



# Application Note

## AN\_411

# FTx232H MPSSE I2C Master Example in C#

**Version 1.1**

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This application note shows an example of using the MPSSE feature of the FT232H, FT2232H and FT4232H devices to create a USB to I2C Master Device with a C# Visual Studio project.

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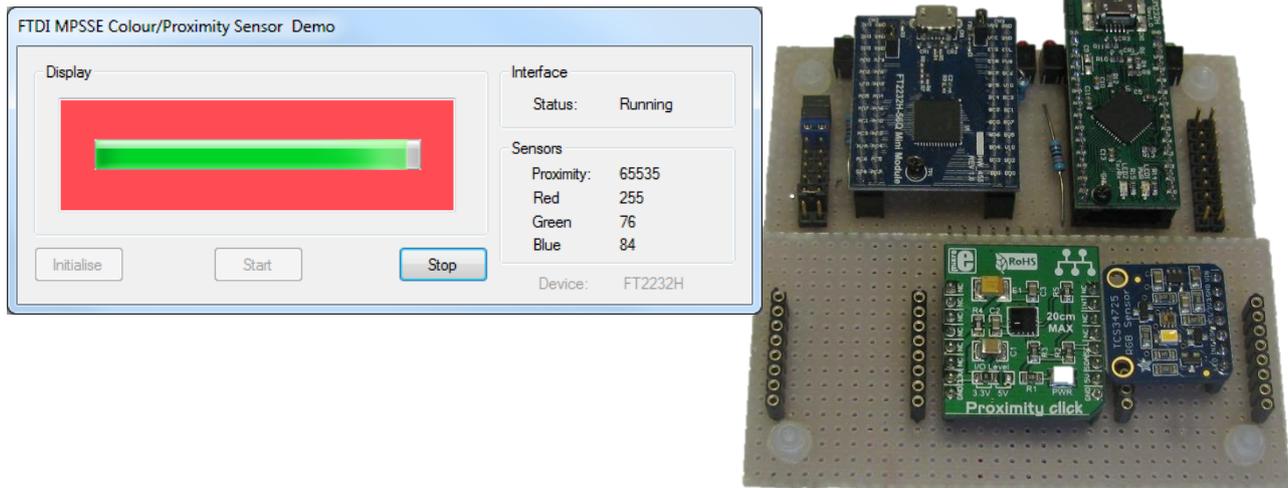
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## 1 Introduction

This application note shows an example of using the MPSSE feature of the [FT232H](#), [FT2232H](#) and [FT4232H](#) devices as an I<sup>2</sup>C Master with a C# project.

It uses a proximity sensor and an RGB colour sensor as I<sup>2</sup>C peripherals and to create a system which can detect the presence of an object in close proximity and can then determine its colour.



**Figure 1 - Sensor hardware and application**

The code itself is written in C# and uses the FTDI D2XX Drivers [NET wrapper](#). It provides a graphical user interface for displaying the sensor data, and contains functions to implement the I<sup>2</sup>C protocol and GPIO via MPSSE. These can all be customised in order to tailor the application for different sensors and different ways of presenting the measured data.

The main components, consisting of the proximity sensor, colour sensor and FTDI FT232H / FT2232H / FT4232H are all available on development modules allowing the hardware to be prototyped very quickly and easily.

This application note demonstrates the following principles:

- Using the FTDI [D2XX Drivers](#) with C# applications
- Using the FT232H / FT2232H / FT4232H MPSSE to implement I<sup>2</sup>C Master protocol
- Displaying the gathered data in a graphical user interface
- Using the AD3:7 pins as GPIO (useful for [C232HM cable](#) applications where only ADBUS is accessible)

A big advantage of using MPSSE is that there is no firmware to develop, program and maintain. The FT232H and FTx232H devices are hardware bridges supplied ready to use, with the MPSSE controlled entirely by commands from the PC. This means that any changes in functionality of the end product (such as to add features, read different registers in the I<sup>2</sup>C peripherals or add support for different I<sup>2</sup>C peripherals) can all be implemented with a new release of the application program running on the PC.

## 2 Hardware

### 2.1 Comparison of FT232H, FT2232H, FT4232H MPSSE Features

The software provided with this application note can be used on the FT232H, FT2232H and FT4232H. These devices all have very similar MPSSE feature sets. The following table highlights some features and differences relevant to the I<sup>2</sup>C implementation. Further details of the MPSSE commands and features can be found in [AN\\_108](#) and [AN\\_135](#) and in the [datasheet](#) of the selected FTx232H device.

Feature	FT232H	FT2232H	FT4232H	Notes
<b>Total Ports on device</b>	1	2	4	
<b>MPSSE capable ports</b>	1	2	2	
<b>Open Drain capability</b>	Y	N	N	
<b>Three Phase Clocking</b>	Y	Y	Y	Allows data to be stable on both clock edges as required for I <sup>2</sup> C (see section 6.2.1)
<b>GPIO per I<sup>2</sup>C port (ADBUS/ACBUS)</b>	5/8	5/8	5/0	No ACBUS on FT4232H
<b>Default start up mode</b>	EE	EE	UART	EE indicates that the device starts in the mode selected in EEPROM e.g. UART, FIFO

**Table 1 - Features by device type**

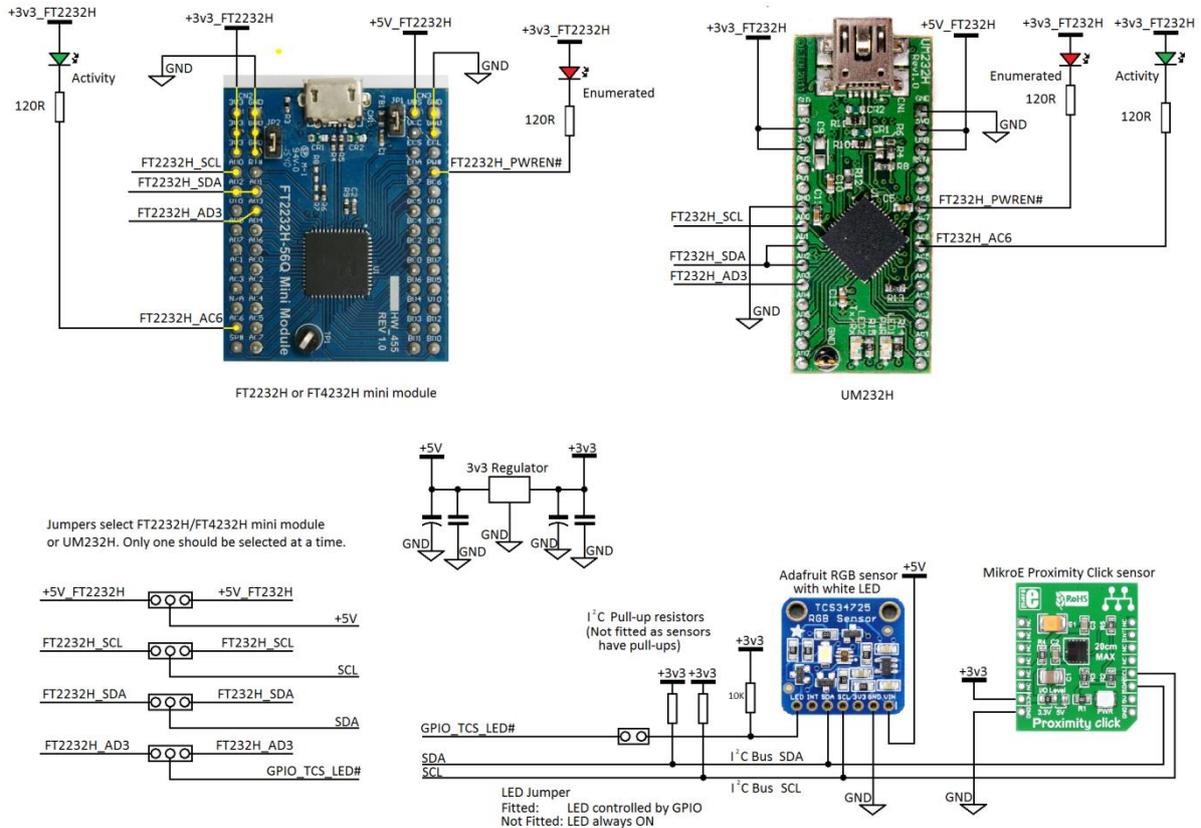
The device selection depends on the requirements of the application. If a single channel is required, the FT232H's open drain feature and the availability of up to 13 GPIO make it a good choice. If the application requires an additional SPI interface, another I<sup>2</sup>C bus, or a UART port, then the FT2232H allows this to be achieved with only one USB port. The FT4232H extends this by offering four ports including up to two MPSSE interfaces.

In terms of throughput, the MPSSE on all three devices will give very similar performance. One thing to consider however that is the USB protocol shares bandwidth across all devices connected. This applies to all devices connected to the same USB host controller (most PCs have just one host controller an internal hub), and so even devices on another USB port of the PC can take bandwidth on the bus. The Bulk USB transfer mode used by the FTx232H devices is optimized for high throughput and error checking but does not offer guaranteed latencies. If the application is sensitive to latencies then it should be tested under the worst case conditions including OS latencies and USB bandwidth.

The MPSSE is always a Master and cannot implement an I<sup>2</sup>C slave interface. If USB to I<sup>2</sup>C slave conversion is needed (e.g. to connect an MCU which has an I<sup>2</sup>C Master to a PC over USB) then the FTDI [FT200XD/FT201X](#) devices would be suitable. In addition, the MPSSE does not support multi-master I<sup>2</sup>C operation.

