## Revision history

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<th>Revision</th>
<th>Date</th>
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</tr>
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<tbody>
<tr>
<td>A</td>
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<td>Initial release</td>
</tr>
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1 RB3 Platform Linux SDK

The Linux SDK for the Qualcomm Robotics RB3 Platform is built by Thundercomm. The platform is based on Yocto Rocko with Linux Kernel 4.9 and GCC 6.5.

This document provides information on how to obtain, build, and program SDA845 software into the RB3 Platform.

For more information about software updates and the software development kit (SDK) for your host machine operating system please visit:

https://www.thundercomm.com/app_en/product/1544580412842651

1.1 RB3 Platform Linux SDK support

For support, create a request in the Qualcomm Robotics RB3 Platform forum:

https://www.thundercomm.com/forum/category/1/qualcomm-robotics-rb3-platform
2 Set Up the Development Environment

This chapter describes how to set up the Linux development environment on an Ubuntu/Windows host machine.

- For compiling code using Qualcomm SDK, Ubuntu 14.04 is required.
- For flashing firmware images, an Ubuntu/Windows machine is needed.

2.1 Required hardware, software, and equipment

The following table lists the hardware, software, and other equipment required to install and run the software.

<table>
<thead>
<tr>
<th>Item description</th>
<th>Version</th>
<th>Source/vendor</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>Standalone system minimum requirement:</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>8 GB RAM</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Quadcore CPU</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td><strong>NOTE:</strong> Lower specs will increase compilation time. Ideal compilation time required for a system with 16 GB RAM and Intel i7-2600 @3.4 GHz is about an hour.</td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Ubuntu 14.04 LTS Linux distribution for 64-bit architecture</td>
<td>14.04 LTS</td>
<td>Ubuntu Community/Canonical, Ltd.</td>
<td>SDK build host OS</td>
</tr>
<tr>
<td>Repo</td>
<td></td>
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<td>SDK source management tool</td>
</tr>
<tr>
<td>Python</td>
<td>Python 2.7.6 with sqlite3 library</td>
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<td>Building subsystem</td>
</tr>
<tr>
<td>QTI USB driver</td>
<td>QUD.WIN 1.1 Installer 10032.1 or later</td>
<td><a href="https://www.thundercomm.com/app_en/product/1545580412842651#doc">https://www.thundercomm.com/app_en/product/1545580412842651#doc</a></td>
<td>QTI USB WWAN Driver installer for Microsoft Windows</td>
</tr>
<tr>
<td>Android SDK tools (ADB, Fastboot)</td>
<td>r10 or later ADB 1.0.29 or later</td>
<td>Android open-source project</td>
<td>ADB and Fastboot tools for Windows</td>
</tr>
</tbody>
</table>

**NOTE:** See the release notes for current versions of the ARM toolchain and Qualcomm® Hexagon™ LLVM toolchain.
2.2 Install Ubuntu 14.04 (64-bit) system

**Prerequisite:** You must be able to log in as root or use sudo to have root permissions during the installation.

1. Create an installation CD (the CD image is ubuntu-14.04.2-desktop-amd64.iso) and install it on the computer following the instructions at:


2. Perform a software update using one of the following options:
   - In the GUI, select System > Administration > Update Manager.
   - From a shell command line:
     a. Edit the source config file to directly enable the universe and multiverse sources and disable the Ubuntu installation CD source.
        
        ```
        sudo vi /etc/apt/sources.list
        ```
     b. From the command line, perform the package list update and package upgrades.
        
        ```
        sudo apt-get update
        sudo apt-get upgrade
        ```
     c. Use apt-get to install the additional required packages.
        
        ```
        sudo apt-get install libssl-dev
        ```
     d. See [https://source.android.com/source/initializing.html](https://source.android.com/source/initializing.html) for the required packages. In addition to the packages mentioned in the link, install libssl-dev.
        
        ```
        sudo apt-get install libssl-dev
        ```
     e. Make bash the default shell (shell /bin/sh to invoke bash) using one of the following options:
        - Use sudo dpkg-reconfigure dash command and reconfigure the package.
        - Manually change the symlink /bin/sh > dash to /bin/sh > bash. Use the sudo rm /bin/sh command to remove
        - Use sudo ln -s /bin/bash /bin/sh

   For more information, see the Ubuntu Wiki page at: [https://wiki.ubuntu.com/DashAsBinSh](https://wiki.ubuntu.com/DashAsBinSh)

2.3 Install ADB, Fastboot, and USB host interface

The Fastboot tool communicates with the RB3 bootloader and allows you to flash images onto the board. This section provides instructions for installing ADB, Fastboot, and USB drivers on your host machine.
2.3.1 On the Windows host machine

Install ADB and Fastboot
Google currently does not offer a standalone Windows Installer for Fastboot. Instead Fastboot is part of the full Android Studio integrated development environment (IDE) installation.

2. Follow the instructions to install the standalone SDK Tools. During the installation, Fastboot and ADB drivers are installed

**NOTE:** If you want to install Fastboot without the full Android Studio installation you can find third party installers on the web.

Install the USB drivers

1. Add the system environment path for ADB and Fastboot.
2. Install the Windows drivers. Windows will usually update the drivers automatically from the server. You can also download here:
   [https://www.thundercomm.com/app_en/product/1544580412842651#doc](https://www.thundercomm.com/app_en/product/1544580412842651#doc)

2.3.2 On the Linux (Ubuntu) host

Install ADB and Fastboot

To install ADB and Fastboot, execute the following command:

```
sudo apt-get install android-tools-adb
```
```
sudo apt-get install android-tools-fastboot
```

Install and configure the USB driver

Setup the udev rules on your Linux PC as follows:

3. Login as root or sudo and navigate to the directory `/etc/udev/rules.d/

1. Add the following rules in file 99-android.rules:

```
# fastboot for Robotics DragonBoard 845c
SUBSYSTEM=="usb", ATTR{idVendor}=="18d1", MODrmmodE="0777", GROUP="adm"
```
```
# adb for Robotics DragonBoard 845c
SUBSYSTEM=="usb", ATTR{idVendor}=="05c6", MODE="0777", GROUP="adm"
```
2. Restart the udev service:

   $ build@ubuntu$ sudo chmod a+r /etc/udev/rules.d/99-android.rules
   $ build@ubuntu$ sudo service udev restart

3. Reconnect RB3 to PC with USB cable.
4. Connect the power adapter.
5. Press **Power** and the system will start.

   ![Diagram](image.png)

   Server@: ~$ adb devices
   List of devices attached
   7a7d0e08        device

2.4 Required build environment

**Recommendation:** Use Ubuntu 14.04 along with gcc/g++ version 4.8.

1. Run following commands to ensure gcc/g++ 4.8 is installed:

   $ gcc --version
   $ g++ --version

2. If your host machine has an older version, complete the following steps to upgrade to 4.8:

   a. Run the following commands:

   $ sudo add-apt-repository ppa:ubuntu-toolchain-r/test
   $ sudo apt-get update
   $ sudo apt-get install gcc-4.8-multilib g++-4.8-multilib
   $ sudo update-alternatives --install /usr/bin/gcc gcc /usr/bin/gcc-4.8 100
   $ sudo update-alternatives --install /usr/bin/g++ g++ /usr/bin/g++-4.8 100
b. Select 4.8 in the prompt shown and run the following command:

```
$ sudo update-alternatives --config gcc
```

c. Select 4.8 in the prompt as shown:

```
$ sudo update-alternatives --config g++
```

3. To install the dependency library, run the following commands:

```
$ sudo apt-get install gawk wget git-core diffstat unzip texinfo gcc-multilib build-essential chrpath libstdc++-dev libssl-dev
$ sudo cpan install XML::Simple
```

4. Check that the bash shell is in use:

```
$ sudo rm /bin/sh
$ sudo ln -sf /bin/bash /bin/sh
```

**NOTE:** To run the build command, the following packages must be installed: diffstat, makeinfo, and chrpath.

For build environment dependencies, go to the Yocto Project Active Release Documentation page at https://www.yoctoproject.org/docs/, select **YP Core – Rocko 2.4.4**, and view the **Yocto Project Quick Start Guide.**
3 Program the Firmware

The following method is the recommended procedure for downloading your experimental version of self-compiled OS on RB3. A host PC is needed to program the board.

The procedure for both Windows and Linux host systems is described.

3.1 Program system images using Fastboot

NOTE: Ensure you have installed the required ADB and Fastboot drivers. Your board must be detected on your host machine.

To install Linux from a host PC complete the following steps:

1. Download the RB3 fastboot images package from the Thundercomm website and unzip to the “$[SDA845-ROBOT-IMAGE]”:
   https://www.thundercomm.com/app_en/product/1544580412842651#doc

2. Entering to Fastboot
   a. Press and hold VOL - then press Power once quickly to force the device to enter Fastboot mode
   b. Alternatively “adb reboot bootloader” from the command prompt
3. Plug the USB cable into the Device Type C port.

4. Confirm that Fastboot is active as follows:
   a. From the Windows command shell, run:
      ```
      $fastboot devices
      dae93bbb  fastboot
      ```
   b. From Linux, run:
      ```
      $ sudo fastboot devices
      dae93bbb  fastboot
      ```

5. Flash images:
   a. From the Windows command shell, run:
      ```
      $ flash_all.bat
      ```
   b. From Linux, run:
      ```
      $ sudo flash_all.sh
      ```

After the script is executed, the board will reboot automatically.
4 RB3 Platform Features and Use Cases

This chapter presents RB3 Platform features and use cases.

4.1 Set up the serial port

To enable DBUG_USB:

1. Turn ON SW2 on switch DIP_SW:

2. Log in using the following account credentials:

```
[ OK ] Started start dsp variants.
[ OK ] Reached target Multi-User System.
    Starting Update UTMP about System Runlevel Changes...
[ OK ] Started Update UTMP about System Runlevel Changes.

robot 201812300250 sda845 ttyMSM0
sda845 login: root
Password: 123456
```
4.2 Button events

The following figure shows the button positions.

![Button positions diagram]

**NOTE:** F_DL is forced download mode (emergency download)

1. Get interrupt event:

   ```
   $ adb shell
   # hexdump /dev/input/event0
   ```

   - Press the “key -” button. The terminal displays the following information:

     ```
     # hexdump /dev/input/event0
     0000000 6a1d 5c2f 0000 0000 c499 000d 0000 0000
     0000010 0001 0072 0001 0000 6a1d 5c2f 0000 0000
     0000020 c499 000d 0000 0000 0000 0000 0000
     ```

4.3 Set up the FAN control interface

The following figure shows the FAN interface position.

![FAN interface diagram]

1. Enable FAN: (1/2/3 indicate different speed levels: 1minimum, 3maximum):

   ```
   $ adb shell
   # echo 1 > /sys/kernel/fan/speed
   # echo 2 > /sys/kernel/fan/speed
   # echo 3 > /sys/kernel/fan/speed
   ```

2. Disable FAN:

   ```
   $ adb shell
   # echo 0 > /sys/kernel/fan/speed
   ```
4.4 Configure CAN interface

The following figure shows the CAN interface positions.

2. Configure the CAN device:
   - $adb shell
     #ip link set can0 down // Disable CAN;
     #ip link set can0 up type can bitrate 800000 // Enable CAN;
3. Perform the data loopback test.
   a. Receive data:
      - $adb shell
        #candump can0
        interface = can0, family = 29, type = 3, proto = 1
   b. Open another terminal, send data:
      - $adb shell
        #cansend can0 0x11 0x22 0x33 0x44 0x55 0x66 0x77 0x88

See Section 5.4 for the source location and compilation of the command.
4.5 Connectivity

The following figure shows the WLAN and BT connectivity.

