Thread	-lpthread
Real Time	-lrt

4. API Library

The OPTO16X16 API Library is the software interface between user applications and the OPTO16X16 device driver. The interface is accessed by including the header file `opto16x16_api.h`.

NOTE: Contact General Standards Corporation if additional library functionality is required.

4.1. Files

The library files are summarized in the table below.

Description	File	Location
Source Files	*.c, *.h ...	.../api/
Header File	opto16x16_api.h	.../include/
Library File	libopto16x16_api.so	.../lib/ /usr/lib/ †

† The shared object library is automatically copied to `/usr/lib/` when it is built.

4.2. Build

The API Library is built via the Overall Make Script (section 2.7, page 11), but can be built separately following the below steps.

NOTE: The following steps may require elevated privileges.

1. Change to the directory where the library sources are installed (`.../api/`).
2. Remove existing build targets using the below command.

```
make clean
```

3. Compile the source files and build the library by issuing the below command. This step copies the API Library file to `/usr/lib/`.

```
make
```

4.3. Library Use

The library is used at application compile time, at application link time and at application run time. At compile time include the below listed header file in each source file using a component of the Library interface. Also, edit the include file search path to locate the header file in the below listed directory. At link time the Library's shared object file is linked via the linker command line. This can be done by naming the `.so` file explicitly or by adding the below linker command line argument. At run time the library is found in the directory `/usr/lib/`. (The shared object file is automatically copied to `/usr/lib/` when it is built.)

Description	File	Location	Linker Argument
Header File	opto16x16_api.h	.../include/	
Shared Object Library	libopto16x16_api.so	.../lib/ /usr/lib/	-lopto16x16_api

4.4. Macros

For detailed macro information refer to this same section number in the *OPTO16X16 API Library Reference Manual*.

4.5. Data Types

For detailed data type information refer to this same section number in the *OPTO16X16 API Library Reference Manual*.

4.6. Functions

For detailed function information refer to this same section number in the *OPTO16X16 API Library Reference Manual*.

4.7. IOCTL Services

For detailed IOCTL information refer to this same section number in the *OPTO16X16 API Library Reference Manual*.

5. The Driver

NOTE: Contact General Standards Corporation if additional driver functionality is required.

5.1. Files

The device driver files are summarized in the table below.

Description	Files	Location
Source Files	*.c, *.h ...	.../driver/
Header File	opto16x16.h	
Driver File	opto16x16.ko † opto16x16.o ‡	

† This is for kernel versions 2.6 and later.

‡ This is for kernel versions 2.4 are earlier.

5.2. Build

NOTE: Building the driver requires installation of the kernel headers and possibly other packages.

The device driver is built via the Overall Make Script (section 2.7, page 11), but can be built separately following the below steps.

1. Change to the directory where the driver and its sources are installed (.../driver/).
2. Remove existing build targets by issuing the below command.

```
make clean
```

3. Build the driver by issuing the below command.

```
make
```

NOTE: Due to the differences between the many Linux distributions some build errors may occur. These errors may include system header location differences, which should be easily corrected.

5.3. Startup

NOTE: The driver will have to be built before being used as it is provided in source form only.

The startup script used in this procedure is designed to load the device driver and create fresh device nodes. This is accomplished by unloading the current driver, if loaded, and then loading the accompanying driver executable. In addition, the script deletes and recreates the device nodes. This is done to ensure that the device nodes in use have the same major number as assigned dynamically to the driver by the kernel, and so that the number of device nodes corresponds to the number of boards identified by the driver.

5.3.1. Manual Driver Startup Procedures

Start the driver manually by following the below listed steps.

NOTE: The following steps may require elevated privileges.

1. Change to the directory where the driver sources are installed (.../driver/).
2. Install the driver module and create the device nodes by executing the below command. If any errors are encountered then an appropriate error message will be displayed.

```
./start
```

NOTE: This script must be executed each time the host is booted.

NOTE: The OPTO16X16 device node major number is assigned dynamically by the kernel. The minor numbers and the device node suffix numbers are index numbers beginning with zero, and increase by one for each additional board installed.