## 2.2 Hardware Description

This section describes the hardware used for the example. The following diagram shows the schematic of the hardware unit:



**Figure 2 – Schematics**

### 2.2.1 FTDI Module

The demo allows the use of any of the three devices FT232H, FT2232H or FT4232H via the following modules:

- FT232H            [UM232H](#)
- FT2232H        [FT2232H-56 Mini Module](#) (or [FT2232H Mini Module](#))
- FT4232H        [FT4232H-56 Mini Module](#) (or [FT4232H Mini Module](#))

These modules are designed by FTDI to allow easy evaluation of the devices and include all components needed for the device including the USB connector and external EEPROM.

A standard 28-pin wide IC socket is provided for a UM232H. Note that connections must be made to the VIO and 5V0 power pins before the module will be recognised by a PC.

A pair of dual-row header sockets is provided for the FT2232H or FT4232H mini modules. For the FT2232H and FT4232H, the 56Q version of the module was used as this has on-board jumpers to connect VCC and VCCIO. The original module with 64-pin IC can be used in the same way provided the external connections are made to power up the module (see the module [datasheet](#) for details)

## 2.2.2 Power

A small regulator provides a stable 3v3 supply to the sensor modules derived from the USB 5V supply. Whilst all of the FTDI modules used in this application note have 3v3 out connections which can provide a small amount of current for external circuitry, an external LDO allows greater current capability which may be required depending on the sensors used.

## 2.2.3 Proximity Sensor (VCNL4010)

The Proximity Click module from MikroElektronika was used which contains the VCNL4010 IC and supporting components in an easy to use dual-in-line format. This sensor has a built-in IR emitter and PIN photodiode which allow it to determine the proximity of an object within a 20cm range. It has built-in processing which turns the amount of reflected light into a single 16-bit register value which represents the distance of the object from the sensor. Additional registers allow configuration of the IR emitter current, averaging settings and other parameters. The sensor has I<sup>2</sup>C address 0x13 (in 7-bit address notation). More information can be found at the product page:

[MikroElektronika Proximity click](#)

## 2.2.4 Colour Sensor (TCS34725)

The colour sensor selected was the TCS34725 RGB colour sensor with IR filter and white LED, which is available on a board from Adafruit. Like the proximity sensor, this board allows easy connection to the small SMD package sensor and has all of the supporting circuitry on-board. An on-board white LED illuminates the object and the sensor measures the reflected light through an IR filter which blocks IR components of the light to produce a more accurate reading. The white LED is controlled via a MOSFET which is connected to a GPIO line on the MPSSE so that the bright light can be turned off until an object is in close proximity. The sensor requires the object to be very close (in practice, the demo requires within one or two centimetres) to get accurate readings. A real colour measuring application would use the sensor under much more controlled conditions in order to get a more accurate reading, including the ambient lighting conditions and calibration. The sensor has I<sup>2</sup>C address 0x29 (in 7-bit address notation). More information can be found at the product page:

[Adafruit Colour Sensor](#)

## 2.2.5 GPIO

A GPIO line is used to control the white LED on the colour sensor module. A second line is used as an activity indicator and turns on when the PC application configures the MPSSE. It toggles on each reading to indicate that the demo is actively polling the sensors. Both GPIO lines use the ADBUS as this is available on all three FTDI devices including the FT4232H and on cables such as C232HM which allow connection to ADBUS only.

The ACBUS lines (not available on FT4232H or C232HM) are also available for GPIO purposes, where AC7:0 provide up to 8 additional I/Os. It is therefore possible to have up to 13 GPIO lines in addition to the I<sup>2</sup>C lines.

## 2.2.6 I<sup>2</sup>C

For the I<sup>2</sup>C itself, the lines AD2:0 are used. AD0 is the MPSSE's clock out pin and is therefore connected to the SCL line of the I<sup>2</sup>C bus. The MPSSE always generates the clock and as such is always the I<sup>2</sup>C Master. It is not designed for multi-master operation.

For data, the MPSSE has two separate pins; ADBUS 1 is the Data Out pin and ADBus2 is the Data In pin. Since the I<sup>2</sup>C bus uses a single bi-directional data line, the data in and data out lines are connected together to allow data to be both written out and read in.

For the FT232H, the I<sup>2</sup>C libraries in the software application set the pin states to be output for AD0 (clock) and AD1 (data out) and to be an input for AD2 (data in). The FT232H has a drive-only-zero feature which allows any of AD7:0 and AC7:0 to be selected as open-drain.

For the FT2232H and FT4232H, the application includes additional GPIO writes to ADBUS which tristate the AD1 Data Out pin when the line is not being driven, to simulate an open-drain pin.

### 2.2.7 EEPROM Settings

It is recommended that the FTx232H device has a configuration EEPROM fitted. This allows several settings to be optimised for the application. FTDI modules such as [UM232H](#), [C232HM](#), and [FTx232H Mini Modules](#) have configuration EEPROMs fitted on-board. FTDI's free [FT\\_PROG](#) software can be used to change EEPROM settings over USB if required.

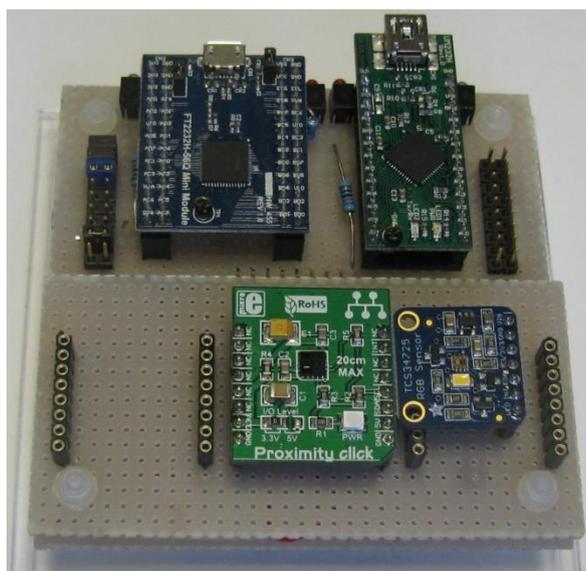
- For the FT232H and FT2232H, it is recommended to set the port to FIFO mode. Provided that the RD# and SI/WU# lines on ACBUS are de-asserted (pulled high) by the hardware then the 8 ADBUS lines will begin as tristate when the device starts up. The device can enter MPSSE mode from either UART or FIFO but if set for UART mode, the ADBUS lines would drive out their idle UART states until the I2C\_ConfigureMPSSE function is called.

Note that even in FIFO mode, some ACBUS lines are driven (e.g. TxE#) and so this should be considered when assigning ACBUS lines for GPIO purposes. Asynchronous FIFO pin assignments can be found in the device datasheet.

- It is suggested that the VCP option be turned off in the EEPROM so that the port is not accidentally opened by the user in other COM port applications such as terminals. This ensures the port is available to be found by the sensor application.
- With an EEPROM, the device description string and serial number can also be changed to allow easy identification of the device. For example, the code could open by the description "SensorDemo" and the EEPROM could be programmed with this description.

## 2.3 Prototype Hardware

The prototype hardware is shown in the figure below –



**Figure 3 - Prototype Hardware**

## 3 Software

The software is written in Visual Studio 2013 using C#. Later versions of Visual Studio should also upgrade the project when opening.

The code for this application note is arranged in four particular areas. These are discussed further in the following sections.

- **Application code**

The main application itself, which handles the user interface and calls the functions which configure and read the sensors.

- **Sensor Interface Functions**

These functions utilise the generic I<sup>2</sup>C functions from the layer below to build up the I<sup>2</sup>C transactions needed to talk to the sensors.

- **I<sup>2</sup>C Functions**

These functions form a generic I<sup>2</sup>C library. This allows them to be used for a variety of different applications. Their main purpose is to convert the I<sup>2</sup>C calls from the layers above into a series of MPSSE commands which are in turn sent using the calls to the D2xx driver.

- **D2xx Driver and C# Wrapper**

When programming in C#, a wrapper is needed to allow the application to call the D2xx functions in the FTDI driver. FTDI also have a VB wrapper and a similar application for I<sup>2</sup>C is presented in [AN\\_355](#). C++ applications can call the functions directly as shown in [AN\\_255](#) (FT232H only) and [AN\\_113](#).

### 3.1 Sample code package

This application note is provided with the [source code](#) for the sensor application. It is important to set the #define at the top of the code to configure the code for the device type being used. In particular, this defines whether the code uses open-drain capabilities (FT232H) or whether it simulates this with GPIO writes (FT2232H/FT4232H) and whether it uses the upper byte of GPIO (FT232H and FT2232H only).

```
///#define FT232H
#define FT2232H
///#define FT4232H
```

The application when running displays the device type for which it was compiled at the bottom-right of the window.

If the application is to be universal, an auto-detect can be added to select the device based on device properties (e.g. device type and PID)

**Note:** This application is intended to demonstrate the MPSSE programming required to implement an I<sup>2</sup>C Master interface. Some error checking and handling have been implemented where possible without affecting readability of the MPSSE code. However, the code is not intended to reflect all best practices for Windows application programming such as error handling and GUI implementation and C# programming techniques.