![WLAN BT Connectivity Diagram]

4.5.1 Set up Wi-Fi

1. Confirm the antenna is properly connected.

2. To verify connectivity while the device is in Station mode, execute the following commands

   ```
   $ adb shell
   # vi /data/misc/wifi/wpa_supplicant.conf
   ```

   Fill in the ssid and psk of wifi as follows.

   ```
   update_config=1
eapol_version=1
ap_scan=1
fast_reauth=1
pmf=1
p2p_add_cli_chan=1
network={
    ssid="wifissid1"
    psk="wifipsk1"
}
Network={
    ssid="wifissid2"
    psk="wifipsk2"
}
   ```

3. Restart the device and connect to wifi.

   Run the following command to confirm that the device is connected to wifi. The log of IP address acknowledgement proves the connection is successful:

   ```
   $ adb shell
   #ifconfig wlan0
   wlan0      Link encap:Ethernet  HWaddr 00:0A:F5:83:66:EF
   inet addr:192.168.43.92  Bcast:192.168.43.255
   Mask:255.255.255.0
   ```
NOTE: If ping does not work, check the firewall and try to ping outside the firewall.

4.5.2 Bluetooth Generic Access Profile (GAP)

1. Before running btapp, run the btproperty in the background (run only once at the beginning):

   $ adb shell
   # btapp

2. After running btapp, type gap_menu and press Enter.

   gap_menu
   **************************************** Menu ****************************************
   enable
   disable
   inquiry
   cancel_inquiry
   pair < bt_address >       eg. pair 00:11:22:33:44:55
   unpair < bt_address >     eg. unpair 00:11:22:33:44:55
   inquiry_list
   bonded_list
   get_state
   get bt_name
   get bt address
   set bt_name < bt name >   eg. set bt_name MDM_Fluoride
   set le bt_name < bt name > eg. set_le_bt_name
   MDM_LE_Fluoride
   main_menu
   ***********************************************
4.5.3 Enable Bluetooth

After running btapp, input “enable” and press “Enter”

```
  enable
  killall: wcnsfilter: no process killed
  killall: btsnoop: no process killed
  killall: qcbtdaemon: no process killed
  /bin/sh: qcbtdaemon: not found
  BtHfpAgMsgHandler event = 1028
  ACDB -> No .acdb files found in /etc/acdbdata/
  ACDB -> found 0 form factor & soundcard independant files
  ... ...        
  ACDB -> MBHC ACDB_PIDGENERALCONFIG
  ACDB -> MBHC ACDB_PIDPLUGREMOVALDETECTION
  ACDB -> MBHC ACDB_PIDPLUGTYPEDETECTION
  ACDB -> MBHC ACDB_PIDBUTTONPRESSDETECTION
  ACDB -> MBHC ACDB_PIDIMPEDEANCEDETECTION
  send vbat data
  ACDB -> VBAT ACDB_PIDADC_CAL
  ACDB -> VBAT ACDB_PIDGAIN_PROC
  send vbat data, calling convert_vbat_data
  Vbat Registers Size: 17
  copied vbat cal size =72
  BT State is ON
```

4.5.4 Start inquiry

After running enable, type inquiry and press Enter to start inquiry.

```
  inquiry
  Inquiry Started
  Device Found details:
  Found device Addr: 28:11:a5:01:00:a2
  Found device Name: LE-Bose SoundSport
  Device class is: 7936
  Device Found details:
  Found device Addr: e4:ba:d9:10:00:c9
  Found device Name: 360FLY4K_00C8
  Device class is: 7936
  Device Found details:
  Found device Addr: 28:11:a5:24:01:05
  Found device Name: LE-reserved_N
  Device class is: 7936
  Inquiry Stopped automatically
```

**Note:** To cancel inquiry, issue the following command while the inquiry in progress: cancel_inquiry
4.5.5 Check the inquiry list

After running inquiry, type `inquiry_list` and press Enter to check the list.

```
inquiry_list
*************************** Inquiry List***************************
LE-Bose SoundSport  28:11:a5:01:00:a2
360FLY4K_00C8      e4:ba:d9:10:00:c9
LE-reserved_N       28:11:a5:24:01:05
*************************** End of List ***************************
```

4.5.6 Pair outgoing SSP

- Use the following command to pair outgoing SSP:

```
pair <bd_address>
```

- To accept or reject the outgoing pairing for the following example (pair e4:ba:d9:10:00:c9), type Yes or No and press Enter.

```
pair e4:ba:d9:10:00:c9
****************************************************
BT pairing request::Device iPhone::Pairing Code:: 281155
****************************************************
** Please enter yes / no **
yes
****************************************************
Pairing state for 360FLY4K_00C8 is BONDED
****************************************************
```

4.5.7 Check the bonded list

1. After running btapp, type `bonded_list` and press Enter to check the bonded list:

```
bonded_list
*************************** Bonded Device List ***************************
360FLY4K_00C8      a4:f1:e8:c6:2f:b4
*************************** End of List ***************************
```

2. Disconnect bonded, type disable and press Enter disable:

```
disable
killall: qcbtdaemon: no process killed
BtHfpAgMsgHandler event = 1029
killall: wcnssfmessage: no process killed
BT State is OFF
```

3. To exit from btapp, navigate to the main menu and enter the following command:

```
exit
```

See Section 5.4 for the source location and compilation of the command

4.6 Ethernet
The following figure shows the LAN port.

- Connect the LAN cable to the LAN port.

```shell
$ adb shell
# ifconfig
enp1s0u3    Link encap:Ethernet  HWaddr 00:0E:C6:81:79:01
    inet addr:192.168.7.196  Bcast:192.168.7.255
Mask:255.255.255.0
    inet6 addr: fe80::20e:c6ff:fe81:7901%1819682900/64 Scope:Link
    UP BROADCAST RUNNING MULTICAST  MTU:1500  Metric:1
    RX packets:319  errors:0  dropped:0  overruns:0  frame:0
    TX packets:17  errors:0  dropped:0  overruns:0  carrier:0
    collisions:0  txqueuelen:1000
    RX bytes:34988 (34.1 KiB)  TX bytes:1774 (1.7 KiB)

# ping www.qualcomm.com
PING www.qualcomm.com (140.205.16.110): 56 data bytes
64 bytes from 140.205.16.110: seq=0 ttl=40 time=38.816 ms
64 bytes from 140.205.16.110: seq=1 ttl=40 time=42.177 ms
64 bytes from 140.205.16.110: seq=2 ttl=40 time=38.260 ms
^C
--- www.qualcomm.com ping statistics ---
3 packets transmitted, 3 packets received, 0% packet loss
round-trip min/avg/max = 38.260/39.751/42.177 ms
```

**NOTE:** If ping does not work, check the firewall and try to ping outside the firewall.

### 4.7 Digital microphone
The following figure shows the digital microphone (DMIC) positions:

1. The board has four DMICs. Use dmic-ctl to perform separate DMIC enable, disable, and record operations.

   ```
   $ adb shell
   # dmic-ctl
   /usr/bin/dmic-ctl <MDIC_NUMBER> <SWITCH>
   DMIC_NUMBER: [0, 1, 2, 3]
   SWITCH: enable, disable
   ```

2. In the following example DMIC1 is used.
   a. To enable DMIC1:
      ```
      $ adb shell
      # dmic-ctl 0 enable
      ```
   b. To start recording, enter arecord and press Enter:
      ```
      # arecord /data/dmic0_test.wav -f S16_LE -c 1 -r 48000 -d 10
      ```
   c. The command parameter setting only records for 10 seconds. After 10 seconds, the recording stops.
   d. Move the recording file to the PC for playback verification or use a tool like Audacity to view the waveform.
      ```
      $ adb pull /data/dmic0_test.wav .
      ```
   e. To disable DMIC1:
      ```
      $ adb shell
      # dmic-ctl 1 disables
      ```
4.8 Audio

1. To verify the audio decoding functionality download the test files from here.
   https://www.thundercomm.com/app_en/product/1544580412842651#doc

   And See Section 5.5 for the source location and compilation of the command

2. Unzip to extract the contents of the file:
   □ Audio_Decode_WAV_Stereo_48KHz_16Bit.wav;
   □ Audio_Decode_AAC-LC_adts_32KHz_stereo.aac;
   □ Audio_Decode_HE-AAC V1_stereo_32KHz.aac;
   □ Audio_Decode_HE-AAC V2_stereo_44.1KHz.m4a;
   □ Audio_Decode_MP3v1_32KHz_cbr_stereo.mp3;

4.8.1 Playback WAV using amixer + aplay

```
$ adb push Audio_Decode_WAV_Stereo_48KHz_16Bit.wav /data/
```

1. To enable speaker:
   ```
   $ adb shell
   # spk-ctl enable
   ```

2. To play:
   ```
   $ adb shell
   # aplay /data/Audio_Decode_WAV_Stereo_48KHz_16Bit.wav
   ```

3. To disable speaker:
   ```
   $ adb shell
   # spk-ctl disables
   ```

4.8.2 Playback AAC_LC using hal_play_test_64bit

```
$ adb push Audio_Decode_AAC-LC_adts_32KHz_stereo.aac /data/
# hal_play_test_64bit -f /data/Audio_Decode_AAC-LC_adts_32KHz_stereo.aac -t 4 -d 2 -v 0.3 -r 32000 -c 2 -a 1
```

4.8.3 HE-AAC-V1 using hal_play_test_64bit

```
$ adb push Audio_Decode_HE-AAC V1_stereo_32KHz.aac /data/
# hal_play_test_64bit -f /data/Audio_Decode_HE-AAC\ V1_stereo_32KHz.aac -t 4 -d 2 -v 0.3 -r 16000 -c 2 -a 2
```
4.8.4 HE-AAC-V2 using hal_play_test_64bit

```
$ adb push Audio_Decode_HE-AAC V2_stereo_44.1KHz.m4a /data/
# hal_play_test_64bit -f /data/Audio_Decode_HE-AAC\ V2_stereo_44.1KHz.m4a -
  t 3 -d 2 -v 0.3 -r 22050 -c 2 -a 3
```

4.8.5 Mp3 using hal_play_test_64bit

```
$ adb push Audio_Decode_MP3v1_32KHz_cbr_stereo.mp3 /data/
# hal_play_test_64bit -f /data/Audio_Decode_MP3v1_32KHz_cbr_stereo.mp3 -t 2
  -d 2 -v 0.3 -r 32000 -c 2 -a 1
```

4.9 Sensors

The device supports five sensor types: accelerometer, gyroscope, magnetometer, proximity, and light. The sensors are situated in two groups.

The following table shows the sensor modules enabled using the SW_5 switch.

