Revision History


<table>
<thead>
<tr>
<th>Date</th>
<th>Version</th>
<th>Revision</th>
</tr>
</thead>
<tbody>
<tr>
<td>05/03/2017</td>
<td>2017.1</td>
<td>Changed document name. This document now applies to multiple devices.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Verbiage changes in Chapter 5, Co-Simulating With QEMU.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>Added Example QEMU Command in Chapter 5 and Example Simulator Command in Chapter 5.</td>
</tr>
</tbody>
</table>
Table of Contents

Chapter 1: Using Xilinx QEMU
What is QEMU? ................................................................. 5
Documentation and Support Scope ...................................... 5

Chapter 2: Getting Started with QEMU
QEMU Supported Features .................................................. 6
Installing PetaLinux ............................................................ 9

Chapter 3: QEMU Quick Reference Card
Quick Reference .................................................................. 10
QEMU Command Line Reference Manual ................................. 12

Chapter 4: Using XSDB with QEMU
Introduction ........................................................................ 34
Connecting QEMU ............................................................... 34
Downloading and Running with XSDB .................................... 35
Stopping and Starting Execution .............................................. 35
Using Breakpoints ................................................................. 36
Reading and Writing to Memory Registers ............................... 36
Limitations .......................................................................... 36

Chapter 5: Co-Simulating With QEMU
Introduction ........................................................................ 37
Remote-Port ...................................................................... 37
libsystemctllm-soc ............................................................... 37
Co-Simulating with QEMU .................................................... 38

Chapter 6: Using Boot Images on QEMU
Introduction ........................................................................ 40
Using SD for Boot ............................................................... 41
Using QSPI for Boot ............................................................. 41
Using TFTP for Boot ............................................................ 42
SD-Card Partitioning and Loading an Ubuntu-core File System ................................. 43
Appendix A: Additional Resources and Legal Notices

Xilinx Resources ................................................................. 46
Solution Centers ................................................................. 46
Documentation Navigator and Design Hubs ............................ 46
References ............................................................................ 47
Please Read: Important Legal Notices .................................... 48
Chapter 1

Using Xilinx QEMU

What is QEMU?

Xilinx provides a Quick EMUlator (QEMU) for software developers targeting the Zynq®-7000 AP SoC, Zynq UltraScale+™ MPSoC, and MicroBlaze™ development platforms. This system-emulation-model runs on an Intel-compatible Linux and Windows host systems. To use this system emulation model you must be familiar with:

- Device architecture
- GDB for remote debugging QEMU
- Generation of guest software application using Xilinx® PetaLinux and SDK tools
- Device trees

This document provides the basic information to familiarize, use, and debug software with QEMU.

Documentation and Support Scope

Within each package, Xilinx documents only those devices for which bare-metal drivers exist and have been tested.

Users might find additional device models by diving into the QEMU model itself (for example, using the `info mtree` command on the QEMU Console).
# Chapter 2

## Getting Started with QEMU

### QEMU Supported Features

The following table summarizes the status of elements of the QEMU model according to the delivery.