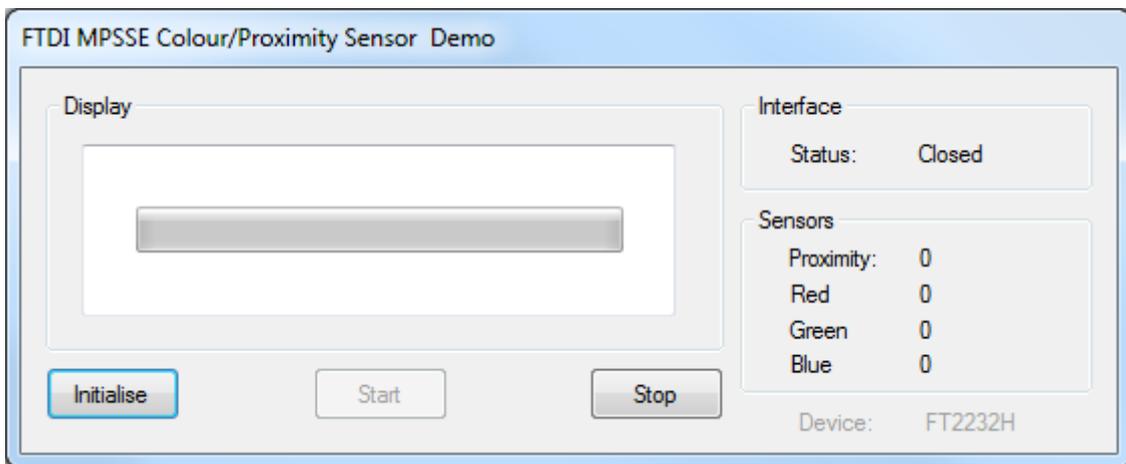
Both the main application and the library functions are intended to be used as the basis for further development and may require customisation to suit the particular application and I<sup>2</sup>C peripheral. The functions are not intended as a ready-made library to suit all applications without modification. This flexibility to customise the code at lower levels allows fine-tuning of the I<sup>2</sup>C routines to suit the intended application.

## 4 Software - Application Code

This section briefly outlines the demo application. The application consists of the main window and has handlers for each of the buttons.

The user interface has the following features:

- Status indication showing port Open, Ready, Closed, Running etc.
- Readout of the proximity value (0-65535)
- Readout of the Red, Green and Blue values (0-255)
- Horizontal Bar showing the relative proximity of an object to the sensor
- Coloured background behind the bar changes to indicate the colour of the object when in close proximity



**Figure 4 - Application window**

The handlers are described below for each button and event.

### 4.1 Form1\_Load

On loading of the form, this handler sets the properties of the buttons and radio buttons to their initial states.

### 4.2 Button1\_Click (Initialise button)

When the user clicks the Initialise button, D2xx calls are used to determine how many FTDI devices are connected.

The application then does an open by index to open the first port of the FTDI device connected. This will be the single port of the FT232H and will be port A of the FT2232H and FT4232H.

The commented line above the OpenByIndex call shows an example of how to open a device by its description instead and would be a better solution for cases where multiple FTDI devices may be used on the computer. Or a drop-down could be added to the GUI to allow the user to select the device. Note that on multi-port devices, when opening by serial number or description, an A/B/C/D is appended to the serial number or description to identify the corresponding port on the device.

Then, the I2C\_ConfigureMPSSE function is called to set the device up for MPSSE operation.

On completion, the status LED on ACbus6 is illuminated by calling the I2C\_SetGPIOValuesHigh function.

This is only implemented for FT232H and FT2232H as the FT4232H does not have a high byte.

The functions ProximitySensorConfig and ColourSensorConfig are then called to set up the sensors over I<sup>2</sup>C.

### 4.3 Button2\_Click (Start button)

When the user clicks the start button, the application enters a loop where it takes a reading from the proximity sensor. The call will return when the sensor has a reading available. This is then converted to a string which is displayed in the main application window. The reading will sit at a value of up to 2500 under ambient conditions with no item in close proximity.

The code then carries out some very basic processing on the data whereby if the reading is above a typical idle level (i.e. if an object does appear to be within range) a Log10 is applied. This was found in practice to present a more linear relationship between object distance and bar graph value. The Log10 isn't applied below 2500 as it amplifies small changes in background level when no object is nearby and makes the bar appear jittery.

If the proximity is greater than 10,000 (which correlates to the object being within a couple of cm of the sensor) it is now considered that the colour sensor becomes usable.

- A GPIO write is used to turn on the white illumination LED controlled by ADbus3.
- The background colour of the application changes from a standard Windows 'control light' dialog box background colour to instead represent the RGB data from the colour sensor.

The ColourSensorReading function is called to retrieve the RGB values from the sensor and these are used to update the colour of the background in the application window and to display the RGB values in the window.

On the FT232H and FT2232H, the GPIO line AC6 is toggled low and high again to blink the LED to indicate activity.

The loop continues whilst the variable 'Running' is true.

### 4.4 Button3\_Click (Stop button)

The Stop button will set the variable 'Running' to false so that the sensor reading stops.

It calls `myFtdiDevice.Close();` to close the port of the FTDI device and then closes the application itself.

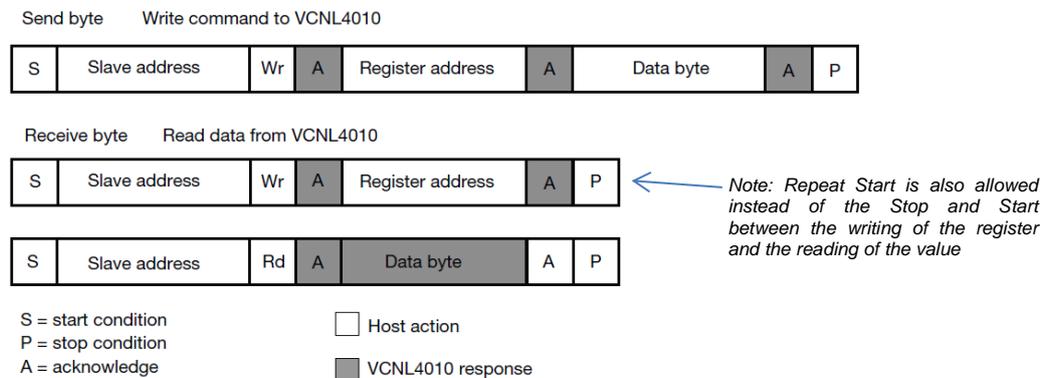
## 5 Software - Sensor Interface Functions

The sensor interface functions handle the configuration and reading of the sensors. This section summarises each function.

As demonstrated by the proximity and colour examples here, most I<sup>2</sup>C sensors will use the same basic sequence of I<sup>2</sup>C operations to write and read their registers and so the code can be adjusted easily to work with many other sensors. It is however important to consult the datasheet of the chosen I<sup>2</sup>C peripheral to confirm the protocol for writes and reads and for details of which registers it has available and what configuration is needed.

### 5.1 Proximity Sensor

The proximity sensor uses the I<sup>2</sup>C transactions shown below for writing and reading.



**Figure 5 - I<sup>2</sup>C transfers for Proximity sensor**

#### 5.1.1 Configuration (ProximitySensorConfig())

This sample code carries out a basic configuration of the proximity sensor. The same technique can be used to configure the device to use all of its features. Details of the full feature set and registers can be found in the [datasheet](#).

An example of writing the current register is shown below. This also serves as a general example of writing registers in an I<sup>2</sup>C device using the library functions provided with this application note.

```
// VCNL_WrSingle(REGISTER_PROX_CURRENT, 20);
AppStatus = I2C_SetStart(); // I2C START
    if (AppStatus != 0) return 1;
AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(VCNL40x0_ADDRESS), false); // SEND ADDR (WR)
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SendByteAndCheckACK((byte)(REGISTER_PROX_CURRENT)); // SEND REGID
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SendByteAndCheckACK((byte)(20)); // SEND VALUE
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SetStop(); // I2C STOP
    if (AppStatus != 0) return 1;
```

An I<sup>2</sup>C start condition is first sent to the bus.

- If the writing of the commands to create the start condition failed (if AppStatus != 0) then this function returns with an error code 1.

Then, the device address is written to the I<sup>2</sup>C bus. The call includes the 7 bit address of the desired sensor on the bus and Boolean value false to indicate that this is the beginning of a write transaction.

- If the sending of the MPSSE commands failed, and so AppStatus != 0, then this function returns with an error code 1.
- If the call succeeded but the sensor didn't acknowledge the byte, a stop condition is sent and the function returns with error code 1.

Another write transaction now sends the register index to which the value will be written. The same error checking is used to ensure that the command succeeded and that the sensor acknowledges the byte.

A third write transaction now sends the value to be written to the register specified above and performs the same error checking to ensure the sensor actually took the byte.

Finally, an I<sup>2</sup>C Stop puts the stop condition on the bus and frees up the bus for the next transaction.

### 5.1.2 Reading (ProximitySensorReading())

When reading the proximity sensor, the first step is to check the Config register in the sensor to determine if a valid reading is ready. In this application, it was decided to poll the sensor in a while loop until a reading was available.

As shown in

Figure 5 the read transaction begins with an I<sup>2</sup>C Start followed by an I<sup>2</sup>C write of the sensor's address with the write bit set. The following byte written then specifies which register in the sensor is to be read (REGISTER\_COMMAND in this case).

A repeat start (via I2C\_SetStart) is then sent which begins the transaction to read the data from the previously specified register in the sensor, without giving up control of the bus.

The sensor's I<sup>2</sup>C address is then sent again but with the read bit set, to indicate that this is a read transaction. As with any write, it is recommended to check both the success of the call and that the sensors acknowledged the address phase before proceeding.

A call to I2C\_ReadByte then clocks in a byte from the sensor which is the value from the register addressed above. The parameter (false) causes the I<sup>2</sup>C library to clock out a NAK in response to the byte read, which tells the sensor that this is the last byte to read.