<table>
<thead>
<tr>
<th>SW_5</th>
<th>Sensor</th>
<th>Sensor_name</th>
<th>Sensor type ID</th>
</tr>
</thead>
<tbody>
<tr>
<td>ON</td>
<td>Magnetometer</td>
<td>ak0991x Magnetometer Wakeup</td>
<td>2</td>
</tr>
<tr>
<td></td>
<td>Pressure</td>
<td>icp101xx Pressure Sensor Wakeup</td>
<td>6</td>
</tr>
<tr>
<td>OFF</td>
<td>Accelerometer</td>
<td>icm4x6xx Accelerometer Wakeup</td>
<td>1</td>
</tr>
<tr>
<td></td>
<td>Gyroscope</td>
<td>icm4x6xx Gyroscope Wakeup</td>
<td>4</td>
</tr>
<tr>
<td></td>
<td>Proximity</td>
<td>ltr559 Proximity Sensor Wakeup</td>
<td>8</td>
</tr>
<tr>
<td></td>
<td>Light</td>
<td>ltr559 Ambient Light Sensor Wakeup</td>
<td>5</td>
</tr>
</tbody>
</table>

**NOTE:** Whenever the SW_5 switch is toggled, the device must be rebooted.

See Section 5.6 for the source location and compilation of the command
4.9.1 Get sensor data via sns_hal_batch

To get sensor data via sns_hal_batch:

```bash
$ adb shell
# sns_hal_batch --help
Usage: sns_hal_batch [OPTIONS]...

-h --help                  Print this message
-l --listsensors          List all available sensors and their
                          attributes
-o --output               the output file to write the sensor values to
default: /data/local/sns_hal_batch.out

Providing no parameter options runs the interactive command line
interface
Providing 1 or more parameters to sns_hal_batch will run the following
sequence:
- set batching parameters for the sensor: (sampling rate, report
  rate)
- activate the sensor
- wait for the specified duration
- deactivate the sensor

The parameters, as well as their default values, are as follows:
-s --sensor               the android sensor type enumeration
                          value
                          default: 1 for
                          android.sensor.accelerometer
-w --wakeup               flag for wakeup or non-wakeup sensor
                          w for wakeup
                          n for non-wakeup
                          d for don't care or default
                          default: d
-sr --samplingrate        the sampling rate (in Hz)
                          default: 5 Hz
-rr --reportrate          the report rate (in Hz)
                          use 0 for no batching
                          (report events as available)
                          default: 0
-d --duration             the duration (in seconds) to run the
                          sensor for
                          default: 10 seconds
```

4.9.2 Get accelerometer data

To get accelerometer data, set SW_5 to OFF and SW_6 to OFF position:

NOTE: whenever SW_5 switch is toggled, device has to be rebooted
4.9.3 Get gyroscope data

To get gyroscope data, set SW_5 to OFF and SW_6 to OFF position:

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

```
# sns_hal_batch -s 4 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version   : 0x256
HAL hal_id            : sensors
HAL hal_name          : QTI Sensors HAL Module
HAL hal_author        : Qualcomm Technologies, Inc.
get_sensors_list took 9877721611 nanoseconds
batch success
activate success
Activated sensor [Type: 4] icm4x6xx Gyroscope Wakeup (d) for 30 seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type:  4] android.sensor.gyroscope (wakeup)
    Name:icm4x6xx Gyroscope Wakeup Vendor:TDK-InvenSense
Version:275 Handle:11
    maxRange: 34.905556 resolution: 0.000067 power: 0.570000 mA
    minDelay: 2000 us maxDelay: 1000000 us
    fifoReservedEventCount: 0 fifoMaxEventCount: 10000
```

4.9.3 Get gyroscope data

To get gyroscope data, set SW_5 to OFF and SW_6 to OFF position:

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

```
# sns_hal_batch -s 4 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version   : 0x256
HAL hal_id            : sensors
HAL hal_name          : QTI Sensors HAL Module
HAL hal_author        : Qualcomm Technologies, Inc.
get_sensors_list took 9877721611 nanoseconds
batch success
activate success
Activated sensor [Type: 4] icm4x6xx Gyroscope Wakeup (d) for 30 seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type:  4] android.sensor.gyroscope (wakeup)
    Name:icm4x6xx Gyroscope Wakeup Vendor:TDK-InvenSense
Version:275 Handle:11
    maxRange: 34.905556 resolution: 0.000067 power: 0.570000 mA
    minDelay: 2000 us maxDelay: 1000000 us
    fifoReservedEventCount: 0 fifoMaxEventCount: 10000
```
4.9.4 Get magnetometer data

To get data from the magnetometer, set SW_5 to ON position:

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

```
# sns_hal_batch -s 2 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version : 0x256
HAL hal_id : sensors
HAL hal_name : QTI Sensors HAL Module
HAL hal_author : Qualcomm Technologies, Inc.
get_sensors_list took 10010516142 nanoseconds
batch success
activate success
Activated sensor [Type: 2] ak0991x Magnetometer Wakeup (d) for 30 seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type: 2] android.sensor.magnetic_field (wakeup)
Name:ak0991x Magnetometer Wakeup Vendor:akm Version:10058
Handle:3
maxRange: 4912.00000 resolution: 0.150000 power: 1.100000 mA
minDelay: 10000 us maxDelay: 1000000 us
fifoReservedEventCount: 600 fifoMaxEventCount: 10000
requiredPermission:
Sleeping for 30 seconds before deactivating and exiting
```

4.9.5 Get pressure sensor data

To get data from the pressure sensor, set SW_5 to ON position.

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

```
# sns_hal_batch -s 6 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version : 0x256
HAL hal_id : sensors
HAL hal_name : QTI Sensors HAL Module
HAL hal_author : Qualcomm Technologies, Inc.
```
get_sensors_list took 9613565153 nanoseconds
batch success
activate success
Activated sensor [Type: 6] icp101xx Pressure Sensor Wakeup (d) for 30
seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type: 6] android.sensor.pressure (wakeup)
Name:icp101xx Pressure Sensor Wakeup Vendor:TDK-Invensense Version:65544
Handle:41
maxRange: 1150.000000 resolution: 0.000100 power: 0.010000 mA
minDelay: 40000 us maxDelay: 1000000 us
fifoReservedEventCount: 300 fifoMaxEventCount: 10000
requiredPermission:
Sleeping for 30 seconds before deactivating and exiting
182936428.889120, android.sensor.pressure/icp101xx Pressure Sensor
Wakeup, 1547642389965.965156, 1012.952209, 0.000000, 0.000000, 0.000000,
1149058289, latency(ms): 16899284620172.475580
182936528.848286, android.sensor.pressure/icp101xx Pressure Sensor
Wakeup, 1547642390065.965729, 1012.957520, 0.000000, 0.000000, 0.000000,
1149058376, latency(ms): 16899284620172.434173
182936628.178390, android.sensor.pressure/icp101xx Pressure Sensor
Wakeup, 154764239165.970573, 1012.956543, 0.000000, 0.000000, 0.000000,
1149058360, latency(ms): 16899284620171.759433

4.9.6 Get light sensor data
To get data from the light sensor, set SW_5 to OFF position.

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

Whenever SW_5 switch is toggled, device has to be rebooted
# sns_hal_batch -s 5 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version : 0x256
HAL hal_id : sensors
HAL hal_name : QTI Sensors HAL Module
HAL hal_author : Qualcomm Technologies, Inc.
get_sensors_list took 3367598176 nanoseconds
batch success
activate success
Activated sensor [Type: 5] ltr559 Ambient Light Sensor Wakeup (d) for 30
seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type: 5] android.sensor.light (wakeup)
Name:ltr559 Ambient Light Sensor Wakeup Vendor:Lite-On
Version:256 Handle:25
maxRange: 1.000000 resolution: 0.100000 power: 0.110000 mA
minDelay: 0 us maxDelay: 0 us
fifoReservedEventCount: 0 fifoMaxEventCount: 10000
requiredPermission:
4.9.7 Get proximity sensor data

To get data from the proximity sensor, set SW_5 to OFF position:

NOTE: whenever SW_5 switch is toggled, device has to be rebooted

```
Whenever SW_5 switch is toggled, device has to be rebooted
# sns_hal_batch -s 8 -sr 10 -rr 10 -d 30
HAL open
HAL module_api_version: 0x1
HAL hal_api_version : 0x256
HAL hal_id : sensors
HAL hal_name : QTI Sensors HAL Module
HAL hal_author : Qualcomm Technologies, Inc.
get_sensors_list took 9779863069 nanoseconds
batch success
activate success
Activated sensor [Type: 8] ltr559 Proximity Sensor Wakeup (d) for 30
seconds, sampling at 10.000000 Hz and reporting at 10.000000 Hz
[Type: 8] android.sensor.proximity (wakeup)
Name:ltr559 Proximity Sensor Wakeup Vendor:Lite-On Version:256 Handle:27
maxRange: 1.000000 resolution: 0.100000 power: 0.150000 mA
minDelay: 0 us maxDelay: 0 us
fifoReservedEventCount: 300 fifoMaxEventCount: 10000
requiredPermission:
Sleeping for 30 seconds before deactivating and exiting
327390.761418, android.sensor.proximity/ltr559 Proximity Sensor Wakeup,
1547459690500.729312, 0.000000, 0.000000, 0.000000, 0.000000,
1065353216, latency(ms): 1689928462099.583722
242050.179333, android.sensor.proximity/ltr559 Proximity Sensor Wakeup,
154745969247.851604, 0.000000, 0.000000, 0.000000, 0.000000, 0,
latency(ms): 16899284620511.879345
```

4.10 Camera

The device supports four camera interfaces as shown in the following figure:
The sensor ID changes depending on the number of camera sensors connected simultaneously. Use the following matrix to calculate the ID for the camera devices attached in various combinations:

<table>
<thead>
<tr>
<th>No of sensors connected</th>
<th>Sr. No</th>
<th>Stereo</th>
<th>ToF</th>
<th>OV8856</th>
<th>Tracking (OV7251)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>1.1</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>1.2</td>
<td>x</td>
<td>0</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>1.3</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>1.4</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>x</td>
</tr>
<tr>
<td>2</td>
<td>2.1</td>
<td>0</td>
<td>1</td>
<td>x</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>2.2</td>
<td>0</td>
<td>x</td>
<td>1</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>2.3</td>
<td>0</td>
<td>x</td>
<td>x</td>
<td>1</td>
</tr>
<tr>
<td></td>
<td>2.4</td>
<td>x</td>
<td>0</td>
<td>1</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>2.5</td>
<td>x</td>
<td>0</td>
<td>x</td>
<td>1</td>
</tr>
<tr>
<td></td>
<td>2.6</td>
<td>x</td>
<td>x</td>
<td>0</td>
<td>1</td>
</tr>
<tr>
<td>3</td>
<td>3.1</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>x</td>
</tr>
<tr>
<td></td>
<td>3.2</td>
<td>0</td>
<td>1</td>
<td>x</td>
<td>2</td>
</tr>
<tr>
<td></td>
<td>3.3</td>
<td>0</td>
<td>x</td>
<td>1</td>
<td>2</td>
</tr>
<tr>
<td></td>
<td>3.4</td>
<td>x</td>
<td>0</td>
<td>1</td>
<td>2</td>
</tr>
<tr>
<td>4</td>
<td>4.1</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>3</td>
</tr>
</tbody>
</table>

For example:
- Sr.No 1.4: Here we are connecting only one of the supported sensors. “cameraID = 0” will select “Tracking”
- Sr.No 2.3: Here we are connecting stereo camera along with tracking(2 camera sensor scenario). In this case, “cameraID=1” will select “Tracking” while “cameraID=0” will select “Stereo”

The hal3_test application is available to capture image streams provided by the cameras. This application is written using the HAL3 API.