**Table 2-1: QEMU Roadmap**

<table>
<thead>
<tr>
<th>Description</th>
<th>QEMU Status</th>
</tr>
</thead>
<tbody>
<tr>
<td><strong>Application Processing Units</strong></td>
<td></td>
</tr>
<tr>
<td>ARM interrupt controller (GIC v2)</td>
<td>Yes</td>
</tr>
<tr>
<td>ARMv8 (A53) implementation. Quad Core.</td>
<td>Little Endian only</td>
</tr>
<tr>
<td>ARM v8 EL0 support</td>
<td>AArch64 and AArch32</td>
</tr>
<tr>
<td>ARM v8 EL1 support</td>
<td>AArch64 and AArch32</td>
</tr>
<tr>
<td>ARM v8 EL2 support</td>
<td>AArch64</td>
</tr>
<tr>
<td>ARM v8 EL3 support</td>
<td>AArch64</td>
</tr>
<tr>
<td>ARMv8 Crypto instruction support</td>
<td>Supported</td>
</tr>
<tr>
<td>Vector Floating Point (VFP) support</td>
<td>As maintained by mainline. No formal acceptance criteria to feature.</td>
</tr>
<tr>
<td>SIMD support</td>
<td>As maintained by mainline. No formal acceptance criteria to feature.</td>
</tr>
<tr>
<td>ARMv7 Support</td>
<td>A9, R5, R4 supported.</td>
</tr>
<tr>
<td><strong>Realtime Processing Units</strong></td>
<td></td>
</tr>
<tr>
<td>Dual core Cortex®-R5f</td>
<td>Incomplete coverage of system register set, little endian only.</td>
</tr>
<tr>
<td>Dual core R5 CPU run-time configuration</td>
<td>Static dual core, no parallel/lock transitioning.</td>
</tr>
<tr>
<td>Fault Handling</td>
<td>Faults can be externally injected.</td>
</tr>
<tr>
<td>Tightly coupled Memories</td>
<td>No R5 local view. Only globally accessible TCM memory region is accessible. Flat memory only, no control register implementation.</td>
</tr>
<tr>
<td>Interrupt controller</td>
<td>Yes.</td>
</tr>
<tr>
<td>SLCRs</td>
<td>Very limited functionality. Only dummy registers, except SD is_MMC control.</td>
</tr>
<tr>
<td>Description (Cont’d)</td>
<td>QEMU Status (Cont’d)</td>
</tr>
<tr>
<td>--------------------------------------------------</td>
<td>----------------------------------------------------------</td>
</tr>
<tr>
<td><strong>PMU (ZynqMP)</strong></td>
<td></td>
</tr>
<tr>
<td>IPI</td>
<td>Limited Connectivity specific to PMU functionality.</td>
</tr>
<tr>
<td>Global Registers</td>
<td>Yes.</td>
</tr>
<tr>
<td>PMU MicroBlaze</td>
<td>Yes.</td>
</tr>
<tr>
<td>PMU Interrupt Controller</td>
<td>Yes.</td>
</tr>
<tr>
<td><strong>I/O Peripherals and Devices</strong></td>
<td></td>
</tr>
<tr>
<td>I/O Peripherals</td>
<td>Not all peripherals are implemented. Some standard peripherals are slight variations on the actual cores configuration-wise.</td>
</tr>
<tr>
<td>Cadence Gigabit Ethernet Controller</td>
<td>1588 not supported.</td>
</tr>
<tr>
<td>SD Host Controller Interface (v3.0)</td>
<td>Yes.</td>
</tr>
<tr>
<td>SD Card model</td>
<td>no SDXC.</td>
</tr>
<tr>
<td>ONFi compliant NAND flash device modelpwd</td>
<td>Partial model of ANFC command set. Limited selection of parts. Limited ONFi 3.0 features.</td>
</tr>
<tr>
<td>QSPI controller (excludes Linear and Generic)</td>
<td>Yes.</td>
</tr>
<tr>
<td>QSPI linear region</td>
<td>No XIP. Slow emulation performance.</td>
</tr>
<tr>
<td>QSPI NOR flash devices</td>
<td>Incomplete but reasonable selection of parts including many modern QSPI capable devices.</td>
</tr>
<tr>
<td>UART Controller</td>
<td>Yes.</td>
</tr>
<tr>
<td>SPI controller</td>
<td>Master mode only.</td>
</tr>
<tr>
<td>I2C controller</td>
<td>Master mode only.</td>
</tr>
<tr>
<td>DDR</td>
<td>Simple flat RAM model, no ECC.</td>
</tr>
<tr>
<td>CAN</td>
<td>No.</td>
</tr>
<tr>
<td>XADC</td>
<td>No.</td>
</tr>
<tr>
<td>GPIO</td>
<td>Limited functionality: connects to remote port.</td>
</tr>
<tr>
<td>MDIO and Ethernet PHY</td>
<td>Dummy models, show link up on requested PHY using MDIO.</td>
</tr>
<tr>
<td>USB</td>
<td>No.</td>
</tr>
<tr>
<td>SATA</td>
<td>Yes.</td>
</tr>
<tr>
<td>PCI</td>
<td>Yes.</td>
</tr>
<tr>
<td><strong>Display Ports</strong></td>
<td></td>
</tr>
<tr>
<td>DP model</td>
<td>AUX Communication.</td>
</tr>
<tr>
<td></td>
<td>DPCP: DisplayPort Configuration Information.</td>
</tr>
<tr>
<td></td>
<td>EDID.</td>
</tr>
<tr>
<td>DPDMA</td>
<td>Yes</td>
</tr>
</tbody>
</table>
### Chapter 2: Getting Started with QEMU

<table>
<thead>
<tr>
<th>Description (Cont’d)</th>
<th>QEMU Status (Cont’d)</th>
</tr>
</thead>
<tbody>
<tr>
<td>2 Layers</td>
<td>Yes.</td>
</tr>
<tr>
<td>Alpha Blending</td>
<td>Yes.</td>
</tr>
<tr>
<td>Audio</td>
<td>With some unexpected behavior.</td>
</tr>
<tr>
<td>Dynamic resolution changes</td>
<td>Yes.</td>
</tr>
<tr>
<td>Multiple Pixel formats</td>
<td>Not all.</td>
</tr>
<tr>
<td>Mali GPU</td>
<td>No.</td>
</tr>
</tbody>
</table>