Finally, an I2C\_SetStop call finished the transaction and frees up the I<sup>2</sup>C bus.

```
do
{
    AppStatus = I2C_SetStart(); // I2C START
    if (AppStatus != 0) return 1;
    AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(VCNL40x0_ADDRESS), false); // SEND ADDR (WR)
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
    AppStatus = I2C_SendByteAndCheckACK((byte)(REGISTER_COMMAND)); // REG ADDR
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
    AppStatus = I2C_SetStart(); // RPT START
    if (AppStatus != 0) return 1;
    AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(VCNL40x0_ADDRESS), true); // SEND ADDR (RD)
}
```

```
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_ReadByte(false); // READ BYTE
    if (AppStatus != 0) return 1;
    Command = InputBuffer2[0];
AppStatus = I2C_SetStop(); // I2C STOP
    if (AppStatus != 0) return 1;
} while ((Command & (COMMAND_MASK_PROX_DATA_READY)) == 0);
```

Once the PROX\_DATA\_READY bit is found to be set, the function can proceed to carry out a similar read transaction to obtain the proximity values from the results registers. The main difference is that since this is a 16-bit value, I2C\_ReadByte is called twice in succession. The first call sends an ACK to the sensor (true) to tell it that more bytes will be read and the second call responds with a NAK telling the sensor that no more bytes are being read.

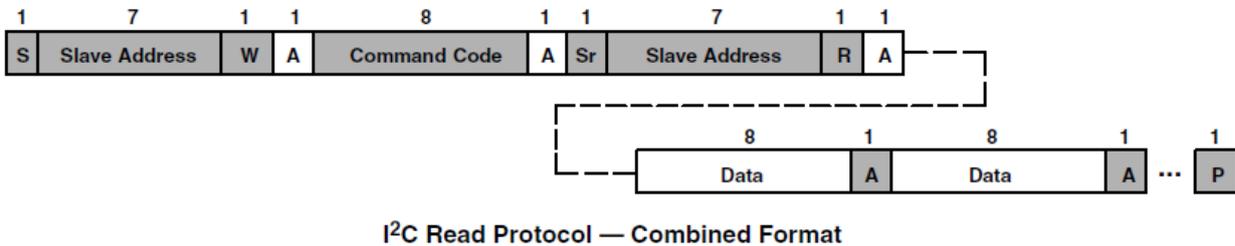
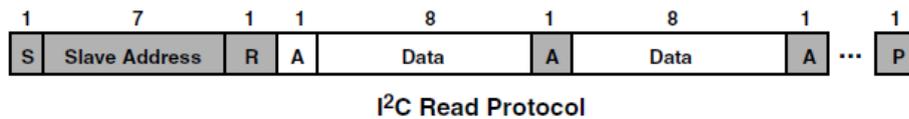
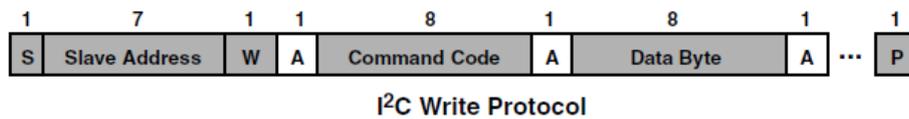
```
AppStatus = I2C_SetStart();
    if (AppStatus != 0) return 1;
AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(VCNL40x0_ADDRESS), false);
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SendByteAndCheckACK((byte)(REGISTER_PROX_VALUE));
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SetStart();
    if (AppStatus != 0) return 1;
AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(VCNL40x0_ADDRESS), true);
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_ReadByte(true);
    if (AppStatus != 0) return 1;
ProxDData[0] = InputBuffer2[0];
AppStatus = I2C_ReadByte(false);
    if (AppStatus != 0) return 1;
ProxDData[1] = InputBuffer2[0];
AppStatus = I2C_SetStop();
    if (AppStatus != 0) return 1;
ProxiValue = (UInt16)((ProxDData[0] << 8) | ProxDData[1]);
```

Note that the calls highlighted above could be replaced with a combined function which sends the address and reads the two bytes (see I2C\_Read2BytesWithAddr). Likewise, new I<sup>2</sup>C functions could be created to customize and optimize the communication even further (e.g. to include the I<sup>2</sup>C start, address, reading of n bytes and then I<sup>2</sup>C stop).

## 5.2 Colour Sensor

This section details the configuration and reading of the colour sensor. The I<sup>2</sup>C transfers are shown below:

- A Acknowledge (0)
- N Not Acknowledged (1)
- P Stop Condition
- R Read (1)
- S Start Condition
- Sr Repeated Start Condition
- W Write (0)
- ... Continuation of protocol
- Master-to-Slave
- Slave-to-Master



**Figure 6 - I<sup>2</sup>C Transfers for Colour sensor**

### 5.2.1 Configuration (ColourSensorConfig())

The configuration of the colour sensor uses the same register writing technique as the proximity sensor. This code performs a relatively minimal configuration but the same I<sup>2</sup>C writes to the various registers in the device can be used to configure all of its features.

### 5.2.2 Reading (ColourSensorReading())

The reading of the result is again similar to the reading of the Proximity sensor. The main difference is that the colour sensor has eight bytes in the result (16-bit clear, red, green and blue).

Many I<sup>2</sup>C devices support reading of multiple registers in a single transaction. The Master will perform a read operation to the first register (lowest index) in a linear block of registers within the sensor. It will read the value and respond with ACK. The sensor will increment its internal pointer to point to the next register. Another read will therefore automatically take the next register value without sending the register address again. This technique can be used to read all 8 registers containing colour values from the TCS34725 in a single transaction.

```
AppStatus = I2C_SetStart();
    if (AppStatus != 0) return 1;
AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(COLOR_ADDRESS), false);
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SendByteAndCheckACK((byte)(0xB4)); // ID of the first register
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_SetStart();
    if (AppStatus != 0) return 1;
AppStatus = I2C_SendDeviceAddrAndCheckACK((byte)(COLOR_ADDRESS), true);
    if (AppStatus != 0) return 1;
    if (I2C_Ack != true) { I2C_SetStop(); return 1; }
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
ClearColorSensorL = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
ClearColorSensorH = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
RedColorSensorL = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
RedColorSensorH = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
GreenColorSensorL = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
GreenColorSensorH = InputBuffer2[0]; // Read byte and ACK
AppStatus = I2C_ReadByte(true); // Read byte and ACK
    if (AppStatus != 0) return 1;
BlueColorSensorL = InputBuffer2[0]; // Read byte and NAK
AppStatus = I2C_ReadByte(false); // Read byte and NAK
    if (AppStatus != 0) return 1;
BlueColorSensorH = InputBuffer2[0];
AppStatus = I2C_SetStop();
    if (AppStatus != 0) return 1;

ClearColorSensor = (ushort)((ClearColorSensorH * 256) | ClearColorSensorL);
RedColorSensor = (ushort)((RedColorSensorH * 256) | RedColorSensorL);
GreenColorSensor = (ushort)((GreenColorSensorH * 256) | GreenColorSensorL);
BlueColorSensor = (ushort)((BlueColorSensorH * 256) | BlueColorSensorL);
```

One point to note is that the value from each read is stored in the corresponding variable (e.g. RedColorSensorL) since InputBuffer2[0] will be overwritten on the next call to I2C\_ReadByte. These calls could be replaced with a combined address and read call following a similar principle to the function in the I2C layer I2C\_Read2BytesWithAddr.

## 6 Software - I<sup>2</sup>C Functions

The I<sup>2</sup>C functions provide the main application and sensor interface functions with a set of commands for the familiar I<sup>2</sup>C operations and create the required buffer of MPSSE commands which are sent to the chip in order to implement them on the I<sup>2</sup>C lines. By doing so, they avoid the layers above from needing to know about the specifics of the MPSSE.

The following functions are provided within the example application:

- I2C\_ConfigureMpsse
- I2C\_SendByteAndCheckACK
- I2C\_SendDeviceAddrAndCheckACK
- I2C\_ReadByte
- I2C\_Read2BytesWithAddr
- I2C\_SetStart
- I2C\_SetStop
- I2C\_SetLineStatesIdle
- I2C\_GetGPIOValuesLow
- I2C\_SetGPIOValuesHigh
- I2C\_GetGPIOValuesHigh

Note that these functions are intended as a starting point for development of an application rather than a fixed library. They may need to be changed or additional ones created to suit the specific application and intended I<sup>2</sup>C Slave devices.

These functions use return code 0 to indicate success and a return code of 1 if an operation inside the function call failed. This could be extended to provide additional return codes if it is required to inform the calling function of the reason for failure.

This section uses the terminology I<sup>2</sup>C transaction to represent the time between I<sup>2</sup>C Start and I<sup>2</sup>C Stop i.e. the bus is busy.

Idle-within-transaction	SCL held low and SDA released/floating
Idle-outwith-transaction	SCL and SDA lines are both released/floating

### 6.1 MPSSE Commands

The application uses a combination of D2xx calls and MPSSE commands to configure the device and then to implement I<sup>2</sup>C communications.

- The D2xx calls are commands direct to the chip hardware and/or driver. Examples include FT\_SetFlowControl, FT\_SetBitMode, FT\_Read and FT\_Write. In this application, they are made via the C# wrapper and so have the syntax myFtdiDevice.SetBitMode etc. (assuming the device was opened as myFtdiDevice)
- Please refer to the [D2xx Programmers Guide](#). See Appendix A - References for the link to this document and also to the intellisense documentation provided by the xml file when including the [FTD2XX NET wrapper](#) in the project.
- The MPSSE commands are built up into a buffer/array by the application and sent to the chip via a MyFtdiDevice.Write(...). The device must be put into MPSSE mode beforehand. The MPSSE engine in the device will then parse and execute these commands in the same sequence. Sending a buffer containing a series of GPIO commands and data clocking commands allows customized data transfers to be achieved and makes the MPSSE very flexible. Application note [AN\\_108](#) details the command set of the MPSSE and [AN\\_135](#) contains further information on the MPSSE.