3. Verify that the device driver module has been loaded by issuing the below command and examining the output. The module name `opto16x16` should be included in the output.

```
lsmod
```

4. Verify that the device nodes have been created by issuing the below command and examining the output. The output should include one node for each installed board.

```
ls -l /dev/opto16x16.*
```

5.3.2. Automatic Driver Startup Procedures

Start the driver automatically with each system reboot by following the below listed steps.

1. Locate and edit the system startup script `rc.local`, which should be in the `/etc/rc.d/` directory. Modify the file by adding the below line so that it is executed with every reboot. The example is based on the driver being installed in `/usr/src/linux/drivers/`, though it may have been installed elsewhere.

```
/usr/src/linux/drivers/opto16x16/driver/start
```

NOTE: For `systemd` installations the file `rc.local` may be located under the `/etc/` directory rather than under `/etc/rc.d/`.

2. Load the driver and create the required device nodes by rebooting the system.
3. Verify that the driver is loaded and that the device nodes have been created. Do this by following the verification steps given in the manual startup procedures.

5.3.2.1. File `rc.local` Not Present

Some distributions may not install a default version of `rc.local`. Some may not even create the directory `/etc/rc.d/`. If the directory is not present, then it may be created. The directory must be created with the owner and group set to `root`. The directory permissions must be set to `rxwxr-xr-x`. If the file `/etc/rc.d/rc.local` is not present, then it too may be created. The file must also be created with the owner and group set to `root`. Additionally, the file permissions must also be set to `rxwxr-xr-x`. After the directory and file are created as described, reboot to verify boot time loading of the driver. Here is an example of a default version of `rc.local`.

```
#!/bin/bash

# Add your local content here.
```

5.3.2.2. Default `rc.local` File Permissions

The `rc.local` script may fail to run at boot time because some distributions install a default version of the file without execute permissions. Without execute permissions, boot time invocation of the script fails, which inhibits boot time loading of the driver. If this is the case, then change the file permissions to `rxwxr-xr-x`. After the file permissions are adjusted as described, reboot to verify boot time loading of the driver.

5.3.2.3. `systemd` Installations

With the advent of the `systemd` startup implementation, `rc.local` may be accessed via a `systemd` startup service. The service name may be `rc-local`, `rc-local.service` or something similar. This service may or may not be enabled by default. If the service is disabled, then the script will not execute, which prevents boot time loading of the driver. The service can be enabled with the below command line. After the service is enabled, reboot to verify boot time loading of the driver.

```
systemctl enable rc-local
```

NOTE: For `systemd` installations the file `rc.local` may be located under the `/etc/` directory rather than under `/etc/rc.d/`.

5.3.2.4. `systemd` and `rc.local` Timing

If the above steps have been performed but the driver still does not start then examine the `dmesg` output for driver messages. If the output shows that the driver starts and immediately stops, then the problem may be timing. That is, since `systemd` doesn't serialize startup initialization as done in the past, driver loading may fail if required services have not completed their own initialization. If this is the problem, then it may be corrected simply by inserting a delay in `rc.local` prior to it calling the driver's start script (i.e., `sleep` for one or more seconds).

5.3.2.5. SELinux Implications

If not disabled, then SELinux may prevent boot time loading of the driver. If this is the case, then it can be verified and corrected using SELinux related tools and utilities. First, install the necessary software using the below command. (As necessary, replace the `yum` command line with that which is available for your distribution.)

```
yum install setroubleshoot setools
```

Next, run the below command to determine if SELinux is preventing the driver from loading at boot time.

```
sealert -a /var/log/audit/audit.log
```

If SELinux is preventing the driver from loading, then the output from the above command should include a reference to the driver's start script, the `insmod` command that loads the driver or the name of the driver executable. If so, then the output should also indicate the commands necessary to resolve the issue. The following is an example of the instructions given when the culprit is `insmod`, which is the start script command that loads the driver. After running these commands reboot the system to verify boot time loading of the driver.

```
ausearch -c 'insmod' --raw | audit2allow -M my-insmod
semodule -X 300 -i my-insmod.pp
```

5.4. Verification

Follow the below steps to verify that the driver has been properly installed and started.