#### AMBA AXI Bus

<table>
<thead>
<tr>
<th>AMBA/AXI bus interconnect system</th>
<th>Simple bus model, no AXI/AMBA-specific features (such as MIDs). Master IDs and Trustzone (secure versus non-secure) transactions supported.</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bus quality of service monitoring and control</td>
<td>N/A</td>
</tr>
<tr>
<td>On Chip Memory</td>
<td>Yes.</td>
</tr>
<tr>
<td>AXI Performance Monitor (APM)</td>
<td>N/A</td>
</tr>
<tr>
<td>ATM AXI Trace Monitor (ATM)</td>
<td>N/A</td>
</tr>
</tbody>
</table>

#### Additional Zynq UltraScale+ MP SoC Capabilities

<table>
<thead>
<tr>
<th>XMPU</th>
<th>Does not return Slave error; CPU does not recognize asynchronous aborts on failed accesses.</th>
</tr>
</thead>
<tbody>
<tr>
<td>XPPU</td>
<td>Does not return Slave error; CPU does not recognize asynchronous aborts on failed accesses.</td>
</tr>
<tr>
<td>SMMU</td>
<td>Only supports 64-bit page tables</td>
</tr>
<tr>
<td>Clock/reset controllers for low-power and high power domains.</td>
<td>Limited feature set specific to CPU functionality.</td>
</tr>
<tr>
<td>Interprocessor Interrupt controller</td>
<td>Yes.</td>
</tr>
<tr>
<td>PL-based AMS block</td>
<td>N/A</td>
</tr>
</tbody>
</table>

#### Miscellaneous QEMU Non-IP Related Feature

| Ability to boot multiple software in different CPUs. | Yes.                                                                 |
| Create QEMU Machine models from Linux device tree binaries (DTB)s. | Limited to QEMU maintained DTBs only. IPI/HSI generated DTBs unsupported. |
| FPDDMA                                         | No FCI and no rate-control.                                                                    |
| LPDDMA                                         | No FCI and no rate-control.                                                                    |

#### Timers and Clock Generators

| Triple Timer Counter                          | Yes.                                                                 |
| SWDT, WDT                                     | No.                                                                  |
| Si570/71                                      | I2C device. Dummy emulation of clock generator.                        |
Installing PetaLinux

QEMU comes with the Xilinx® PetaLinux Tools and Xilinx SDK installer. See the PetaLinux documentation [Ref 8] for installation instructions.

**TIP:** Use `which qemu-system-aarch64` to know where QEMU binary is installed after PetaLinux or SDK paths are set.

Launch QEMU Using PetaLinux Commands

QEMU is integrated with the PetaLinux workflow.

To use QEMU with a PetaLinux project, create and build a PetaLinux project for the Zynq® UltraScale+™ MPSoC platform and use the PetaLinux boot flow to boot Linux on QEMU, as follows:

```
petalinux-boot -qemu -prebuilt 3
```
QEMU Quick Reference Card

Quick Reference

Zynq UltraScale+ MPSoC Command Base Template

This is a basic template for Zynq® UltraScale+™ MPSoC device QEMU command lines:

```
qemu-system-aarch64 -M arm-generic-fdt -nographic -dtb <hw-dtb> \
   -device loader,file=<program.elf>,cpu=<cpu-id> \ 
   -global xlnx,zynqmp-boot.cpu-num=<cpu index> \  
   [-device loader,addr=<cpu-reset-register-addr>,data=<value>,data-len=4] \  
   [-global xlnx,zynqmp-boot.use-pmufw=true] \  
   [-boot mode=<boot-mode-id>] \  
   [-drive file=<image-path>, if=<sd | mtd | pflash>, format=raw, \ 
     index=<index_num> ]
```

QEMU Command Options and Descriptions

The following table lists the options and descriptions for QEMU commands.