## 6.2 Function Descriptions

This section describes the provided I<sup>2</sup>C functions. The text below each table refers to the FT232H and then differences for the FT2232H/FT4232H are highlighted in blue text.

### 6.2.1 I2C\_ConfigureMpsse

Configures the MPSSE in the device for operation as an I2C Master

<code>public byte I2C_ConfigureMpsse()</code>		
IN	Global	Instance of FTDI class for the device ( <code>myFtdiDevice</code> in this code)
IN	Global	ClockDivisor value
IN	Global	<code>GPIO_Low_Dir</code> - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	<code>GPIO_Low_Dat</code> - data values to write to AD7:3
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) before proceeding to make any further calls to this I2C library.

This function uses a combination of device API calls (e.g. `myFtdiDevice.SetLatency`) and MPSSE commands sent via `myFtdiDevice.Write` (e.g. setting MPSSE clock divider).

It requires that the device channel is already open. It then uses the `SetBitMode` command to enter MPSSE mode. The flow control is set to `RTS_CTS` mode to ensure that the driver uses flow control.

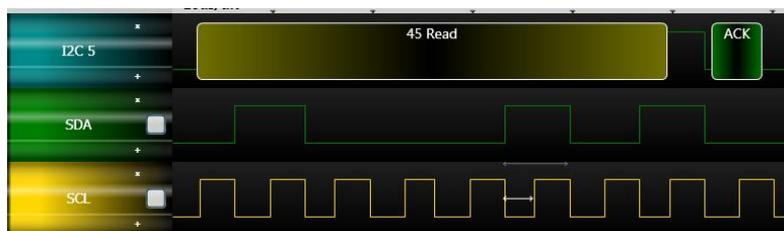
The latency timer is left at 16ms as the I<sup>2</sup>C functions use the MPSSE's send immediate command to get bytes back to the PC quickly when required. This is preferable as setting low latency timer values increases the USB traffic (since it sends a packet back at the interval specified even if no data is being transferred) whereas Send Immediate will only do so when required.

After purging the read buffer to ensure it is empty, the function checks that the device is correctly in MPSSE mode by sending a bad command. This is an invalid command `0xAA` which is not part of the MPSSE command set. The MPSSE should respond with two bytes, `0xFA` followed by the invalid command `0xAA` which is received. Reading these back confirms that the device is correctly in MPSSE mode. This is then repeated with `0xAB`.

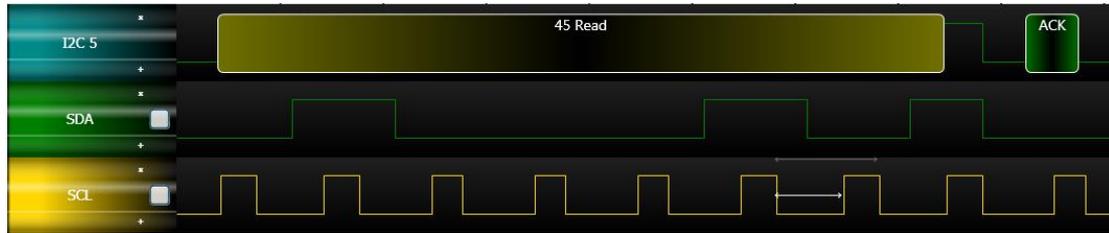
### 6.2.2 3-phase clock

The 3-phase clock mode is enabled which gives three clock phases. This is necessary as the I<sup>2</sup>C protocol requires data to be valid on both clock edges. The comparison of two vs three phase clocking is shown below.

- There is now both a rising and a falling edge whilst the data is stable, as required by the I<sup>2</sup>C protocol.
- The three-phase clocking extends each clock cycle by a half-cycle and so each cycle will now be 50% longer. Therefore the frequency (for a given clock divider value) in three phase mode is 2/3<sup>rd</sup> of the value than the same waveform in two-phase mode.
- The clock duty cycle is now 33.3% rather than 50%.



Two-phase clocking: Clock Period: 6.5us, Clock Frequency: 153.846KHz, Duty Cycle 50%



Three-phase clocking: Clock Period: 10us, Clock Frequency: 100KHz, Duty Cycle 33.3%

**Figure 7 - Three-Phase clocking**

### 6.2.3 Clock rate

The clock divider is set to give the required I<sup>2</sup>C clock rate, which is created by dividing down the 60MHz clock which is supplied internally to the MPSSE. The divider calculation below is for a 400KHz I<sup>2</sup>C rate. 600KHz is used as the basis due to the actual rate being 1/3<sup>rd</sup> lower in three-phase clock mode.

MPSSE Clock Source = 60MHz

$$\text{Clock Rate} = \frac{60\text{MHz}}{(1 + \text{CLOCKDIVIDER}) * 2}$$

$$600,000 = \frac{60,000,000}{(1 + \text{CLOCKDIVIDER}) * 2}$$

$$600,000 * (1 + \text{CLOCKDIVIDER}) * 2 = 60,000,000$$

$$1 + \text{CLOCKDIVIDER} = 50$$

$$\text{CLOCKDIVIDER} = 49 \quad (0x31)$$

An optimised equation for three phase clock mode is:

$$\text{Clock Divisor} = \frac{30}{(\text{Clock Rate} * 1.5)} - 1$$

*Assuming Clock Rate in MHz, three-phase clocking enabled, and MPSSE divide-by-5 option disabled*

**Note:** The Clock Divisor is always an integer and so some rates may need to be rounded to the nearest available value.

### 6.2.4 Open Drain

The I2C\_SetLineStatesIdle function is then called to set the I<sup>2</sup>C lines to their idle states and will also apply the GPIO values to ADBUS required by the application (which can be set in global variables ADBusVal and ADBusDir before calling the I2C\_ConfigureMPSSE function. A call could also be added here to set the high byte GPIO if desired.

The FT232H has a drive-only-zero feature which can be enabled individually on any of the 16 ACBUS and ADBUS pins. This is effectively an open-drain mode for the selected pins and is again ideal for I<sup>2</sup>C where the lines are pulled down for logic 0 but released (pulled up by external resistors rather than driven high) for logic 1, thereby allowing many devices to share the same clock and data lines.

FT2232H/FT4232H: These devices don't have open drain capability and so a GPIO write is used to simulate open drain by setting the data value low and the direction to input.

The function returns a status value where 0 indicates success. It would be possible to extend this to return additional error codes in the event that the function failed to allow the calling code to identify the cause.

### 6.2.5 I2C\_SendByteAndCheckACK

Writes a byte to the I2C bus

<code>public byte I2C_SendByteAndCheckACK(byte DataByteToSend)</code>		
IN	Passed In	Data Byte to be sent
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Global	I2C_Ack is a boolean value (True if the I <sup>2</sup> C device ACKed the byte)
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) and then check if I2C_Ack is True to determine if the I <sup>2</sup> C peripheral ACKed the byte written.

This function will clock out one byte to the I<sup>2</sup>C bus, to write a value to the attached I<sup>2</sup>C peripheral. Before calling this function, the I<sup>2</sup>C device should be addressed via I2C\_SendDeviceAddrAndCheckACK.

The first command clocks out one byte MSB first, which is the data byte to be sent.

A GPIO command is then added to the buffer. This is to ensure that the SDA line is always released after the write regardless of the last data value. The value written combines the normal state of the I<sup>2</sup>C lines (AD2:0) when within a transaction (SCL low, SDA released) with the GPIO values of AD7:3. The GPIO lines are therefore also updated to the current values of their global variables. This command adds negligible delay but can be removed if the application does not require SDA to be at a particular state when idle within a transaction or can be changed so that SDA stays pulled low between transfers during a transaction.

The third command clocks in one bit which is the ACK bit from the peripheral.

Finally, a Send Result Back Immediately command (0x87) is added which will cause the value clocked in from the I<sup>2</sup>C peripheral (the ACK bit) to be sent back to the host PC as quickly as possible.

The buffer of commands is sent to the device by calling the Send\_Data function. The Receive\_Data function is used to read a single byte which has come back from the MPSSE and contains the ACK/NAK bit. The function checks this value and sets the I2C\_Ack global variable to reflect the state (True means the peripheral ACKed).

The function returns 0 if all calls for the writing of the commands and reading of the ACK bit succeeded. It returns 1 if any of these failed. The code could be extended to return a wider range of error codes if desired.

**FT2232H/FT4232H:** Note that if the FT2232H or FT4232H are selected, additional GPIO writes are added to the MPSSE buffer which make the ADBUS bit 1 (data out) an output initially so that the data byte can be clocked out. It then puts the line back to an input to allow the attached I<sup>2</sup>C device to drive the line for the ACK bit.

## 6.2.6 I2C\_SendDeviceAddrAndCheckACK

Sends an I2C address on the bus

<b>public byte</b> I2C_SendDeviceAddrAndCheckACK( <b>byte</b> Address, <b>bool</b> Read)		
IN	Passed In	Address - I2C address of the device to be communicated with
IN	Passed In	Read - Boolean value specifying read (true) or write (false)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
OUT	Global	I2C_Ack is a boolean value (True if the I2C device ACKed the address)
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) and then check if I2C_Ack is True to check if the I <sup>2</sup> C peripheral ACKed the address written.

This function is very similar to the I2C\_SendByteAndCheckACK call discussed above but is specifically intended for addressing the I<sup>2</sup>C device.

Instead of taking the byte to write as a parameter, this modified function takes two parameters; a 7-bit I<sup>2</sup>C address (in the lower 7 bits) and a separate Boolean value defining whether to address the device for reading or writing.