See Section 5.7 for the source location and compilation of the command

To run the hal3_test application, log in to the device as a root (using serial or adb shell).

```bash
$ adb shell
# hal3_test -h
Enter Camera Testing
==================== Camera Test Version =====================
CAMTEST_SHA1 : 0eaa4e256a34e2eaa014d251c2a794b684c70e00
CAMTEST_BUILD_TS: 10/24/2018 12:6:35
CAMTESTHOSTNAME : ecbld-bd116-1nx.qualcomm.com
CAMBUILD_IP     : 10.225.16.179/23

=================================================================
```
Command in program:

<order>:[Params]
Orders:
  A: ADD a camera device for test

>>A:id=0,psize=1920x1080,pformat=yuv420,ssize=1920x1080,sformat=jpeg
  U: Update meta setting
   >>U:manualae mode=1
  D: Delete current camera device
   >>D
  S: trigger Snapshot and dump preview/video
   >>Ss:2 num take num(1,2,..) picture(s), eg. s:1
  s: trigger Snapshot
   >> s:num take num(1,2,..) picture(s), eg. S:2 S:2
  v: trigger video that switch from preview
   >>v:id=0,psize=1920x1080,pformat=yuv420,vsize=1920x1080,ssize=1920x1080,
  sformat=jpeg
  p: trigger dump Preview
   >> p:num dump num(1,2,..) preview frame(s), eg. p:3 p:2
  M: set Metadata dump tag
   >>M:exp value=1,scenemode=0
  Q: Quit
4.10.1 Main Camera (OV8856)

**NOTE:** The default directory where hal3_test saves files is: /data/misc/camera/.

- Start the camera with preview mode (size:1920x1080, format:YUV420)
  - `psize`: set preview size.
  - `pformat`: set preview format and support format: yuv420, yuv_ubwc, raw10, raw8, raw16.
  - `P:1`, dump one preview frame.
    
    ```
    $ adb shell
    # hal3_test
    CAM0>> A:id=2,psize=1920x1080,pformat=yuv420
    CAM0>> P:1
    CAM0>> D
    CAM0>> Q
    # exit
    $ adb pull /data/misc/camera/"filename" 
    ```

- Set the camera auto awb mode.
  - `manualawbmode`: set manual abw mode(0:off 1:auto)
  - `file=ALOGE, tag=MyTest`: enable monitor abw status, using ALOG to output log with MyTest tag.
    
    ```
    $ adb shell
    # hal3_test
    CAM0>> A:id=2,psize=1920x1080,pformat=yuv420
    CAM0>> M:awbmode=1,file=ALOGE,tag=MyTest
    CAM0>> U:manualawbmode=1
    CAM0>> P:1
    CAM0>> D
    CAM0>> Q
    # exit
    $ adb pull /data/misc/camera/"filename" 
    ```

- Start preview with manual ae mode on.
  - `manualaemode`: set manual aemode(0:off, 1:on)
    
    ```
    $ adb shell
    # hal3_test
    CAM0>> A:id=2,psize=1920x1080,pformat=yuv420
    CAM0>> M:aemode=1,file=ALOGE,tag=MyTest
    CAM0>> U:manualaemode=1
    
    //Test under Lowlight
    CAM0>> P:5
    //switch to Brightlight
    CAM0>> P:5
    ```
Start preview with snapshot (size: 3264x2448, format: jpeg)

- `size`: set snapshot size.
- `sformat`: set snapshot format, support formats: yuv420, jpeg, raw10, raw16.

```
$ adb pull /data/misc/camera/"filename" .
```

Snapshot with auto awb mode.

```
$ adb shell
# hal3_test
CAM0>> A:id=2, psize=1920x1080, pformat=yuv420, ssize=3264x2448, sformat=jpeg
CAM0>> P:1
CAM0>> s:1
CAM0>> D
CAM0>> Q
# exit
$ adb pull /data/misc/camera/"filename" .
```

Snapshot_Camera_Auto Flicker Detection

- `manualantimode`: set manual antimode (0: off, 1: 50HZ, 2: 60HZ, 3: auto)
- `zslmode`: enable/disable zsl mode (0: disable, 1: enable)

```
$ adb shell
# hal3_test
CAM0>> A:id=2, psize=1920x1080, pformat=yuv420, ssize=3264x2448, sformat=jpeg
CAM0>> M:zslmode=1, ae_antimode=1, file=ALOGE, tag=MyTest
CAM0>> U:manualantimode=1, manualzslmode=1
CAM0>> s:1
CAM0>> D
CAM0>> Q
# exit
$ adb pull /data/misc/camera/"filename" .
```
CAM0>> s:1
CAM0>> D
CAM0>> Q
# exit
$ adb pull /data/misc/camera/"filename" .

- Snapshot_Camera_Digital Zoom
  - manualcropregion: set zoom parameters(leftxtopxwidthxheight),
  - e.g., 1306x979x653x490(crop region left:1306, top:979,width:653,height:490)
    $ adb shell
    # hal3_test
    CAM0>>
    A:id=2,psize=1920x1080,pformat=yuv420,ssize=3264x2448,sformat=jpeg
    CAM0>> M:zslmode=1,zoomvalue=1,file=ALOGE,tag=MyTest
    CAM0>> U:manualzslmode=1,manualcropregion=0x0x3264x2448
    CAM0>> P:1
    CAM0>> s:1
    CAM0>> U:manualzslmode=1,manualcropregion=1306x979x653x490
    CAM0>> P:1
    CAM0>> s:1
    CAM0>> U:manualzslmode=1,manualcropregion=1428x1071x408x306
    CAM0>> P:1
    CAM0>> s:1
    CAM0>> D
    CAM0>> Q
    # exit
    $ adb pull /data/misc/camera/"filename" .

- Snapshot_Camera_MFNR
  - Turn on MFNR:
    $ adb root
    $ adb remount
    $ adb shell mount -o rw,remount /
    $ adb shell echo "overrideEnableMFNR=TRUE" > /vendor/etc/camera/camxoverridesettings.txt
    $ adb shell echo "advanceFeatureMask=0x02" >> /vendor/etc/camera/camxoverridesettings.txt

    $ adb shell
    # hal3_test
    CAM0>>
    A:id=2,psize=1920x1080,pformat=yuv420,ssize=3264x2448,sformat=jpeg
    CAM0>> M:zslmode=1,file=ALOGE,tag=MyTest
    CAM0>> U:manualzslmode=1
    CAM0>> P:1
    CAM0>> s:1
    CAM0>> D
    CAM0>> Q
# exit
$ adb pull /data/misc/camera/"filename".

- Turn off MFNR:

  $ adb shell "echo "overrideEnableMFNR=False" >>
  /vendor/etc/camera/camxoverridesettings.txt"
  $ adb shell "echo "advanceFeatureMask=0x01" >>
  /vendor/etc/camera/camxoverridesettings.txt"
  $ adb reboot

  $ adb shell
  # hal3_test
  CAM0>>
  A:id=2,psize=1920x1080,pformat=yuv420,ssize=3264x2448,sformat=jpeg
  CAM0>> M:zslmode=1,file=ALOGE,tag=MyTest
  CAM0>> U:manualzslmode=1
  CAM0>> P:1
  CAM0>> s:1
  CAM0>> D
  CAM0>> Q

- Camera video recording with fps:30, encoder:h264, size:1920x1080, bitrate:16Mbit.

  - vsize: set video size.
  - codectype: select encoder(0:H264/avc, 1:H265/hevc)
  - fpsrange: set sensor fps. If you want a variable fps mode, you can use format like this fpsrange=min-max.
  - bitrate: set encoder output bitrate(Mb)

  $ adb shell
  # hal3_test
  CAM0>>
  A:id=2,psize=1920x1080,pformat=yuv420,ssize=3264x2448,sformat=jpeg,
  fpsrange=30-30,codectype=0,bitrate=16
  CAM0>> D
  CAM0>> Q

- Camera video recording with fps:30, encoder:h265, size:1920x1080, bitrate:8Mbit

  $ adb shell
  # hal3_test
  CAM0>>
  A:id=2,psize=1920x1080,pformat=yuv420,ssize=1920x1080,sformat=jpeg,
  fpsrange=30-30,codectype=1,bitrate=8
  CAM0>> D
  CAM0>> Q
Camera video recording with MCTF on,

The video file is saved on /data/misc/camera/ path and can get this file by adb pull cmd, this video can be play with various video player on PC that support H264 decoding.

```bash
$ adb root
$ adb remount
$ adb shell mount -o rw,remount /
$ adb shell "echo "advanceFeatureMask=0x01">
/vendor/etc/camera/camxoverridesettings.txt"
$ adb shell "echo logVerboseMask=0xFFFFFFFF">
/vendor/etc/camera/camxoverridesettings.txt"
$ adb shell "echo enableMCTF=TRUE">
/vendor/etc/camera/camxoverridesettings.txt"

$ adb shell
# hal3_test
CAM0>>
A:id=2,psize=1920x1080,pformat=yuv420,vsize=1920x1080,ssize=3264x2448,sformat=jpeg,fpsrange=30-30,codectype=0
CAM0>> P:1
CAM0>> D
CAM0>> Q
```

Turn off MCTF:

```bash
$ adb shell "echo "advanceFeatureMask=0x01">
/vendor/etc/camera/camxoverridesettings.txt"
$ adb shell "echo logVerboseMask=0xFFFFFFFF">
/vendor/etc/camera/camxoverridesettings.txt"
$ adb shell "echo "enableMCTF=False">
/vendor/etc/camera/camxoverridesettings.txt"
$ adb reboot
$ adb shell
# hal3_test
CAM0>>
A:id=2,psize=1920x1080,pformat=yuv420,vsize=1920x1080,ssize=3264x2448,sformat=jpeg,fpsrange=30-30,codectype=0
CAM0>> P:1
CAM0>> D
CAM0>> Q
```

Camera video recording and live shot.

```bash
$ adb shell
# hal3_test
CAM0>>
A:id=2,psize=1920x1080,pformat=yuv420,ssize=3264x2448,sformat=jpeg,vsize =1920x1080,codectype=0,fpsrange=30-30
CAM0>> P:1
CAM0>> s:1
CAM0>> D
CAM0>> Q
```
4.10.2 Tracking (OV7251)

- Preview_Camera_640*480 dump raw

```bash
$ adb shell
# hal3_test
CAM0>> a:id=3,psize=640x480,pformat=raw10
CAM0>> P:1
CAM0>> D
CAM0>> Q
#exit
$ adb pull /data/misc/camera/"filename" .
```

- Check raw picture with “imageJ” (https://imagej.nih.gov/ij/) tools.

4.10.3 Stereo camera

- Depth Camera_Preview_720P_ Dump RAW:

```bash
$ adb shell setprop persist.al.miniisp.camx.stop 1
$ adb shell setprop persist.al.camera.depth.dump 1
$ adb shell setprop persist.al.dump.count 5
$ adb shell setprop persist.al.scid 4

# hal3_test
CAM0>>
A:id=0,psize=1280x720,pformat=yuv420,ssize=1280x720,sformat=jpeg,altek=1
CAM0>> Quit
# exit
$ adb pull /data/misc/camera/"filename" .
```

- Use AltekImageViewer.exe tool to check raw files.

  Get AltekImageViewer.exe and refer to altek ImageViewer_1.30w-v01.pdf file for how to use AltekImage Viewer.

  https://www.thundercomm.com/app_en/product/1544580412842651#doc
4.10.4 ToF Dump RAW

- ToF camera 640x480 dump raw 2vc iRGB+depth:

```bash
$ adb shell
# testapp
# 1    //Select image type
# 0    //Select synchronization method, 0:Internal  1: External
# 0    //Select mode, 0:near  1:far
# 10   //Select the number of frames saved
# 3    //Select ini_ofst_delay
# 0    //Select idle_delay
# ls /output/
bg_0001.raw bg_0007.raw depth_0003.raw depth_0009.raw ir_0005.raw
bg_0002.raw bg_0008.raw depth_0004.raw depth_0010.raw ir_0006.raw
bg_0003.raw bg_0009.raw depth_0005.raw ir_0001.raw ir_0007.raw
bg_0004.raw bg_0010.raw depth_0006.raw ir_0002.raw ir_0008.raw
bg_0005.raw depth_0001.raw depth_0007.raw ir_0003.raw ir_0009.raw
bg_0006.raw depth_0002.raw depth_0008.raw ir_0004.raw ir_0010.raw
$ adb pull /output/ .
```

Use imageJ tool to check raw files.