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>-device loader,file=&lt;program.elf&gt;,cpu=&lt;cpu-id&gt;</code></td>
<td>Specify the software to run (in ELF format).</td>
</tr>
<tr>
<td><code>-device loader,addr=&lt;cpu-reset-register-addr&gt;,data=&lt;value&gt;,data-len=4</code></td>
<td>Release CPU from reset. This command is optional because the next command can also be used to release resets of A53s. Note: R5 resets can be released only with this command.</td>
</tr>
<tr>
<td><code>-global xlnx,zynqmp-boot.cpu-num=&lt;cpu index&gt;</code></td>
<td>Release the specified A53 core. For details regarding the CPU index, refer to CPU Enumeration.</td>
</tr>
<tr>
<td><code>-global xlnx,zynqmp-boot.use-pmufw=true/false</code></td>
<td>Specify true if running with pmu firmware. Note: This option will be deprecated in future, when pmufw uses a default configuration.</td>
</tr>
<tr>
<td><code>-boot mode=&lt;boot-mode-id&gt;</code></td>
<td>Specify the boot mode pins.</td>
</tr>
</tbody>
</table>
Standalone Hello World Example

This example runs a “Hello-world” ELF file on an A53 processor. Substitute the hello_world.elf with the location your target software, as follows:

```
gem5-arm-aarch64 -nographic -M arm-generic-fdt -dtb qemu-arm.dtb -device loader,file=./hello_world.elf,cpu=0 -device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4
```

Zynq-7000 AP SoC Command Base Template

Below is the command base template for Zynq-7000 AP SoC devices.

```
gem5-arm-aarch64 -M arm-generic-fdt-7series [-machine linux=on] -serial /dev/null -serial mon:stdio -display none -kernel <guest image path> -dtb <dtb path> [-device loader,addr=0xf8000008,data=0xDF0D,data-len=4 [-device loader,addr=0xf8000140,data=0x00500801,data-len=4 [-device loader,addr=0xf800012c,data=0x1ed044d,data-len=4 [-device loader,addr=0xf8000108,data=0x0001e008,data-len=4
```

| Table 3-2: Command Options for Zynq-7000 AP SoC Devices |
|---------------------------------|---------------------------------|
| Option                          | Description                     |
| -machine linux=on               | Specifies if -kernel is provided an linux kernel image. |
| --kernel <guest image path>     | Specify path to guest image, such as kernel |
| -dtb <dtb path>                 | Specify the linux dtb path which is used by QEMU emulation |
MicroBlaze Processor Command Base Template

Below is the command base template for MicroBlaze processors.

qemu-system-microblazeel -M microblaze-fdt-plnx \
-m <ram_size> \
-serial mon:stdio \
-display none \
-kernel <guest image path> \
-dtb <path to the dtb>

<table>
<thead>
<tr>
<th>Option</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>-m &lt;ram_size&gt;</td>
<td>Specifies the RAM needed to be created.</td>
</tr>
<tr>
<td>--kernel &lt;guest image path&gt;</td>
<td>Specify path to guest image, such as kernel</td>
</tr>
<tr>
<td>-dtb &lt;dtb path&gt;</td>
<td>Specify the linux dtb path which is used by QEMU emulation</td>
</tr>
</tbody>
</table>


This section provides details of QEMU command line options. The following sections detail boot, network, serial, storage, and miscellaneous command line options.

Using Extra QEMU Command Line Arguments with PetaLinux

The petalinux-boot --qemu command has an argument --qemu-args that lets you specify extra QEMU command line arguments.

Some of the optional arguments specified in the section can be passed to the PetaLinux QEMU using this switch.

**IMPORTANT:** Do not specify the standard, boot, or network options to petalinux-boot; those options are handled transparently by the application.

QEMU Boot Options

[ -device loader,(file=<file_name>|data=<value>,data-len=4),\ 
 [addr=<value>], [cpu=<value>],[force-raw=true] ] ...

This (repeatable) argument configures the QEMU machine for boot.
The boot options perform the following tasks:

- Loads software or data into RAM sections
- Sets the CPU entry points
- Releases CPUs from reset

In ZynqMP, by default, the six ARM CPUs (four cores of Cortex®-A53 and two cores of Cortex-R5) are in reset by their respective reset controllers when no software is loaded. You can use a combination of -device loader arguments to load software and setup the CPUs.

There are two basic modes for the loader argument: file mode and single transaction mode. Specify one mode only. The following subsections describe these modes.

**File Mode**

In file mode, the loader accepts a file as data to load. The file can be in any format and is passed using the file=<file_name> sub-option.

If the file is an ELF or a U-Boot image, the file is parsed and the sections loaded into memory as specified by the image; otherwise, the file is assumed as a raw image and loaded accordingly as an image into memory.

Specify the address for loading raw images with the addr=<value> argument. The address default is 0. The address is ignored if the file is an ELF or U-Boot image.

Optionally, you can specify a CPU using the cpu-num=<value> sub-option.

If specified, the CPU has a set entry point.