Note that documentation for I<sup>2</sup>C peripheral devices may quote the I<sup>2</sup>C address in either the 7-bit or 8-bit formats. E.g. some documentation and sample code may quote 7-bit address 0x40 whilst others may quote the write and read values as 0x80 and 0x81 respectively. This code is designed to accept the 7-bit value with the R/W bit specified separately.

It combines these into a single 8-bit value by shifting the 7-bit address one place left and OR'ing with the Read Boolean parameter, and sends this to the I<sup>2</sup>C bus. As with the I2C\_SendByteAndCheckACK call, this function returns the ACK/NAK status via the global variable I2C\_Ack.

FT2232H/FT4232H: Note that if the FT2232H or FT4232H are selected, additional GPIO writes are added to the MPSSE buffer which make the ADBUS bit 1 (data out) an output initially so that the address byte can be clocked out. It then puts the line back to an input to allow the attached I<sup>2</sup>C device to drive the line for the ACK bit.

## 6.2.7 I2C\_ReadByte

Reads a single byte from the I2C bus

<b>public byte</b> ReadByte( <b>bool</b> ACK)		
IN	Passed In	ACK - Boolean value, sends ACK if True, NAK if False
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Global	InputBuffer(0) has received byte
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) and then read the byte from InputBuffer(0). Read the byte before calling the next I <sup>2</sup> C function to avoid overwriting.

This function will clock in one byte from the I<sup>2</sup>C bus, to read the value from a register in the attached I<sup>2</sup>C peripheral. Before calling this function, the I<sup>2</sup>C device should be addressed and (if required) have the register selected which is to be read. See the code snippets in section 5 for examples.

The first command clocks in one byte MSB first. This is the data byte being read from the I<sup>2</sup>C peripheral. The second command clocks out one bit which forms the ACK bit. The SDA value clocked out for the ACK bit can be configured by the application when calling the function. True will result in an ACK (SDA pulled low) whereas False will result in a NAK (SDA left pulled high).

A GPIO command is then added to the buffer. This is to ensure that the SDA line is always released in between bytes regardless of the last data value. The value written combines the normal state of the I<sup>2</sup>C lines (AD2:0) when within a transaction (SCL low, SDA released) with the GPIO values of AD7:3. The GPIO lines are therefore also updated to the values of their global variables. This command adds negligible delay but can be removed if the application does not require SDA to be at a particular state when idle within a transaction or can be changed so that SDA stays pulled low between transfers during a transaction.

Finally, a Send Result Back Immediately command 0x87 is added which will cause the byte clocked in from the I<sup>2</sup>C peripheral to be sent back to the host PC immediately.

The buffer of commands are sent to the device by calling the Send\_Data function The Receive\_Data function is used to read the single byte which will be clocked in by the MPSSE from the I<sup>2</sup>C peripheral. The function returns 0 if all calls for the writing of the commands and reading of the data byte succeeded. It returns 1 if any of these failed. The code could be extended to return a wider range of error codes if desired.

FT232H/FT4232H: Note that if the FT232H or FT4232H are selected, additional GPIO writes are added to the MPSSE buffer which make the ADBUS bit 1 (data out) an input before the clock pulses are generated to clock in the data value, and then put it back to output before sending out the ACK bit. It is then returned to an input again after the ACK bit is sent.

### 6.2.8 I2C\_Read2BytesWithAddr

Addresses the device and reads 2 bytes

public byte I2C_Read2BytesWithAddr(byte Address)		
IN	Passed In	Address - I <sup>2</sup> C address of the device to be communicated with
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Global	I2C_Ack indicates if the address phase was ACKed
OUT	Global	InputBuffer[0] and [1] have received bytes
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) and then check that I2C_Ack is True. Then, read the bytes from InputBuffer[0] and InputBuffer[1]. Read the bytes before calling the next I <sup>2</sup> C function to avoid overwriting.

This function combines the commands from I2C\_SendDeviceAddrAndCheckACK and I2C\_ReadByte to form a single call which addresses the peripheral for reading, and reads two bytes. It ACKs the first byte read and NAKs the second.

Many I<sup>2</sup>C peripherals have 16-bit registers or a series of sequential 8-bit registers which can be read in a burst. The Master reads the first byte from the peripheral, sending an ACK in response. It then reads the second byte responding with a NACK. The NACK tells the peripheral that the Master does not wish to read further bytes in this transaction.

Whilst this could be accomplished with three separate calls (an address call and two read calls), combining the equivalent operations into a single sequence of MPSSE commands can improve speed as the commands all get sent on a single USB micro frame and the actual operations on the I<sup>2</sup>C bus will have no gaps between. The actual saving depends on the scheduling of the USB host controller and also whether the USB micro frame rate (125us) is significant compared to the I<sup>2</sup>C clock rate.

This function is not used in the case of this application but is provided as an example of the ways in which a series of operations can be combined. This can have some dependency on the I<sup>2</sup>C peripheral being used. Since this hybrid function will not return the ACK or the two bytes read until fully complete, it is not possible for the application to check the ACK state of the addressing *before* reading. The calling code can however check the ACK bit after completion of the call and therefore determine whether the two bytes read are valid or not. If the continuation to generating the read cycle is not allowable by the particular I<sup>2</sup>C peripheral, then this combined function may not be well suited.

The developer of an application may find other opportunities to group commands in a way that optimises the communication for their I<sup>2</sup>C peripherals. This could involve reading of more than two bytes in a burst for example.

### 6.2.9 I2C\_SetStart

Sends the I2C Start condition

<code>public byte I2C_SetStart()</code>		
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success)

This function will put the I<sup>2</sup>C Start condition onto the bus to begin an I<sup>2</sup>C transaction. The function can also be used as a repeat start which is used in transactions which read data from an I<sup>2</sup>C peripheral, in between writing to the device to select the register to be read and the actual reading operation.

The function builds a buffer of GPIO commands for the MPSSE, which it will work through in sequence. Each GPIO write is repeated six times to hold the associated pin state for a longer time. Both SCK and SDA are initially high (open drain pulled up). The SDA line is brought low by putting ADbus1 low. Then, the SCL line is also brought low (ADbus0) to complete the sequence. The line is then left in the idle-during-transaction state which is SDA released and SCL held low. This could be easily changed if required by the applications.

FT2232H/FT4232H: These devices simulate an open-drain by keeping the data value low and using the pin direction to release the line (pin set as input) or pull it low (pin set as output)

### 6.2.10 I2C\_SetStop

Sends the I2C Stop condition

<code>public byte I2C_SetStop()</code>		
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success)

This function will put the I<sup>2</sup>C Stop condition onto the bus, to end the I<sup>2</sup>C transaction on the bus.

The function builds a buffer of GPIO commands for the MPSSE which it will work through in sequence. Each GPIO write is repeated six times to hold the associated pin state for a longer time.

For the Stop condition, the SCL and SDA lines are pulled down initially. The SCL line is first brought high, followed by the SDA line. Both lines finish in the high (open drain) state.

FT2232H/FT4232H: These devices simulate an open-drain by keeping the data value low and using the pin direction to release the line (pin set as input) or pull it low (pin set as output)

### 6.2.11 I2C\_SetLineStatesIdle

Sets the I2C lines to Idle Outwith Transaction and write ADbus GPIO

<b>public byte</b> I2C_SetLineStatesIdle()		
IN	Global	GPIO_Low_Dir - direction to set for AD7:3 (1 = out, 0 = in)
IN	Global	GPIO_Low_Dat - data values to write to AD7:3
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success). Do not call in the middle of an I <sup>2</sup> C transaction (i.e. between Start and Stop). This function is only for setting GPIO when no transaction is in progress.

The global variables containing the data and direction for AD7:3 are combined with the idle-outwith-transaction I<sup>2</sup>C pin states for ADbus2:0 (SCL and SDA both released) and this value is written via the 0x80 GPIO low commands. This masking is required since an MPSSE GPIO write command always writes all 8 bits of the port.

Since the use of this function would result in the SCL line being released, it is only intended for use when an I<sup>2</sup>C transaction isn't in progress.

**Note:** The other I<sup>2</sup>C library calls for addressing, reading and writing will update the GPIO lines on ADbus as part of their operation and so if a GPIO line on ADBUS requires to be changed during a transition, the associated global variables GPIO\_Low\_Dir and GPIO\_Low\_Dat can be written before the next I<sup>2</sup>C operation.

### 6.2.12 I2C\_GetGPIOValuesLow

Gets the GPIO values of ADbus 7:3

<b>public byte</b> I2C_GetGPIOValuesLow()		
OUT	Global	InputBuffer(0) has GPIO values in bits 7:3
OUT	Return	byte value containing status code (0 indicates success)
Notes		Check that the function returns success. Then read the GPIO value from InputBuffer(0). The SetLineStatesIdle function must have been called at least once before in order to set the directions of the GPIO.

This function sends a GPIO low byte read command to the MPSSE along with a send-immediate command which causes the result to be returned immediately.

The resulting value is masked to zero the lower three bits, leaving the upper five bits reflecting the GPIO value. The value can be read in bits 7:3 of the resulting byte via InputBuffer(0) after the function has been called.

### 6.2.13 I2C\_SetGPIOValuesHigh (FT232H and FT2232H Only)

Sets the data and direction of ACbus bits 7 to 0

<b>public byte</b> I2C_SetGPIOValuesHigh(byte ACbusDir, byte ACbusVal)		
IN	Passed in	ACbusDir contains the directions for the pins (1 = output)
IN	Passed in	ACbusVal contains the values to write to the pins which are outputs
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that the function returns success.

This function sends the 0x82 Write GPIO High Byte command followed by the value and direction bytes. This allows control of bits 7 to 0 of the ACBUS port. The values in parameter ACbusVal will be applied to pins which are configured as an output in the ACbusDir parameter (1 = output). This function can be called any time after the MPSSE is initialised and does not affect the I<sup>2</sup>C lines.