Get imageJ at:

[https://imagej.nih.gov/ij/](https://imagej.nih.gov/ij/)

- Guide of imageJ:

1. From the File menu, select **Open**.

2. Use the following configuration.

   - **depth**: 640 x 480.
   - **ir or bg**: 320 x 240.
   - **image type**: 16-bits unsigned.
3. An image similar to the following will be displayed (ir + bg + depth):

![Image of TOF camera temperature feature](image.png)

- TOF camera temperature feature:

```
$ adb shell
# testapp
# 0 //Select mode, 0:near  1: far
# 1  //Display the current temperature of the TOF camera, as shown below.

tof is working
please press 0 to exit
please press 1 to see current temperature
please press 2 to dump raw in /output/. 
Enter:
1
current temperature : 28.0
```
4.10.5 Three camera concurrency mode

Connect the camera sensors in the following table before running the test app. To enable each camera, see the camera ID shown:

<table>
<thead>
<tr>
<th>Camera module name</th>
<th>Stereo</th>
<th>ToF</th>
<th>OV8856</th>
<th>Tracking</th>
</tr>
</thead>
<tbody>
<tr>
<td>Camera ID</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>3</td>
</tr>
<tr>
<td>Whether Depend on ISP</td>
<td>Yes</td>
<td>No</td>
<td>Yes</td>
<td>No</td>
</tr>
</tbody>
</table>

There are only two ISP interfaces on Robotics DK. As soon as ToF is enabled both the ISPs are automatically selected for ToF consumption. During the concurrency mode, enable other camera sensors before enabling ToF/Tracking. This prevents the ToF camera from occupying the ISP interface on the Robot DK.

- Enable preview of Main+Tracking+ToF:
  
  ```shell
  adb shell
  # hal3_test
  A:id=2, psize=1920x1080, pformat=yuv420
  P:1
  A:id=3, psize=640x480, pformat=raw10
  P:1
  A:id=1, psize=640x480, pformat=raw16, dsize=640x480, dformat=raw16
  P:1
  D
  Q
  ```

- Enable preview of Main+Stereo (depth)+ToF:
  
  ```shell
  adb shell
  # hal3_test
  A:id=2, psize=1920x1080, pformat=yuv420
  P:1
  A:id=0, psize=1280x720, pformat=yuv420, ssize=1280x720, sformat=jpeg, altek=1
  A:id=1, psize=640x480, pformat=raw16, dsize=640x480, dformat=raw16
  P:1
  D
  Q
  ```

- Enable preview of Tracking+Stereo (depth)+ToF:
  
  ```shell
  adb shell
  # hal3_test
  A:id=3, psize=640x480, pformat=raw10
  P:1
  A:id=0, psize=1280x720, pformat=yuv420, ssize=1280x720, sformat=jpeg, altek=1
  A:id=1, psize=640x480, pformat=raw16, dsize=640x480, dformat=raw16
  P:1
  D
  Q
  ```

**NOTE:** Choose only one resolution for each camera for example. More resolution for each camera please check the spec of camera module.
4.11 Video

Download the test file from:

https://www.thundercomm.com/app_en/product/1544580412842651#doc

- H264_3840_2160_60fps;
- 1920_1080_60fps.mp4;
- 1920_1080.yuv

4.11.1 OMX

- Configure the macro environment, mainly used to set the input and output video path.

  □ MasterConfig.xml:

```xml
<xml>
  <InputFileRoot>/data/input/</InputFileRoot>
  <OutputFileRoot>/data/output/</OutputFileRoot>
</xml>
```

  □ SampleDecode.xml:

```xml
<xml>
  <DecodeSession>
    <TestCaseID>3840_2160</TestCaseID>
    <CompressionFormat>VIDEO_CodingAVC</CompressionFormat>
    <InputFile>H264_3840_2160_60fps</InputFile>
    <session_mode>dec</session_mode>
    <SinkType>FILE</SinkType>
    <PlaybackMode>1</PlaybackMode>
    <SourceHeight>2160</SourceHeight>
    <SourceWidth>3840</SourceWidth>
    <OutputHeight>2160</OutputHeight>
    <OutputWidth>3840</OutputWidth>
  </DecodeSession>
</xml>
```

- Decode command:

```
$ adb shell mkdir /data/input /data/output
$ adb push MasterConfig.xml /data/
$ adb push H264_3840_2160_60fps /data/input/
```
$ adb push SampleDecode.xml /data/

$ adb shell
# mm-vidc-omx-test /data/ /data/SampleDecode.xml
Frame Num= 299 file_offset=0x0 frame_size=0x40f0 pBuffer=0xebac1000
fileoffset:0x4b909b status:0x0
Frame Num= 300 file_offset=0x0 frame_size=0x40f0 pBuffer=0xeb401000
fileoffset:0x4bd18b status:0x0
VT_CONSOLE RunTest::69 Test passed
# ls -al /data/output/
-rw-rw-rw- 1 root root 940032000 Dec 29 20:10 3840_2160.yuv

4.11.2 GST

- See Section 5.8.2 for the source location and compilation of the command

- Environmental configuration:

$ adb shell mkdir /data/input /data/output
$ adb push 1920_1080_60fps.mp4 /data/input
$ adb push 1920_1080.yuv /data/input
$ adb shell
# export GST_REGISTRY=/data/gstreamer-1.0/registry.$(uname -m).bin
# export GST_REGISTRY_UPDATE=no
# gst-launch-1.0 > /dev/null

- Decoder/Encoder
  - Decoder:SW (Software Decoder):
    # gst-launch-1.0 -e filesrc location=/data/input/1920_1080_60fps.mp4
      ! qtdemux name=demux demux. ! queue ! h264parse ! avdec_h264 !
      filesink location=/data/output/1920_1080_60.yuv

      Setting pipeline to PAUSED ...
      Pipeline is PREROLLING ...
      Redistribute latency...
      Redistribute latency...
      Pipeline is PREROLLED ...
      Setting pipeline to PLAYING ...
      New clock: GstSystemClock
      Got EOS from element "pipeline0".
      Execution ended after 0:00:08.570580309
      Setting pipeline to PAUSED ...
      Setting pipeline to READY ...
      Setting pipeline to NULL ...
      Freeing pipeline ...

      #ls /data/output
      1920_1080_60.yuv

  - Decoder:HW (Hardware Decoder):
# gst-launch-1.0 -e filesrc location=/data/input/1920_1080_60fps.mp4 ! qtdemux name=demux demux. ! queue ! h264parse ! omxh264dec ! filesink location=/data/output/1920_1080_60hw.yuv

Setting pipeline to PAUSED ...
Pipeline is PREROLLING ...
Pipeline is PREROLLED ...
Setting pipeline to PLAYING ...
New clock: GstSystemClock
Got EOS from element "pipeline0".
Execution ended after 0:00:08.476530986
Setting pipeline to PAUSED ...
Setting pipeline to READY ...
Setting pipeline to NULL ...
Freeing pipeline ...

#ls /data/output
1920_1080_60hw.yuv

Encoder:HW (Hardware Encoder):

# gst-launch-1.0 -e filesrc location=/data/input/1920_1080.yuv ! videoparse width=1920 height=1080 format=nv12 framerate=60 ! omxh264enc target-bitrate= 80000000 quant-p-frames=59 quant-b-frames=0 control-rate=variable ! 'video/x-h264,streamformat=(string)byte-stream,profile=high' ! h264parse ! filesink location=/data/output/1920_1080_60.h264

Setting pipeline to PAUSED ...
Pipeline is PREROLLING ...
Pipeline is PREROLLED ...
Setting pipeline to PLAYING ...
New clock: GstSystemClock
Got EOS from element "pipeline0".
Execution ended after 0:00:10.204220673
Setting pipeline to PAUSED ...
Setting pipeline to READY ...
Setting pipeline to NULL ...
Freeing pipeline ...

#ls /data/output
1920_1080_60.h264
4.12 OpenGL ES

1. Get the test file from:
   https://www.thundercomm.com/app_en/product/1544580412842651#doc

   https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip

2. Extract the downloaded file:

   $ unzip Robotics-opengles-testbin.zip
   $ tree Robotics-opengles-testbin/
   Robotics-opengles-testbin/
   ├── es11
   │   └── es11_32
   │       └── conform_cl
   │       └── conform_cm
   │       └── covegl
   │       └── covegl_cl
   │       └── covegl_cm
   │       └── primtest_cl
   │       └── primtest_cm
   │   └── es11_64
   │       └── conform_cl
   │       └── conform_cm
   │       └── covegl
   │       └── covegl_cl
   │       └── covegl_cm
   │       └── primtest_cl
   │       └── primtest_cm
   └── push.sh

3. Upload test commands to the device:

   $ adb root
   $ adb remount
   $ adb shell mount -o remount rw /
   $ adb shell mount -o remount rw /data
   $ adb shell mkdir -p /data/testApp/es11
   $ adb push es11_64 /data/testApp/es11
   $ adb shell chmod 777 /data/testApp/es11/*

4. OpenGL ES conformance test:

   $ adb shell
   # cd /data/testApp/es11
# ./conform_cl -h
Options:
- 1 <test> Single test using "test" id.
- c <id> Use config id.
- C [1-1] Use predefined config.
- f <file> Use test set in "file".
- g <file> Generate test set in "file".
- h Print this help screen.
- l <file> Generate logfile.
- p [1-4] Set path level.
- r <seed> Set random seed.
- s Skip state check.
- v [0-2] Verbose level.
- x Force fail for config tests.

5. Execute the example as follows (testing process can take up to five hours):

# ./conform_cl -r 32555 -l mustpass.log
OpenGL ES Conformance Test
Version CONFORM_VERSION (CONFORM_DATE)

Setup Report.
Verbose level = 1.
Random number seed = 32555.
Path inactive.

Config Report.
Config ID = 1.
RGBA (5, 6, 5, 0).

Default State test passed.
Must Pass test passed.
...

Config Report.
Config ID = 63.
RGBA (8, 8, 8, 8).
Stencil (8).
Depth (24).

Config is identified as NON_CONFORMANT.
It may be rendered to using an OpenGL ES context.

************************** SUMMARY OF 'conform' RESULTS ****************************
SUMMARY: NO tests failed at any path level.
SUMMARY: 48 conformant configs, 12 non-conformant configs.
************************** END SUMMARY OF 'conform' RESULTS **************************
4.13 LTE Module

NOTE: This section explains the how to validate the Serria LTE module on Qualcomm cellular mezzanine board.

1. Please look at the picture, it shows the Serria LTE module, SIM1 Slot, SIM2 Slot.

2. Select active SIM interface

Before using SIM interface, you need to select it.