- For ELFs and U-Boot images, the address is set as specified by the image.
- For raw images, the entry point is set to the start address.
- If you do not specify a CPU, the bus for CPU0 loads images, but no program entry point is set. See CPU Enumeration, page 14 for more details on the meaning of <value>.

There are cases where you might want to treat an ELF or a U-Boot image as a raw data image (particularly useful for testing bootloaders with ELF or U-Boot capability).

You can pass the force-raw=true sub-option to instruct the loader to treat the image as raw in this case.

You must specify the addr; in this case and the section information in the ELF or U-Boot image are ignored.
Single Transaction Mode

In single transaction mode, a single bus transaction occurs.

- `data addr` and `data-len` must be specified.
  - `data-len` must equal 4 (corresponding to a single 4-bit transaction).
  - `addr` must be aligned to 4-bits.

Before the initial system reset for ZynqMP, the QEMU performs the specified bus transaction. The initial system reset might clear the value set by the single transaction when the transaction accesses the I/O peripherals. As a work-around, key registers interpret bit 31 (usually reserved) as an indicator to not reset that particular register when resetting this system. This is useful for releasing CPU resets from the command line.

The registers that support bit-31 `reset-ignore` are:

- `CRF.RST_FPD_APU`
- `CRL.RST_LPD_TOP`
- `PMU_LOCAL.LOCAL_RESET`
- `RPU.RPU_GLBL_CNTL`

Optionally, you can specify a CPU using the `cpu-num=<value>` sub-option.

The single transaction occurs from the perspective of the specified CPU. If you do not specify a CPU, then the system assumes `CPU0`.

See the *Zynq UltraScale+ MPSoC Registers Users Guide* (UG1087) [Ref 7] for more information about registers.

CPU Enumeration

The `cpu-num=<value>` argument interprets value are shown in the following table:

<table>
<thead>
<tr>
<th>Value</th>
<th>CPU</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>A53-0</td>
</tr>
<tr>
<td>1</td>
<td>A53-1</td>
</tr>
<tr>
<td>2</td>
<td>A53-2</td>
</tr>
<tr>
<td>3</td>
<td>A53-3</td>
</tr>
<tr>
<td>4</td>
<td>R5-0</td>
</tr>
<tr>
<td>5</td>
<td>R5-1</td>
</tr>
</tbody>
</table>
Advanced

If you edit the /cpus dtb node, these enumerations change. The enumerations of the CPUs matches the DTS /cpus node ordering.

**Hot Loading**

You can use the loader at runtime to load new software into an already running system. This is accessible from the QEMU monitor. See the Non-Graphical I/O Option, page 18 for information on accessing the monitor.

From the monitor, you can stop the emulation using the `stop` command:

```
(qemu) stop
```

You can then use the loader to add new software or release CPUs from reset. The syntax is:

```
(qemu) device_add loader,(file=<file>|data=<value>,data len=4),
[addr=<value>],[cpu-num=<value>],[force-raw=true]
```

All sub-options are the same as described in the previous section. The emulation can then be resumed (with the new memory and CPU state from the loading operations) using the following `c` command:

```
(qemu) c
```

**QEMU Command Examples**

The following table provides command examples.

<table>
<thead>
<tr>
<th>Description</th>
<th>Command</th>
</tr>
</thead>
<tbody>
<tr>
<td>Load an ELF onto Cortex-A53-0.</td>
<td><code>-device loader, file=./hello_world.elf,cpu-num=0</code></td>
</tr>
<tr>
<td>Release Cortex-A53-0 from reset.</td>
<td><code>-device loader,addr=0xfd1a0104, data=0x8000000e, data-len=4</code></td>
</tr>
<tr>
<td>Load a binary DTB into RAM at a specific address (no CPU entry point will be set).</td>
<td><code>-device loader,file=./Image,addr=0x0008000</code></td>
</tr>
<tr>
<td>Load an ELF to RAM (no CPU entry point will be set).</td>
<td><code>-device loader,file=./foo.elf</code></td>
</tr>
<tr>
<td>Load an ELF to Cortex-A53-0 from the monitor in an already running system.</td>
<td><code>(qemu) stop</code>&lt;br&gt;<code>(qemu) device_add loader,file=./foo.elf,cpu-num=0</code>&lt;br&gt;<code>(qemu) device_add loader,addr=0xfd1a0104,data=0x8000000e,data-len=4</code>&lt;br&gt;<code>(qemu) c</code></td>
</tr>
</tbody>
</table>
Using Single Transactions to Unlock CPUs

You can unlock CPUs by writing into system configuration registers using single transactions. The A53-0,1,2,3 reset register is CRF_APB.RST_FPD_APU.