1. Verify that the file `/proc/opto16x16` is present. If the file is present then the driver is loaded and running. Verify the file's presence by viewing its content with the below command.

```
cat /proc/opto16x16
```

5.5. Version

The driver version number can be obtained in a variety of ways. It is reported by the driver both when the driver is loaded and when it is unloaded (depending on kernel configuration options, this may be visible only in places such as `/var/log/messages`). It is reported in the text file `/proc/opto16x16` while the driver is loaded and running. The version number is also given in the file `release.txt` in the root install directory.

5.6. Shutdown

Shutdown the driver following the below listed steps.

NOTE: The following steps may require elevated privileges.

1. If the driver is currently loaded then issue the below command to unload the driver.

```
rmmod opto16x16
```

2. Verify that the driver module has been unloaded by issuing the below command. The module name `opto16x16` should not be in the listed output.

```
lsmod
```

6. Document Source Code Examples

The source code examples included in this document are built into a statically linkable library usable with console applications. The purpose of these files is to verify that the documentation samples compile and to provide a library of working sample code to assist in a user's learning curve and application development effort.

6.1. Files

The library files are summarized in the table below.

Description	Files	Location
Source Files	*.c, *.h ...	.../docsrc/
Header File	opto16x16_dsl.h	.../include/
Library File	opto16x16_dsl.a	.../lib/

6.2. Build

The library is built via the Overall Make Script (section 2.7, page 11), but can be built separately following the below steps.

1. Change to the directory where the documentation sources are installed (.../docsrc/).
2. Remove existing build targets by issuing the below command.

```
make clean
```

3. Compile the sample files and build the library by issuing the below command.

```
make
```

4. Rebuild the Main Library (section 3.2.1, page 14).

6.3. Library Use

The library is used both at application compile time and at application link time. At compile time include the above listed header file in each source file using a component of the library interface. At link time include the above listed static library file with the objects being linked with the application.

7. Utilities Source Code

The API Library installation includes a body of utility source code designed to aid in the understanding and use of the interface calls and IOCTL services. Utility sources are also included for device independent and common, general-purpose services. Most of the utilities are implemented as visual wrappers around the corresponding services to facilitate structured console output for the sample applications. The utility sources are compiled and linked into static libraries to simplify their use. An additional purpose of these utility services is to provide a library of working sample code to assist in a user's learning curve and application development effort.

For each API function there is a corresponding utility source file with a corresponding utility service. As an example, for the API function `opto16x16_open()` there is the utility file `open.c` containing the utility function `opto16x16_open_util()`. The naming pattern is as follows: API function `opto16x16_xxxx()`, utility file name `xxxx.c`, utility function `opto16x16_xxxx_util()`. Additionally, for each IOCTL code there is a corresponding utility source file with a corresponding utility service. As an example, for IOCTL code `OPTO16X16_IOCTL_QUERY` there is the utility file `util_query.c` containing the utility function `opto16x16_query()`. The naming pattern is as follows: IOCTL code `OPTO16X16_IOCTL_XXXX`, utility file name `util_xxxx.c`, utility function `opto16x16_xxxx()`.

7.1. Files

The utility files are summarized in the table below.

Description	Files	Location
Source Files	*.c, *.h ...	.../utils/
Header File	opto16x16_utils.h	.../include/
Library Files	opto16x16_utils.a gsc_utils.a os_utils.a plx_utils.a	.../lib/

7.2. Build

The libraries are built via the Overall Make Script (section 2.7, page 11), but can be built separately following the below steps.

1. Change to the directory where the utility sources are installed (.../utils/).
2. Remove existing build targets by issuing the below command.

```
make clean
```

3. Compile the sample files and build the library by issuing the below command.

```
make
```

4. Rebuild the Main Library (section 3.2.1, page 14).

7.3. Library Use

The library is used both at application compile time and at application link time. At compile time include the above listed header file in each source file using a component of the library interface. At link time include the above listed static library file with the objects being linked with the application.

8. Operating Information

For operating information refer to this same section number in the *OPTO16X16 API Library Reference Manual*.

9. Sample Applications

The driver archive includes a variety of sample and test applications located under the `samples` subdirectory. While they are provided without support and without any external documentation, any problems reported will be addressed as time permits. The applications are command line based and produce text output for display on a console. All of the applications are built via the Overall Make Script (section 2.7, page 11), but each may be built individually by changing to its respective directory and issuing the commands “`make clean`” and “`make`”. The initial output from each application includes information on its supported command line arguments. The following gives a brief overview of each application.