□ For selecting first SIM interface:

```bash
# echo -e "AT!UIMS=0\r\n" > /dev/ttyUSB2
# cat /dev/ttyUSB2
AT!UIMS=0?
OK
```

□ For selecting second SIM interface:

```bash
# echo -e "AT!UIMS=1\r\n" > /dev/ttyUSB2
# cat /dev/ttyUSB2
AT!UIMS=1?
OK
```

3. Check if the SIM card exists

□ The following is the case of failure.

```bash
# echo -e "AT+CPIN?\r\n" > /dev/ttyUSB2
# cat /dev/ttyUSB2
+CME ERROR: SIM not inserted
```

□ The following is the case of success.

```bash
# echo -e "AT+CPIN?\r\n" > /dev/ttyUSB2
# cat /dev/ttyUSB2
AT+CPIN?
+CPIN: READY
OK
```

Please refer GetWirelessLLC.com for more information about Sierra LTE module. We recommend looking into the Connection Manager Sample Application within the Sierra Linux QMI SDK.
4.14 Software tools and libraries

4.14.1 ROS

- ROS configuration:

  ```
  # adb shell
  # cd /opt/ros/indigo/
  /opt/ros/indigo # bash
  bash-4.4#source ./ros-env.sh
  bash-4.4# roscore &
  [1] 4065
  bash-4.4# ... logging to /home/root/.ros/log/7ce256f6-2def-11e9-8312-4962d813cee8/roslaunch-sda845-4065.log
  Checking log directory for disk usage. This may take awhile.
  Press Ctrl-C to interrupt
  Done checking log directory for disk usage. Usage is <1GB.

  started roslaunch server http://localhost:46837/
  ros_comm version 1.11.21

  SUMMARY
  ========

  PARAMETERS
  * /roldistro: indigo
  * /rosversion: 1.11.21

  NODES
  auto-starting new master
  process[master]: started with pid [4077]
  ROS_MASTER_URI=http://localhost:11311/

  setting /run_id to 7ce256f6-2def-11e9-8312-4962d813cee8
  process[rosout-1]: started with pid [4090]
  started core service [/rosout]

  Run hello_world:

  bash-4.4# cd bin/
  bash-4.4# ./hello_world
  [ INFO] [1549016659.810443307]: hello_world
  [ INFO] [1549016660.813989869]: hello_world
  [ INFO] [1549016661.81489139]: hello_world
  [ INFO] [1549016662.810563462]: hello_world
  [ INFO] [1549016663.814270649]: hello_world
  [ INFO] [1549016664.813896326]: hello_world
  [ INFO] [1549016665.810701117]: hello_world
  ```
Log painting "[ INFO] [TimeTag]: hello_world" and there should be no failure to return.

- Please refer following link for more details:
  https://github/ander-ansuatesgi/ros-hello-world/archive/master.tar.gz

4.14.2 Qualcomm Hexagon Vector eXtensions (Qualcomm® Hexagon™ Vector eXtensions(HVX))

Hexagon DSP SDK supports the RB3 Platform. For details see:
  https://developer.qualcomm.com/software/hexagon-dsp-sdk

This section provides a step-by-step guide to build, load, and execute the calculator example on Robotics in an Ubuntu environment.

4.14.2.1 Hexagon SDK environment construction

1. Hexagon SDK download:

   a. The installer takes care of downloading and installing all Hexagon SDK dependencies.
   b. If you want, you can install at your desired location eg:
      /local/mnt/RB3/Qualcomm/Hexagon_SDK
   c. To get started with the Hexagon SDK, open a new terminal and run
      setup_sdk_env.source.
This script configures the local environment. These changes are not persistent in the terminal instance, so you must run setup_sdk_env.source on each terminal you want to develop in.

```
$ cd < Hexagon SDK root directory, default is:
~/Qualcomm/Hexagon_SDK/<version> >
$ source setup_sdk_env.source
```

d. Verify env path setting : echo $HEXAGON_TOOLS_ROOT

2. Hexagon tool (Hexagon.LLVM_linux_installer_8.1.05.bin) needs to go to the website below to apply. https://developer.Qualcomm.com/software/hexagon-dsp-sdk/tool-request

When Qualcomm approves your application, you will receive an email with a download link. Download the tool and install it.

   a. During installation you can opt for default location or change it according to your desired path eg: /local/mnt/RB3/Qualcomm/HEXAGON_Tools

   b. If the tools are installed anywhere but the default location, then set the environment variable “HEXAGON_TOOLS_ROOT” to point to the installed location

   On Linux:

```
$export HEXAGON_TOOLS_ROOT=/local/mnt/RB3/Qualcomm/HEXAGON_Tools
```

   RB3@rb3-linux:/local/mnt/workspace/RB3/Qualcomm$ ls -al
   total 16
   drwxrwxr-x 4 rb3-linux users 4096 Feb 13 17:29 .
   drwxr-xr-x 5 rb3-linux users 4096 Feb 13 16:52 ..
   drwxrwxr-x 3 rb3-linux users 4096 Feb 13 16:32 Hexagon_SDK
   drwxr-xr-x 6 rb3-linux users 4096 Feb 13 17:29 HEXAGON_Tools

3. Linux cross-compilation tool

This version of Hexagon SDK supports Android and certain versions of Linux distributions (Yocto and Linaro). Android is supported by variants starting with Android (e.g., Android_Debug). Linux is supported by variants starting with Ubuntu (e.g., Ubuntu_Debug). The binaries (executables and libs) are provided for both HLOS.

The cross compilation tools for Linux are not provided with the Hexagon SDK. You need to download these separately and install them under <SDK_ROOT>/tools/linaro. If you do this, then you will be able to build Ubuntu variants for the examples. The examples are tested with gcc-linaro-4.9.

   ■ Steps to build 64 bit ubuntu binaries on Linux:

   a. Download gcc-linaro-4.9-2014.11-x86_64_aarch64-linux-gnu.tar.xz from:
      http://releases.linaro.org/archive/14.11/components/toolchain/binaries/aarch64-linux-gnu

   b. Extract the tar file and copy folder gcc-linaro-4.9-2014.11-x86_64_aarch64-linux-gnu to <Hexagon_SDK_ROOT>/tools/ folder. Rename gcc-linaro-4.9-2014.11-x86_64_aarch64-linux-gnu folder to linaro.

   ■ Steps to build 32 bit ubuntu binaries on Linuxs:

   a. Download gcc-linaro-4.9-2014.11-x86_64_arm-linux-gnueabi.tar.xz from: 
      http://releases.linaro.org/archive/14.11/components/toolchain/binaries/arm-linux-gnueabi
b. Extract the tar file and copy folder gcc-linaro-4.9-2014.11-x86_64_arm-linux-gnueabi to `<Hexagon_SDK_ROOT>/tools/` folder. Rename gcc-linaro-4.9-2014.11-x86_64_arm-linux-gnueabi folder to linaro.

4. Compiling example code:

When building the calculator example, both the stub and skeleton must be compiled and linked. This can be done by compiling both for the variant desired on the DSP as well as the application processor.

For example, to create a stub/skel pair for Linux and Hexagon, the following commands must be executed:

```
$ cd ~/Qualcomm/Hexagon_SDK/3.4.1
$ source setup_sdk_env.source
$ cd examples/common/calculator
$ make tree V=hexagon_Debug_dynamic_toolv81_v65 CDSP_FLAG=1
$ make tree V=UbuntuARM_Debug_aarch64 CDSP_FLAG=1
```

Compiled file:

```
$ tree UbuntuARM_Debug_aarch64/ship/
UbuntuARM_Debug_aarch64/ship/
    ├── calculator
    │   └── calculator_test.so
    └── libcalculator.so
$ tree hexagon_Debug_dynamic_toolv81_v65/ship/
hexagon_Debug_dynamic_toolv81_v65/ship/
    └── libcalculator_skel.a
    └── libcalculator_skel.so
```

**Note:** Please refer to help file “Qualcomm/Hexagon_SDK/3.4.1/docs/Dependencies_Common.html” in case you face compilation issue

### 4.14.2.2 On-target testing

- To execute the calculator test on Robotics perform the following steps:
  ```
  $ cd ~/Qualcomm/Hexagon_SDK/3.4.1/examples/common/calculator
  $ adb push hexagon_Debug_dynamic_toolv81_v65/ship/libcalculator_skel.so /usr/lib/rfsa/adsp/
  $ adb push UbuntuARM_Debug_aarch64/ship/libcalculator.so /usr/lib64/
  $ adb push UbuntuARM_Debug_aarch64/ship/calculator /usr/bin/
  ```
  
- To install the TestSig on device:
  1. First discover the device serial number. The following steps print out the device serial number.
     ```
     $ cd ~/Qualcomm/Hexagon_SDK/3.4.1
     $ adb push tools/elfsigner/getserial/UbuntuARM_Release_aarch64/getserial
     /usr/bin/
     $ adb shell /usr/bin/getserial
     /usr/bin/getserial: /usr/lib64/libadsprpc.so: no version information available (required by /usr/bin/getserial)
     ```
Next generate a test signature based on that serial number and push it to the device. The test signature is discovered on boot so a reboot is required.

```bash
$ cd ~/Qualcomm/Hexagon_SDK/3.4.1
$ source setup_sdk_env.source
$ python tools/elfsigner/elfsigner.py -t 0x2f5800d6
Logging to ~/Qualcomm/Hexagon_SDK/3.4.1/output/Elfsigner_log.txt
Attention:
Use of this tool is conditioned upon your compliance with Qualcomm Technologies'(and its affiliates') license terms and conditions; including, without limitations, such terms and conditions addressing the use of such tools with open source software.

Agree? [y/n]:
y
Signing a file may take up to 3 minutes due to network connectivity. Please wait patiently.

------------------------------------------------------------
Signing complete! Output saved at
/home/lizc/Qualcomm/Hexagon_SDK/3.4.1/output/testsig-0x2f5800d6.so

$ adb push output/testsig-0x2f5800d6.so /usr/lib/rfsa/adsp/
$ adb reboot
```

Execute the example as follows:

```bash
$ adb shell
# calculator 1 1000 // Run Calculator Example Locally on CPU
- starting calculator test
- allocate 4000 bytes from ION heap
- creating sequence of numbers from 0 to 999
- compute sum locally
- sum = 499500
- success

# calculator 0 1000 //Run Calculator Example on DSP
- starting calculator test
- allocate 4000 bytes from ION heap
- creating sequence of numbers from 0 to 999
- compute sum on the DSP
- sum = 499500
- success
```
4.14.3 FastCV™

FastCV is designed for efficiency on all ARM-based processors, but is tuned to take advantage of the Qualcomm® Snapdragon™ processor (S2 and above). This gives you the most widely used, computationally intensive vision processing APIs, with hardware acceleration and better performance on mobile devices.

1. Download “FastCV_test_data” test resources from:
   https://www.thundercomm.com/app_en/product/1544580412842651#doc

2. Push the test resource to the device:
   $ adb push fastcv_test_data /data/

3. The test commands are divided into 64bit and 32bit. The following is introduced with 64bit:
   $ adb shell
   # lib64_fastcv_test
   USAGE: lib64_fastcv_test test_data_directory [-l loops] [-m module_name]
   [-p power_level][-E] [-S resolution#] [-f func_name] [-t target] [-M

   OPTIONS
   -----------------------------------------------------------------------
   -nbp
   Uses mallocs instead of internal buffer pool for
   scratch/temporary buffers.

   -psb nPreAllocBytes
   Enable Preallocate Scratch Buffers
   nPreAllocBytes is the number of bytes for the pre-allocated
   buffer.

   -l +integer
   0 = [default] do not profile
   +integer = loops to use when profiling.