[FT232H: Note that the MPSSE can control and read only bits 0-7 of the ACBUS port. On the FT232H, the additional bits 8 and 9 are configurable in the EEPROM for other functions such as PWREN etc.](#)

FT4232H: This function cannot be used as the FT4232H has only 8 bits per port and no upper byte.

### 6.2.14 I2C\_GetGPIOValuesHigh (FT232H and FT2232H Only)

Read the values of ACbus bits 7 to 0.

<code>public byte I2C_GetGPIOValuesHigh()</code>		
OUT	Global	<code>InputBuffer(0)</code> has GPIO values for this port
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that the function returns success.

This function sends the 0x83 Read GPIO High Byte command followed by a send-immediate opcode which causes the MPSSE to send the resulting byte back on the next available micro frame.

The return value should be checked to be 0 (success) and then the byte containing the pin values can be read via `InputBuffer(0)`.

It is recommended to call `I2C_SetGPIOValuesHigh` at least once after initialisation before using the `GetGPIOValuesHigh`. This ensures that the ACBUS pin directions are set as required for the application.

FT232H: Note that the MPSSE can control and read only bits 0-7 of the ACBUS port. On the FT232H, the additional bits 8 and 9 are configurable in the EEPROM for other functions such as PWREN etc.

FT4232H: This function cannot be used as the FT4232H has only 8 bits per port and no upper byte.

## 7 Software - D2xx Driver and C# Wrapper

Since effective use of the FT\_Write and FT\_Read D2xx calls involves some error checking and additional steps (such as checking the queue status before reading), the I<sup>2</sup>C library source provided here wraps these calls into functions Send\_Data and Receive\_Data. An additional call is used during initialisation to flush any data in the driver's buffer.

This application utilises the managed C# wrapper provided by FTDI and so the D2xx calls are made via the wrapper. The wrapper consists of a DLL for the wrapper itself [FTD2XX\\_NET.DLL](#) and an xml file [FT22XX\\_NET.XML](#) to provide intellisense help. The source code for the wrapper is also provided on the C# samples page. Further information on the wrapper and download details can be found at the page below:

<http://www.ftdichip.com/Support/SoftwareExamples/CodeExamples/CSharp.htm>

The sample code provided with this application note already includes a copy of these files.

### 7.1.1 Send\_Data

Sends the requested number of bytes to the FTDI device

<b>private byte</b> Send_Data( <b>uint</b> BytesToSend)		
IN	Global	Instance of FTDI device (in this example myFtdiDevice.)
IN	Passed In	BytesToSend - number of bytes to send
IN	Global	Data to send in SendBuffer(0) to SendBuffer(BytesToSend-1)
OUT	Return	Byte value containing status code (0 indicates success)
OUT	Global	BytesSent - number of bytes actually sent
Notes		Check that function returns 0 (success) which means that all bytes were sent. If return is non-zero, bytes actually sent can be found in BytesSent

This function uses the FT\_Write D2xx call (myFtdiDevice.Write) to send the data. The USB host in the PC will determine how and when the data is sent but from the application's point of view the data will be sent as quickly as possible. The call blocks until complete and so setting a timeout with FT\_SetTimeouts (e.g. 5 seconds as this is only a safety measure) is strongly recommended.

### 7.1.2 Receive\_Data

Reads the requested number of bytes from the driver

<b>private byte</b> Receive_Data( <b>uint</b> BytesToRead)		
IN	Global	Instance of FTDI device (in this example myFtdiDevice.)
IN	Passed In	BytesToRead - number of bytes to read
OUT	Return	byte value containing status code (0 indicates success)
OUT	Global	BytesRead - number of bytes actually read
OUT	Global	Data read in ReceiveBuffer(0) to ReceiveBuffer(BytesRead-1)
Notes		Check that function returns 0 (success) which means that requested number of bytes were read. If return is non-zero, bytes actually read can be found in BytesRead

This function reads the data from the driver buffer after using the D2xx FT\_GetQueueStatus (myFtdiDevice.GetRxBytesAvailable) to check how much data is available. When the MPSSE clocks in data or reads a byte from the GPIO of the chip, it will buffer the data on-chip. This data will be sent back to the PC when the buffer has enough data for a USB frame (510 bytes of data) or if the latency timer ticks over (16ms default), or if a Send Immediate command is executed by the MPSSE. This library uses the send immediate opcode after any operation involving clock in or GPIO read and so this will be the normal mechanism used in this case. The driver issues IN requests over USB to the device and the chip will put the data into the IN packet when one of the aforementioned conditions occurs. The driver will buffer up this data and make it available for the application to read.

The Queue Status allows the application to check how much is currently buffered in the driver. This is especially useful as the FT\_Read (myFtdiDevice.Read) is a blocking call and so it is best to read only data that is known to be available and so in theory a timeout should never occur. It is strongly recommended to set a read timeout (e.g. 5 seconds) via FT\_SetTimeouts as a safety measure however.

This function works by running a loop which checks the queue status and if >0 bytes available, it reads these and appends to a buffer/array within the function. This process continues until the expected number of bytes (as passed in) has been received, or until the loop has run for a certain number of cycles (acting as a software timeout).

### 7.1.3 FlushBuffer

Reads any bytes in the receive buffer of the driver to clear it out

<b>private byte</b> FlushBuffer()		
IN	Global	Instance of FTDI device (in this example myFtdiDevice.)
OUT	Return	Byte value containing status code (0 indicates success)
Notes		Check that function returns 0 (success) which means that all data was flushed successfully (or no data was there to be flushed)

This function is normally only used when initializing the device for I<sup>2</sup>C. It checks the Queue Status of the driver's receive buffer and reads any data in the buffer in order to clear the buffer.

### 7.1.4 Multiple Channels

Note that the functions Send\_Data, Receive\_Data and FlushBuffer are hard-coded to an FTDI device instance opened at the beginning of the program as the code assumes the use of only one MPSSE channel.

e.g. `ftStatus = myFtdiDevice.Write(MPSSEbuffer, NumBytesToSend, ref NumBytesSent);`

If the code requires multiple MPSSE channels (e.g. if implementing two I2C Masters on an FT232H device from the same application) then each channel would be opened with a different instance and this example code would either require a Send\_Data function per device or to pass in the device reference to Send\_Data.

Open: `ftStatus = myFtdiDeviceCHA.OpenByIndex(0);`  
`ftStatus = myFtdiDeviceCHB.OpenByIndex(1);`

Example of writing data to channel A:

`ftStatus = myFtdiDeviceCHA.Write(MPSSEbuffer, NumBytesToSend, ref NumBytesSent);`

## 8 Further Development

The sample applications provided with this application note, including the I<sup>2</sup>C functions, are intended as the basis for further development and customisation to suit the intended application. Additional error checking relevant to the sensors used and application should also be added.

Some possible areas for further development include:

### 8.1 Other Languages

This application note uses the general MPSSE command set and so can be ported to any platform which supports D2xx drivers for the FTx232H. The MPSSE commands would remain the same but the method of sending and receiving data (i.e. equivalent syntax for FT\_Write and FT\_Read) would require to be ported to the equivalent calls on the new platform. The Graphical interface would also require porting to the new platform/language.

FTDI have I<sup>2</sup>C Master examples for the FT232H device in C++ ([AN\\_255](#)) and Visual Basic NET ([AN\\_355](#)). These could be modified to add FT2232H/FT4232H support by referring to the code provided with this application note.

The sample code provided could also be modified to produce a C# class instead of code functions in the main .cs file.

### 8.2 Clock Stretching

The MPSSE does not support clock stretching. The MPSSE has an adaptive clocking feature but this was not specifically designed for I<sup>2</sup>C and does not provide full clock stretching functionality. For this reason, it is not recommended to use adaptive clocking to implement clock stretching and this is not guaranteed or supported by FTDI.

One solution may be to reduce the SCL rate. Some peripherals do not use their clock stretch capability at lower I<sup>2</sup>C clock rates. It is recommended to test all functions of the peripheral to ensure that it does not require clock stretching when running at this lower rate. It is also recommended to consult the datasheet or manufacturer to confirm this. The clock divisor is a parameter of the I2C\_Configure\_MPSSE function call. See section 6.2.3 for details.

When clock stretching is required by the attached peripheral, it is strongly recommended to use the new I<sup>2</sup>C bridging devices from FTDI including the [FT4222H](#) and [FT260](#) which have support for clock stretching functionality. Examples of interfacing to these devices in C# are available for both FT260 and FT4222H as detailed below:

- For the [FT260](#), see AN438 from the [Application Notes](#) page.
- For the [FT4222H](#), see the Examples package available on the [FT4222H Product page](#)

### 8.3 Hardware

The hardware could be enhanced by the addition of an I<sup>2</sup>C isolation chip between the FTDI device and the sensors. This would be especially beneficial if other sensors are used which have an electrical connection to the device being measured/controlled such as ADCs, DACs and power monitoring ICs. Isolation allows the measurement side to be completely isolated electrically from the PC used to control and monitor the devices.

The application can be modified to suit the wide range of sensors and peripherals available with I<sup>2</sup>C interfaces.

## 9 Using the Demo

This section summarises the steps required to use the example provided with a Windows PC.