The following table lists the arguments that can unlock certain CPU combinations.

### Table 3-6: Single Transaction Unlock Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Command</th>
</tr>
</thead>
<tbody>
<tr>
<td>A53-0</td>
<td>-device loader addr=0xfd1a0104, data=0x8000000e, data-len=4</td>
</tr>
<tr>
<td>A53-1</td>
<td>-device loader addr=0xfd1a0104, data=0x8000000d, data-len=4</td>
</tr>
<tr>
<td>A53-2</td>
<td>-device loader addr=0xfd1a0104, data=0x8000000b, data-len=4</td>
</tr>
<tr>
<td>A53-3</td>
<td>-device loader addr=0xfd1a0104, data=0x80000007, data-len=4</td>
</tr>
<tr>
<td>All A53</td>
<td>-device loader addr=0xfd1a0104, data=0x80000000, data-len=4</td>
</tr>
</tbody>
</table>

Similarly the R5-0,1 reset register is CRL_APB.RST_LPD_TOP. As R5-0 and R5-1 can work in split-mode or lockstep mode, split-mode/lock-step requires extra configuration for R5, which is done using register RPU.RPU_GLBL_CNTL.

### Table 3-7: Cortex-R5 Registers and Commands

<table>
<thead>
<tr>
<th>Register</th>
<th>Command</th>
</tr>
</thead>
</table>
| R5-0 (split mode)   | -device loader, addr=0xff5e023c, data=0x80008fde, data-len=4  
|                     | -device loader, addr=0xff9a0000, data=0x80000218, data-len=4 |
| R5-1 (split mode)   | -device loader, addr=0xff5e023c, data=0x80008fdd, data-len=4  
|                     | -device loader, addr=0xff9a0000, data=0x80000218, data-len=4 |
| Both R5 (split mode)| -device loader, addr=0xff5e023c, data=0x80008fde, data-len=4  
|                     | -device loader, addr=0xff9a0000, data=0x80000218, data-len=4 |
| Lockstep Mode       | -device loader, addr=0xff5e023c, data=0x80008fde, data-len=4 |

See the Zynq UltraScale+ MPSoC Registers Users Guide (UG1087) [Ref 7] for more information.

**Hardware Specification**

```
-M arm-generic-fdt  (-hw-dtb | -dtb) <file> ...
```

These arguments are required for all supported boot flows.

The -M argument to QEMU specifies the QEMU machine to create. In this case, you are selecting the arm-generic-fdt machine option, which tells QEMU to parse a device tree binary (or DTB) for machine generation.

QEMU automatically creates CPUs and peripherals for each node in the device tree it has a corresponding device model for (QEMU has a library of known DTS compatible strings).

The -dtb or -hw-dtb argument specifies the DTB describing the system.
Note: For ZynqMP, dts are available in github: https://github.com/Xilinx/qemu-devicetrees.git. For Zynq-7000 AP SoC device and MicroBlaze processor kernel, dtb can be used.

The ZynqMP DTB is also available in a PetaLinux project at:

<proj_path>/images/linux/zynqmp-qemu-arm.dtb

Or:

<proj_path>/pre-built/linux/images/zynqmp-qemu-arm.dtb

Advanced

DTSs for QEMU are available in the following directory:

<project_directory>/project-spec/meta-user/recipes-bsp/device-tree/files/

Example

qemu-system-aarch64 -nographic -M arm-generic-fdt -dtb ./images/linux/zynqmp-qemu-arm.dtb

-dtb vs -hw-dtb

For Linux Kernel boots, QEMU supports a flow where different DTBs are used for machine generation and Linux Kernel boot. In this flow, both -dtb and -hw-dtb are specified on the command line.

The -hw-dtb is used for machine generation and -dtb is passed to the Linux Kernel (using a memory buffer). When -dtb is passed, QEMU removes the nodes that it cannot emulate and later copies it to RAM for kernel boot.

Note: This procedure is applicable only when kernel is passed on QEMU command line.

For standalone flows, these two arguments are fully interchangeable; specify only one or the other.

CAUTION! For ZynqMP, the QEMU DTB is different from the kernel system.dtb.

QEMU DTS are different for ZynqMP single and multi-architecture models. The following DTBs are available in PetaLinux project.

• Single-arch : zynqmp-qemu-arm.dtb
• Multi-arch : zynqmp-qemu-multiarch-arm.dtb, zynqmp-qemu-multiarch-pmu.dtb
Non-Graphical I/O Option
-`nographic`

By default, QEMU attempts to create a display for user I/O. This option instructs the QEMU that there is no need for a display and I/O is serial.