   -m string
   String name of module to limit to. Valid strings in order are:
   HW, MEM, DEPTH, DOT, SSD, IIMG, IIMGYUV, IDIFF, TRNS, WARP,
   3CHANNELWARP, COLORYUVRGB, COLORYUV, COLORRGB, SCALE, BLUR, EDGES,
   SCHARR, SAD, FAST10, DESCRIPTOR,, THRESH, COPY, VEC, KMEANS, AFFINEEVAL,
AFFINEFIT, HOMOGRAPHY_EVAL, HOMOGRAPHY_FIT, POSE_EVAL, POSE_REFINE,
3_POINTS_POSE_EST, KD_TREE, LINEAR_SEARCH, BITCNT, BITWISE_OP, OFBM, BOUNDRECT,
UPSAMPLE, IPP, IPP_TRANSFORM, CONTOUR, SOLVE, PERSPECTIVE_TRANSFORM, SET,
ADAPT_THRESH, SFG MASK, ABS_DIFF, QUAD, AVERAGE, SHIFT, FLOOD_FILL, MOTION,
SVD, POLYGON, BG CODEBOOK, DRAW_CONTOUR, HOUGH_CIRCLE, HOUGH_LINE,
CALIBRATE, REMAP, PYRAMID, IMGSSEGMENTATION, LBP, FFT, CORNER_SUBPIX,
CHANNEL, STATS, NCC, FIR, FAST, IMG_INTENSITY, EDGE, KLT, MINMAX,
KMEAN STREETS_EAR, SMOOTH, ARITHM, SVM, HARRIS, MSER

-f string
String name of function to limit to. Make sure to specify
the corresponding module using -m. Valid strings are:
fcvNCCPatchOnCircle8x8u8, fcvNCCPatchOnSquare8x8u8,
... ...
fcvGLBPu8, fcvFFT8u8, fcvIFFT32, fcvCornerRefineSubPixu8
Note: Not all modules have function limit functionality yet.
Please use this option with module limit option to limit to
a particular function.

-e string
String name of exhaustive test data directory.

-p integer
Power mode to run QDSP in. Valid values are:
0 = minimum power mode
1 = normal power mode
2 = [default] maximum power mode

-t integer
Integer value indicating target. Valid values are:
FASTCV_ALL_TARGETS = 0; FASTCV_UNIT_ARM = 2; FASTCV_UNIT_VENUM = 4;
FASTCV_UNIT_QDSP = 8; FASTCV_UNIT_FPGA = 16; FASTCV_UNIT_GPU = 32
FASTCV_UNIT_C2D = 64; FASTCV_UNIT_VFP = 128; FASTCV_UNIT_ARMv7 = 256
FASTCV_UNIT_DMA = 512; FASTCV_UNIT_QDSP_TEST = 1024;

-M integer
Integer value indicating operation mode. Valid values are:
Skip operation mode test = 0
FASTCV_OP_LOW_POWER = 1; FASTCV_OP_PERFORMANCE = 2;
FASTCV_OP_CPU_OFFLOAD = 4
Combination FASTCV_OP_LOW_POWER & FASTCV_OP_PERFORMANCE = 3
Combination FASTCV_OP_LOW_POWER & FASTCV_OP_CPU_OFFLOAD = 5
Combination FASTCV_OP_PERFORMANCE & FASTCV_OP_CPU_OFFLOAD = 6
All Combination FASTCV_OP_LOW_POWER & FASTCV_OP_PERFORMANCE &
FASTCV_OP_CPU_OFFLOAD = 7

-OPT
Use this option with [-M operation_mode] to skip unit testing on individual processing units and test only operation tables

-s seed
Seed for random number generator.

-o
FLAG to enable opencv benchmark profiling Results

-L +integer
Tells the number of iterations for profiling a function on QDSP with only single remoting overhead

-U
Enables only the Unit Tests while disabling the Performance Tests

-P
Enables only profiling while disabling the unit Tests

-DF
Disables fuzzing check

-E
Enables exhaustive testing to validate profiling vectors

-S Resolution#
Resolution for profiling. Default is VGA

-H
Enables QDSP test vectors to be allocated on ARM Heap instead of ION

-AC
Bump up ARM clocks

-AL
ION allocation buffers are aligned to no more than element size. No effect on heap allocated buffers.

-TWOp
Test a couple fastcv API without calling any fcvSetOperationMode to run default C reference code.

NOTE: Fast running functions will automatically have a loop multiplier and the results will be normalized accordingly.

4. Execute the example as follows:

$ adb shell
# lib64_fastcv_test /data/fastcv_test_data/ -t 0 -l 1 -L 1 -m HW

FASTCV_PROFILE, CLOCKS: ARM cpu0: 1228800, cpu1: 1516800, cpu2: 1766400, cpu3: 1766400

FASTCV_PROFILE, cpu4: 825600, cpu5: 825600, cpu6: 825600, cpu7: 825600

FASTCV_PROFILE, QDSP clk : 939205026, bimc_clk: 0, snoc_clk: 0

FASTCV_PROFILE, PROFILING ORDER : REF, Venum, QDSP, QDSPw/oRem, GPU, LowPower, Performance, CPUOffload, CPUPerformance,

FASTCV_PROFILE, FIT:(FeatureName=>FASTCV, Overall=>PASS)
5 Develop an application

This section explains how to compile the test commands used in the Section 4.

5.1 Install the Application SDK

1. Download the Application SDK:
   
   https://www.thundercomm.com/app_en/product/15445804128424651#doc
   
   https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/15445804128424651/OpenGLES_LdCuiJg5k1.zip

2. Change to the sdk directory:
   
   $ cd ROBOTICS-SDA845-LE-APP-SDK
   $ ls
   oecore-x86_64-aarch64-toolchain-nodistro.0.sh

3. Execute the oecore-x86_64-aarch64-toolchain-nodistro.0.sh command:
   
   $ ./oecore-x86_64-aarch64-toolchain-nodistro.0.sh

4. To choose the default target directory, press Enter and type Y.
   
   robot SDK installer version nodistro.0
   
   Enter target directory for SDK (default: /usr/local/oecore-x86_64):
   
   You are about to install the SDK to "/usr/local/oecore-x86_64".
   
   Proceed[Y/n]? y
   
   Extracting SDK..........................................................done
   
   Setting it up...done
   
   SDK has been successfully set up and is ready to be used.
   
   Each time you wish to use the SDK in a new shell session, you need to
   
   source the environment setup script e.g.
   
   $ . /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
   
   $ . /usr/local/oecore-x86_64/environment-setup-armv7a-neon-oemllib32-linux-gnueabi
5. Configure the system environment:

   $ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux

6. Compile the command:

   $ aarch64-oe-linux-gcc --sysroot=/usr/local/oecore-
   x86_64/sysroots/aarch64-oe-linux -O2 -fexpensive-optimizations -frenname-
   registers -fomit-frame-pointer -Wl,-O1 -Wl,--hash-style=gnu -Wl,--as-
   needed  test.c -o test

---

5.2 Hello RB3

Once the Application SDK is installed, the first RB3 Hello application can be installed.

1. Create a source file and edit:

   $ vi Hello.c
   
   #include <stdio.h>
   #include <stdlib.h>
   int main(void){
       printf("Hello RB3 !!!\n");
       return 0;
   }

2. Build and transfer the application

   a. Build the application:

      $ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
      $ aarch64-oe-linux-gcc --sysroot=/usr/local/oecore-
      x86_64/sysroots/aarch64-oe-linux -O2 -fexpensive-optimizations -frenname-
      registers -fomit-frame-pointer -Wl,-O1 -Wl,--hash-style=gnu -Wl,--as-
      needed Hello.c -o Hello

   b. Connect to the PC via TYPE-C and ensure that the ADB port can be used. Transfer the
      application:

      $ adb push Hello /bin/

3. Execute the application:

   $ adb shell
   # chmod u+x /bin/Hello
   # Hello

4. The terminal outputs the expected print information:

   / # Hello
   Hello RB3!!!

---

5.3 Button Samples app

This example shows how to get the key value of a button through the corresponding file node.

1. Create a source file and edit:

   $ vi button_test.c
   
   #include <stdio.h>
   #include <unistd.h>
```c
#include <linux/input.h>
#include <stdlib.h>
#include <string.h>
#include <sys/types.h>
#include <sys/stat.h>
#include <fcntl.h>

#define DEV_PATH0 "/dev/input/event0" //VOL-, POWER

int main(int argc, char **argv)
{
    int i = 0;
    int times = 20; //default time
    int keys_fd = 0;
    struct input_event t;

    if (argc == 2) {
        times = (int)strtoul(argv[1], NULL, 10);
    }

    keys_fd = open(DEV_PATH0, O_RDONLY | O_NDELAY);
    if(keys_fd <= 0){
        printf("open /dev/input/event0 device error!\n");
        return -1;
    }

    for(i=0;i<times*10;i++)
    {
        if(read(keys_fd, &t, sizeof(t)) == sizeof(t)){
            if(t.type == EV_KEY && t.value == 1)
                printf("Event0: type:%d, value:%d, code:%d\n",
                        t.type, t.value, t.code);
        }
        usleep(100*1000);
    }

    close(keys_fd);

    return 0;
}
```

2. Build and transfer the application

a. Edit the Makefile:

```bash
OS.exec = uname -s
OS ?= $(shell $(OS.exec))$(OS.exec:sh)
OS := $(OS)

PROG = button_test
```
CFLAGS ?= -O2 -fexpensive-optimizations -frename-registers -fomit-frame-pointer
CFLAGS += -Wl,-O1 -Wl,--hash-style=gnu -Wl,--as-needed

# Common library includes
LDLIBS = -lsensors.ssc -lpthread

$(PROG): $(PROG).o

$(PROG).o: $(PROG).c $(HDR)

clean:
  $(RM) $(PROG).o $(PROG)

sparse: $(PROG).c
  $(SPARSE) $(CPPFLAGS) $(CFLAGS) $(SPARSEFLAGS) ^

.PHONY: clean

b. Build the application:

$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ make

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used.
Transfer the application:

$ adb push button_test /bin/

3. Execute the application:

$ adb shell
# button_test

4. The terminal outputs the expected print information:

Event0: type:1, value:1, code:114
Event0: type:1, value:1, code:114
5.4 CAN

1. Download source code

As mentioned in Section 4.4, the source code for testing CAN can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

```
https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip
```

The directory after decompression is as follows:

```
$ tree can-test/
```

```
 can-test/
    ├── can-test-build.sh
    ├── canutils-4.0.6
    │   ├── iproute2-4.9.0
    │       └── libsocketcan-0.0.11
```

2. Build and transfer the application

a. The compiled script has been integrated into the code.

```
$ cat can-test/can-test-build.sh
#!/bin/bash
set -e

source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux

WORKSPACE=`pwd`

mkdir ${WORKSPACE}/libs
mkdir ${WORKSPACE}/bin

#build libsocketcan-0.0.11
cd ${WORKSPACE}/libsocketcan-0.0.11/
./configure --host=aarch64-oe-linux-gnueabi --prefix=${WORKSPACE}/libs
```
make
make install

#build canutils-4.0.6
cd ${WORKSPACE}/canutils-4.0.6
./configure --host=arm-linux libsocketcan_LIBS="-L${WORKSPACE}/libs/lib -lsocketcan" libsocketcan_CFLAGS="-I${WORKSPACE}/libs/include" CFLAGS="-I${WORKSPACE}/libs/include"
make

#build iproute2-4.9.0
cd ${WORKSPACE}/iproute2-4.9.0
./configure
make

cp -rf ${WORKSPACE}/canutils-4.0.6/src/canconfig ${WORKSPACE}/bin
cp -rf ${WORKSPACE}/canutils-4.0.6/src/candump ${WORKSPACE}/bin
cp -rf ${WORKSPACE}/canutils-4.0.6/src/canecho ${WORKSPACE}/bin
cp -rf ${WORKSPACE}/canutils-4.0.6/src/cansequence ${WORKSPACE}/bin
cp -rf ${WORKSPACE}/iproute2-4.9.0/ip/ip ${WORKSPACE}/bin

echo
echo "Done ...

b. Build the application:

$ ./can-test-build.sh

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used.
Transfer the application:

$ adb push bin/ /usr/bin/

See Section 4.4 for how to use CAN command.
5.5 Bluetooth

1. Download source code

As mentioned in Secton 4.5.2, the source code for testing bluetooth can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

The directory after decompression is as follows:

```
$ tree btapp-samplecode -L 2
btapp-samplecode
├── bt
│   ├── bt-app
│   ├── gatt
│   ├── obex_profiles
│   └── README
├── hardware
│   └── qcom
└── include
    └── hardware
└── lib
    ├── libbtobex.a
    └── libgengatt.a
└── vendor
    └── qcom
```

2. Build and transfer the application

   a. The compiled script has been integrated into the code.