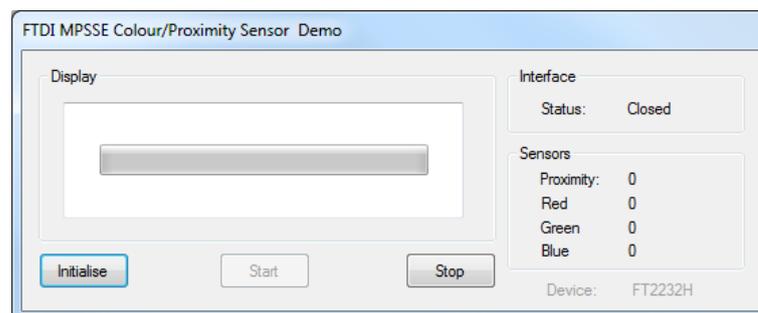
1. If an FTDI driver is not currently installed, install the latest driver.
  - a. Download the executable installer to the PC (onto the desktop etc.). This can be downloaded from the comments column of the Currently Supported Drivers table on the following page: <http://www.ftdichip.com/Drivers/D2XX.htm>
  - b. Right-click and select run-as-administrator
  - c. Follow the steps in the installation wizard until finished

The driver can also be automatically loaded via Windows update when connecting a device if the settings in the OS are configured to allow this.

2. Using a standard USB cable (mini-B or micro-B depending on the module), connect the FTDI module to the USB2 port on the PC. With the circuit shown in the hardware section, the white LED will also illuminate on the colour sensor module until the MPSSE is configured and drives the ADBUS line low.
3. Windows will then complete the driver installation and the device will show up under the Universal Serial Bus Controllers section of the device manager.
4. The red Ready LED on the demo board will illuminate once the driver is installed and enumeration completes (driven by the PWREN# signal going low)
5. Open the sample code by running the executable file. This can be found in the bin > Release folder.

Alternatively, for debugging and modifying the application, the solution (.sln file) can be opened in Visual Studio.

Note that when building the executable in Visual Studio, ensure that the correct device type is selected via the #define at the top. The device type used for the build is displayed in the Interface panel when opening the application. The code could be developed further to provide the user with a drop-down or auto detection.

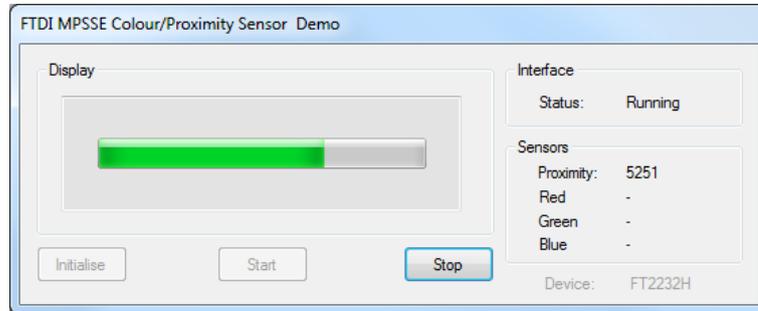


**Figure 8 - Application window after opening the program**

6. Click the Initialise button and the program should find the FTDI device and open it and configure the MPSSE. The Status will change to 'Open' and then a couple of seconds later to 'Ready'.
7. Click the Start button and the green LED will blink to indicate that the measurements are being taken. The white LED on the colour sensor will go off if no object is nearby. The readouts for proximity and RGB values will indicate the measured values. Proximity may show values around

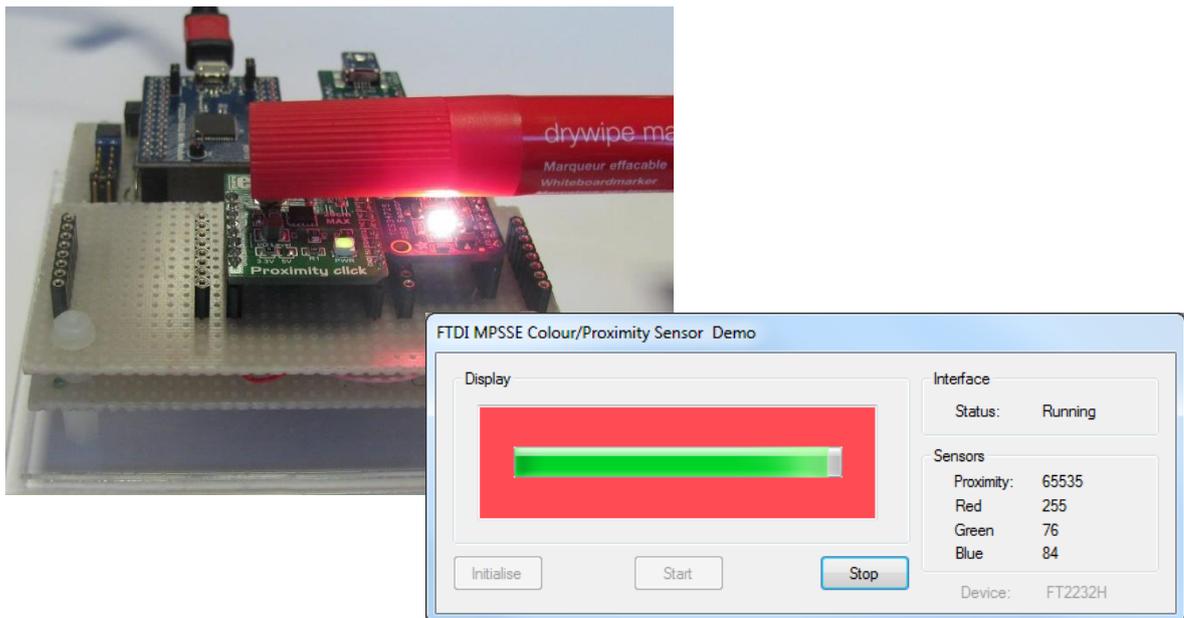
2500 when no object is present due to the background level of the sensor. This could be taken account of by calibration of background levels in a more controlled environment.

8. Bring an object slowly toward the sensors and the proximity bar will increase in proportion to the object approaching (within approx. 20cm range)



**Figure 9 - Application with object approaching**

9. When the object reaches within approx. 2cm of the sensors, the white LED on the colour sensor will come on and the background colour behind the proximity bar will change to indicate the measured colour, for example as shown below with a red object.



**Figure 10 - Application with red object in close proximity**

10. The white LED will go off when the object moves away again as the colour sensing is not required/valid when the object is further away.
11. To close the program, click the Stop button. This will stop the measurements being taken, close the FTDI device port and exit the application.

## 10 Conclusion

This application note and accompanying example have demonstrated the implementation of a USB-I<sup>2</sup>C Master interface with the FTx232H devices, along with the use of the FTDI C# wrapper to control the device from a graphical user interface. In addition, it has explained the features of the MPSSE which are used when implementing the I<sup>2</sup>C protocol.

The code is intended to be modified to suit a wide range of I<sup>2</sup>C interfacing and sensing applications and can be used with other I<sup>2</sup>C sensors and peripherals.

FTDI have a range of FTx232H-based modules including [UM232H](#), [UM232H-B](#), [FT2232H mini modules](#), [FT4232H mini modules](#) and the [C232HM cables](#). This application will work well with all of these modules as well as with the IC itself if placed on a custom designed PCB.

FTDI have a range of other bridging devices capable of I<sup>2</sup>C Master implementation including the [FT4222H](#) and the [FT260](#). The FT260 is the latest addition to the range of USB to I<sup>2</sup>C Master bridge devices and is a HID class device which means that it can be used without loading a separate D2xx driver. Further information can be found on these products at the FTDI homepage [www.ftdichip.com](http://www.ftdichip.com)

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## Appendix A - References

### Document References

#### Product Pages

[FT232H](#)  
[FT2232H](#)  
[FT4232H](#)

#### IC Datasheets

[FT232H Datasheet](#)  
[FT2232H Datasheet](#)  
[FT4232H Datasheet](#)

#### Hardware

[UM232H](#) and [UM232H Datasheet](#)  
[USB Hi-Speed Cables](#) and [C232HM Cables Datasheet](#)  
[UM232H-B](#) and [UM232H-B Datasheet](#)  
[FT2232H Mini-Module](#) and [FT2232H Mini-Module Datasheet](#)  
[FT2232H-56 Mini-Module](#) and [FT2232H-56Q Mini-Module Datasheet](#)  
[FT4232H Mini-Module](#) and [FT4232H Mini-Module Datasheet](#)  
[FT4232H-56 Mini-Module](#) and [FT4232H-56Q Mini-Module Datasheet](#)

#### MPSSE Documents

[AN\\_108 Command Processor for MPSSE and MCU Host Bus Emulation Modes](#)  
[AN\\_135 MPSSE Basics](#)

**Application Notes** [http://www.ftdichip.com/Support/Documents/AppNotes/AN\\_135\\_MPSSE\\_Basics.pdf](http://www.ftdichip.com/Support/Documents/AppNotes/AN_135_MPSSE_Basics.pdf)

[AN\\_355 FT232H MPSSE Example-I2C Master Interface with Visual Basic](#)  
[AN\\_255 USB to I2C Example Using the FT232H and FT201x Devices \(C++\)](#)  
[AN\\_113 Interfacing FT2232H Hi-Speed Devices to I2C Bus](#)

#### Additional References

[D2XX Drivers](#)  
[C# .NET Wrapper](#)  
[AN\\_411 Source Code](#)

### Acronyms and Abbreviations

Terms	Description
GPIO	General Purpose Input Output
I2C	Inter-IC bus
LED	Light Emitting Diode
MPSSE	Multi-Protocol Synchronous Serial Engine
USB	Universal Serial Bus

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## Appendix C – Revision History

Document Title : AN\_411 FTx232H MPSSE I2C Master Example in C#  
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Clearance No. : FTDI#528  
Product Page : <http://www.ftdichip.com/FTProducts.htm>  
Document Feedback : [Send Feedback](#)

Revision	Changes	Date
1.0	Initial Release	2017-05-17
1.1	Update to Clock Stretching section to refer to FT260 and FT4222H for applications needing this feature.	2020-02-12