QEMU attaches the invoking terminal to the serial port in this case (in the default use cases, this is UART0). See Serial Options, page 24 for more information and choices.

In this mode, the QEMU monitor (a command line interface for sending control commands to QEMU) is multiplexed on `stdio`. To switch between the serial port and the monitor, use the following command:

```
CTRL-a c
```

Boot Mode
-`-boot mode=<value>`

This command line argument selects the value of boot mode pins.

Multiple-Architecture QEMU (ZynqMP)

A multiple architecture (Multi-Arch) QEMU is a special concept in which more than one instance of QEMU of completely different architecture can communicate with each other and can run together using socket communication.

This version of QEMU supports running the ARM® Cortex-A53s and Cortex-R5s, and the MicroBlaze™ device power management unit (PMU).

The multi-architecture version of QEMU needs different device tree binaries (DTBs) than what is necessary for Single-Architecture.

Multi-Architecture DTB

The following are PetaLinux DTBs:

- `zynqmp-qemu-multiarch-arm.dtb`: DTB for `qemu-system-aarch64`
- `zynqmp-qemu-multiarch-pmu.dtb`: DTB for `qemu-system-microblazeel`

In `qemu-devicetrees` repositories, you can find them in the following path:

- `qemu-devicetrees/LATEST/MULTI_ARCH/zcu102-arm.dtb`: DTB for `qemu-system-aarch64`
- `qemu-devicetrees/LATEST/MULTI_ARCH/zynqmp-pmu.dtb`: DTB for `qemu-system-microblazeel`
Chapter 3: QEMU Quick Reference Card

Single-Arch DTB

- `zynqmp-qemu-arm.dtb`: DTB for qemu-system-aarch64
- `qemu-devicetrees/LATEST/SINGLE_ARCH/zcu102-arm.dtb`

Machine-path

- `-machine-path [./qemu-tmp]`
- `-machine-path` takes any folder path as argument, and QEMU uses that area for creating sockets and parallel communication. This is a mandatory argument for using Multiple-Architecture.

For example commands running ZynqMP with PMU, refer to Table 3-1.

See the *Zynq UltraScale+ MPSoC: Software Developers Guide* (UG1137) [Ref 6] for steps on running QEMU with ARM and PMU.

Storage Media

Several disk and storage media interfaces are modeled. You can pass each to a regular file(s) to use for stored data. QEMU updates the files so the data can be persistent across multiple sessions.

**Argument Format**

The format is:

```
-drive file=<image-path>, if=(mtd|sd|pflash), format=raw, index=<value>[,readonly]
```

The argument allows specification of extra options such as marking the file as read-only.

The argument can also be used to specify the index of the device, allowing specifying files for devices in an order-independent way.

**QSPI**

QSPI is modeled with the Flash specified in DTS. The SPI flashes can connect in a dual-parallel arrangement. The file size for each should match Flash model size.

If you are using only a single mode QSPI, then only one QSPI argument is needed.

For each, if an image is not provided QEMU still models the flash, but initializes with NULL data and discards the data after QEMU exists. Data can be written and read back within a single session in this case.
**Flash Striper Utility**

In parallel mode, that the QSPI data passes in for each flash is unique to that flash chip. Because the QSPI controller implements bit-stripping in dual parallel mode, a special utility is needed to take a single QSPI data image and format into the two images. The syntax is as follows:

```bash
flash_strip_bw <input> <out1> <out0>
```

where:

- `<input>` is a 128MB image.
- `<out0>` and `<out1>` are the two 64MB images passable to the `-mtdblock` arguments for QSPI.

**IMPORTANT:** `flash-strip-bw` is done the reverse order to QEMU.

The reverse is also possible, taking the two striped images and converting them back to a single 64MB image as shown in the following command:

```bash
flash_unstrip_bw <output> <in1> <in0>
```

**Building the Flash Striper**

Compile for your host with the following commands:

```bash
SOURCE=flash_stripe.c
gcc $SOURCE -o flash_strip_bw -DFLASH_STRIP_BW
```

The Flash Strip utility is available as a part of the `qemu_utilities`.

The following table lists the supported SPI Flash models.