   ```
   $ cat btapp-samplecode/bt/bt-app/configure.sh
   #!/bin/sh
   aclocal
   libtoolize --copy --force
   ```
autoconf
autoheader
automake --add-missing

./configure --build=x86_64-linux --host=arm-oemllib32-linux-gnueabi
--target=arm-oemllib32-linux-gnueabi --prefix=/usr --
exec_prefix=/usr --bindir=/usr/bin --sbindir=/usr/sbin --
libexecdir=/usr/libexec --datadir=/usr/share --sysconfdir=/etc --
sharedstatedir=/com --localstatedir=/var --libdir=/usr/lib --
includedir=/usr/include --oldincludedir=/usr/include --
infodir=/usr/share/info --mandir=/usr/share/man --disable-silent-
rules --disable-dependency-tracking --with-libtool --
sysroot=/usr/local/oecore-x86_64/sysroots/armv7a-vfp-neon-oe-linux-
gnueabi --with-common-includes=$Path/include/ --with-glib --with-lib-
path=/usr/local/oecore-x86_64/sysroots/armv7a-vfp-neon-oe-linux-
gnueabi/usr/lib --with-btobex --enable-target=sd845

b. Build the application:

$ cd btapp-samplecode/bt/bt-app/
$ source /usr/local/oecore-x86_64/environment-setup-armv7a-neon-
oemllib32-linux-gnueabi
$ ./configure.sh
$ make

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used.
Transfer the application:

$ adb push main/btapp /usr/bin/

See Section 4.5.2 for how to use bluetooth command.
5.6 Audio

5.6.1 aplay

1. Download source code

As mentioned in Secton 4.8.1, the source code for testing audio can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip

The directory after decompression is as follows:

$ tree alsa-utils-build
alsa-utils-build
    alsa-utils-1.1.4
    alsa-utils-build.sh

2. Build and transfer the application

a. The compiled script has been integrated into the code.

$ cat alsa-utils-build/alsa-utils-build.sh
#!/bin/bash

ALSARWORKSPACE=`pwd`

mkdir -p ${ALSARWORKSPACE}/build

cd ${ALSARWORKSPACE}/build

../alsa-utils-1.1.4/configure --build=x86_64-linux --host=arm64-oe-linux --target=arm64-oe-linux --prefix=/usr --
exect_prefix=/usr --bindir=/usr/bin --sbinid=/usr/sbin --
libexecdir=/usr/libexec --datadir=/usr/share --sysconfdir=/etc --
sharedstatedir=/com --localstatedir=/var --libdir=/usr/lib64 --
b. Build the application:

```
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ ./alsa-utils-build.sh
```

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:

```
$ adb push alsa-utils-build/build/aplay/aplay /usr/bin/
```

See Section 4.8.1 for how to use aplay command.

### 5.6.2 hal_play_test

1. Download source code

As mentioned in Section 4.8.2, the source code for testing audio can be downloaded here.

[https://www.thundercomm.com/app_en/product/1544580412842651#doc](https://www.thundercomm.com/app_en/product/1544580412842651#doc)

The directory after decompression is as follows:

```
$ tree hal_play_test
hal_play_test
    ├── Android.mk
    ├── build.sh
    ├── configure.ac
    └── inc
        └── hal_play_test.tar
```

2. Build and transfer the application

a. The compiled script has been integrated into the code.

```bash
$ cat hal_play_test/build.sh
#!/bin/bash
aclocal
autoconf
autoheader
touch NEWS README AUTHORS ChangeLog
automake --addmissing
./configure --build=x86_64-linux --host=aarch64-oe-linux --
target=aarch64-oe-linux --prefix=/usr --exec_prefix=/usr --
binder=/usr/bin --sbindir=/usr/sbin --libexecdir=/usr/libexec --
datadir=/usr/share --sysconfdir=/etc --sharedstatedir=/com --
localstatedir=/var --libdir=/usr/lib64 --includedir=/usr/include --
oldincludedir=/usr/include --infodir=/usr/share/info --
mandir=/usr/share/man
make
```

b. Build the application:

```bash
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ ./build.sh
```

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used.

Transfer the application:

```bash
$ adb push hal_play_test /usr/bin/
```

See Section 4.8.2 for how to use aplay command.
5.7 Sensors

1. Download source code

As mentioned in Secton 4.9, the source code for testing sensors can be downloaded here.
https://www.thundercomm.com/app_en/product/1544580412842651#doc

The directory after decompression is as follows:
```
$ tree sns_hal_tests
sns_hal_tests/
    Makefile
    sns_hal_batch.c
```

2. Build and transfer the application

a. The compiled script has been integrated into the code.

```
$ cat sns_hal_tests/Makefile
OS.exec = uname -s
OS := $(shell $(OS.exec))$(OS.exec:sh)
OS := $(OS)

PROG = sns_hal_batch

CFLAGS := -O2 -fexpensive-optimizations -frename-registers -fomit-frame-pointer
CFLAGS += -Wl,-O1 -Wl,--hash-style=gnu -Wl,--as-needed
CFLAGS += -D SNS_LE_QCS605

# Common library includes
LDLIBS = -lsensors.ssc -lpthread

$(PROG): $(PROG).o
```
b. Build the application:

```bash
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ make
```

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:

```bash
$ adb push sns_hal_batch /usr/bin/
```

See Section 4.9 for how to use sns_hal_batch command.

### 5.8 Camera

1. Download source code

As mentioned in Section 4.10, the source code for testing camera can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

![Thundercomm Website](https://www.thundercomm.com/app_en/product/1544580412842651#doc)

The directory after decompression is as follows:

```bash
$ tree -L 1 camera_test
camera_test/
    └── common.mk
    └── count.sh
    └── hal3_test
```

https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip
2. Build and transfer the application

a. Edit the Makefile:

```bash
#### Make sure all is the first target.
all:

CXX  ?= g++
CC   ?= gcc
CFLAGS += -I./src/ -DLINUX_ENABLED -DUSE_GRALLOC1 -DDISABLE_META_MODE=1
CFLAGS += -DCAMERA_STORAGE_DIR=""/data/misc/camera/"" -I./include
CFLAGS += -g -pthread -Wall

LDFLAGS += -lcutils -lutils -llog -lhardware -lcamera_metadata \ 
   -lglib-2.0 -ldl -lstdc++ -latomic -lpthread -lOmxCore \ 
   -lcamera_client -lbinder

C_SRC=
CXX_SRC=
OBJ=
DEP=

CXX_SRC+=src/BufferManager.cpp \ 
   src/QCameraHAL3Device.cpp \ 
   src/QCameraHAL3Base.cpp \ 
   src/QCameraHAL3TestSnapshot.cpp \ 
   src/QCameraHAL3TestVideo.cpp \ 
   src/QCameraTestVideoEncoder.cpp \ 
   src/QCameraHAL3TestConfig.cpp \ 
   src/QCameraHAL3TestPreview.cpp \ 
   src/QCameraHAL3TestTOF.cpp \ 
   src/TestLog.cpp \ 
   src/OMX_Encoder.cpp \ 
   src/BufferManager.cpp

OBJ_CE = src/QCameraHALTestMain.o

hal3_test: $(OBJ_CE)
TARGET_OBJ += $(OBJ_CE)
TARGETS += hal3_test
include ./common.mk
```

b. Build the application:

```
$ source /usr/local/oecore-x86_64/environment-setup-armv7a-neon- oemlib32-linux-gnueabi
$ make
```

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:
$ adb push hal3_test /bin/

See Section 4.10 for how to use hal3_test command.

5.9 Video

5.9.1 OMX

1. Download source code

As mentioned in Section 4.11.1, the source code for testing video can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

![Source Code Directory](https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip)

The directory after decompression is as follows:

```
$ tree mm-vidc-omx
mm-vidc-omx
  └── build.sh
  └── vtest-omx.patch
```

2. Build and transfer the application

a. The compiled script has been integrated into the code.

```
$ cat mm-vidc-omx/build.sh
#!/bin/bash

set -e

svn co https://github.com/Plutonium-AOSP/msm8937-8953_vendor_qcom_proprietary/trunk/mm-video-utils/vtest-omx
cd vtest-omx
patch -p1 < ../vtest-omx.patch
aclocal
```
autoconf
autoheader
touch NEWS README AUTHORS ChangeLog
automake --add-missing

b. make
Build the application:
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ ./build.sh

c. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:
$ adb push vtest-omx/mm-vidc-omx-test /usr/bin

See Section 4.11.1 for how to use gst command.

5.9.2 GST

3. Download source code
As mentioned in Secton 4.11.2, the source code for testing video can be downloaded here.
https://www.thundercomm.com/app_en/product/1544580412842651#doc

https://thundercomm.s3.ap-northeast-1.amazonaws.com/shop/doc/1544580412842651/OpenGLES_LdCuiJg5k1.zip

The directory after decompression is as follows:

$ tree gst_test -L 1
gst_test

button_test.tar

Samples-apps-codes

button_test.tar
bt-app_test.tar
camera_test.tar
can-test.tar
dns_hal_tests.tar
dumpלו_test.tar
gst_test.tar

opengles_tests.tar
4. Build and transfer the application

d. The compiled script has been integrated into the code.

```
$ cat gst_test/build.sh
#!/bin/bash

GSTWORKSPACE=`pwd`

mkdir -p $GSTWORKSPACE/image/usr/bin

#build gst-inspect
cd $GSTWORKSPACE/gst-inspect
make
cp gst-inspect $GSTWORKSPACE/image/usr/bin

#build gst-launch
cd $GSTWORKSPACE/gst-launch
make
cp gst-launch $GSTWORKSPACE/image/usr/bin

#build gst-stats
cd $GSTWORKSPACE/gst-stats
make
cp gst-stats $GSTWORKSPACE/image/usr/bin

#build gst-typefind
cd $GSTWORKSPACE/gst-typefind
make
cp gst-typefind $GSTWORKSPACE/image/usr/bin
```

e. Build the application:

```
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ ./build.sh
```

f. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:

```
$ adb push image/usr/bin /usr/bin/
```

See Section 4.11.2 for how to use `gst` command.
5.10 OpenGL-ES

1. Download source code

As mentioned in Secton 4.12 the source code for testing OpenGL ES can be downloaded here.

https://www.thundercomm.com/app_en/product/1544580412842651#doc

The directory after decompression is as follows:

```
$ tree opengles_test
opengles_test
    ├── es11
    │   ├── Android.mk
    │   └── commondefs
    ├── commonrules
    │   ├── conform
    │   └── covgl.txt
    └── ctk
```

2. Build and transfer the application

a. Build the application:

```bash
$ cd opengles_test/es11
$ source /usr/local/oecore-x86_64/environment-setup-aarch64-oe-linux
$ export CONFORMES=`pwd`
$ make
```
b. Connect the board to the host PC via Type C and ensure that the ADB port can be used. Transfer the application:

```bash
$ adb push conform/conform/conform /bin/conform
```

See Section 4.12 for how to use `conform` command.