9.1. `din` - Digital Input - `.../din/`

This application reads the cable’s digital I/O signals and reports the values read to the console.

9.2. `dout` - Digital Output - `.../dout/`

This application writes a pattern to the cable’s digital output lines as it is displayed to the console.

9.3. `id` - Identify Board - `.../id/`

This application reports detailed board identification information. This can be used with tech support to help identify as much technical information about the board as possible from software.

9.4. `irq` - Interrupt Detection - `.../irq/`

This application reports detailed board identification information. This can be used with tech support to help identify as much technical information about the board as possible from software.

9.5. `regs` - Register Access - `.../regs/`

This application provides menu based interactive access to the board’s registers, and reports other pertinent information to the console.

9.6. `sbtest` - Single Board Test - `.../sbtest/`

This application performs functional testing of the driver and a user specified board, at least to the extent possible with just a single board and no additional equipment.

9.7. `tfest` - Test Fixture Test - `.../tfest/`

This application tests the functionality of the driver and a specified board when the board is connected to an OPTO16X16 specific General Standards test fixture. (This test fixture may or may not be available for your model of the OPTO16X16.)

NOTE: This application should be run with the General Standards OPTO16X16 test fixture attached. The test fixture should have the loopback jumpers installed with both external power supplies attached (+5VDC and either +5VDC or +28VDC according to the board model). The test will then run without user intervention. All tests will fail if the test fixture is not installed.

9.8. `vpd` – Vital Product Data - `.../vpd/`

This application allows a user to program a custom string into the board’s EEPROM. This helps to distinguish between boards when multiple OPTO16X16 boards are installed in the same system.

Document History

Revision	Description
April 3, 2025	Updated to release version 2.7.113.50.0. Minor editorial changes. Updated the kernel support tables. Added the <code>irq</code> sample application. Added the <code>vpd</code> sample application.
September 14, 2023	Updated to release version 2.6.104.47.0. Updated the kernel support table. Numerous minor editorial changes.
July 14, 2022	Updated to release version 2.5.100.42.0. Expanded automatic startup information. Updated the kernel support table. Added section on environment variables. Minor editorial updates.
March 25, 2021	Updated to release version 2.4.93.36.0. Various editorial changes.
November 13, 2020	Updated to release version 2.4.91.35.0. Updated the kernel support table. Expanded automatic startup information. Moved the interface content to the API Reference Manual. Various editorial changes.
August 12, 2019	Updated to release version 2.3.87.28.0. Updated the kernel support table. Various editorial changes. Added a licensing subsection.
March 1, 2019	Updated to release version 2.2.81.26.1.
December 10, 2018	Updated to release version 2.2.81.26.0. Updated the inside cover page. Updated the CPU and kernel support section. Minor editorial changes. Document reorganization.
December 6, 2016	Updated to release version 2.1.68.18.0. Removed the <code>built</code> field from the <code>/proc</code> file. Updated the kernel support table. Updated the notes for the <code>tftest</code> application. Organized sample applications alphabetically. Updated the usage of the Wait Event <code>timeout_ms</code> field. Updated material on the open call. Added open access mode descriptions. Added a section for general operating information. Made various miscellaneous updates. Some document reorganization.
September 16, 2015	Updated to release version 2.0.60.8.0. Updated the device node name to include a period before the device index. Removed double underscore that prefaced various data types.
February 28, 2014	Updated to release version 1.5.52.0. Updated the kernel support table.
January 9, 2014	Updated to release version 1.4.51.0. Updated the kernel support table.
November 8, 2013	Updated to release version 1.4.48.0.
May 18, 2013	Updated to release version 1.4.45.0.
May 11, 2013	Updated to release version 1.4.42.0. Updated the kernel support table.
July 24, 2012	Updated to release version 1.3.39.0. Updated the kernel support table.
January 10, 2012	Updated to release version 1.3.35.0.
November 15, 2011	Updated to release version 1.2.32.0. Various editorial changes. Updated the CPU and Kernel Support information.
June 29, 2010	Updated to release version 1.1.17.0.
June 24, 2010	Initial driver release. This is release version 1.0-BETA.17.0.