<table>
<thead>
<tr>
<th>Vendor</th>
<th>Flash Models</th>
</tr>
</thead>
<tbody>
<tr>
<td>Atmel</td>
<td>at25fs010, 25fs040, at25df041a, at25df321a, at25df641, at26f004, at26df081a, at26df161a, at26df321, at45db081d</td>
</tr>
<tr>
<td>EON -- en25xxx</td>
<td>en25f32, en25p32, en25q32b, en25p64, en25q64</td>
</tr>
<tr>
<td>GigaDevice</td>
<td>gd25q32, gd25q64</td>
</tr>
<tr>
<td>Intel/Numonyx</td>
<td>160s33b, 320s33b, 640s33b, n25q064</td>
</tr>
</tbody>
</table>
For each SPI Flash, if an image is not provided QEMU still models the flash, but initializes with NULL data and discards the data after QEMU exits. Data can be written and read back within a single session in this case.

**SPI**

The SD card model in QEMU is generic and does not attempt to model a specific physical part. The size of the input file initializes the size of the emulated SD card. Only 512MB SD images are officially supported, although powers of two around that order of magnitude will work.

**IMPORTANT:** SDXC (>32GB) sizes do not work.

If an SD argument is not specified, no SD card is modeled, the corresponding SD slot is ejected.

**Note:** This is different from the SPI, where if there is no argument those modes still model a physical device.
**EMMC**

QEMU will model an EMMC card for `drive file=<file_path>,if=sd`. EMMC connects to respective host interface controllers, based on the slcr settings.

The size of the input file initializes the size of the emulated MMC card. Only 512MB images are supported, although powers of two, around that order of magnitude, will work.

**EEPROM**

QEMU models EEPROMS connected to I2C. A back-end file can be passed as follows:

```
-drive file=<file_path>,if=mtd, index=<id>.
```

Users can find the information on which I2C controller eeproms are connected in respective board DTS.

**Passing Bootable Images**

Boot images are passed to the QEMU using the command line with the storage media options. This is useful for testing, or testing with, FSBL or U-Boot bootloaders. See the Bootgen documentation in the *Zynq UltraScale+ MP SoC Software Developers Guide* [Ref 1] for how to create the bootable images.

See the Example, page 17 command for a comprehensive suite of examples for bootable image commands.

**Chardev Options**

```
-chardev backend, id=id [,options]
```

The `-chardev` arguments lets you create a character device. This can be thought of as a file descriptor that routes text from inside QEMU to outside QEMU. The `-chardev` arguments consists of three main parts:

1. The output
2. If the chardev is muxable
3. The ID of this chardev
Character Device Option Examples

- chardev null,id=id[,mux=<on|off>]
- chardev socket,id=id[,host=host],port=port,[to=to],[ipv4],[ipv6]
  ,[nodelay],[reconnect=seconds],[server],[nowait],[telnet]
  ,[reconnect=seconds] [mux=<on|off>] (tcp)
- chardev socket,id=id,path=path,[server],[nowait],[telnet]
  ,[reconnect=seconds] [mux=<on|off>] (unix)
- chardev udp,id=id[,host=host],port=port,[localaddr=localaddr]
  ,[localport=localport],[ipv4],[ipv6],[mux=on|off]
- chardev msmouse,id=id, [mux=on|off]
- chardev vc,id=id[,[width=width],[height=height]][,[cols=cols]
  ,[rows=rows]],mux=on|off]
- chardev ringbuf,id=id,[size=size]
- chardev file,id=id,path=path,[mux=on|off]
- chardev pipe,id=id,path=path,[mux=on|off]
- chardev pty,id=id[,mux=on|off]
- chardev stdio,id=id[,mux=on|off][,[signal=on|off]
- chardev serial,id=id,path=path[,mux=on|off]
- chardev tty,id=id,path=path[,mux=on|off]
- chardev parallel,id=id,path=path[,mux=on|off]
- chardev parport,id=id,path=path[,mux=on|off]

STDOUT

The following is an example chardev:

```
-chardev stdio,mux=on,id=terminal
```

In this case anything sent to the chardev is redirected to the standard I/O. This chardev supports muxing and is called terminal.

Server (TCP Socket)

The following is an example of using chardev to connect to a server:

```
-chardev socket,id=terminal,host=localhost,port=4444,mux=on
```

The server can be nc, in this case use:

```
nc -k -l localhost 4444
```
Chapter 3: QEMU Quick Reference Card

Socket (UNIX Socket)

The following is an example of connecting to a standard UNIX socket:

```
-chardev socket,id=output,path=/tmp/socket,mux=on
```

The socket can be created by nc by using:

```
c -k -lU /tmp/socket
```

pty

The following is an example of connecting to a pseudo-terminal:

```
chardev pty,id=output,mux=on
```

There is no wait on this `chardev` to get connected to `pty`. You can open `pty` c with any serial terminal: Minico, putty, screen.

```
screen /dev/pty/188
```

QEMU puts out on which `pty` it is connected.

```
"char device redirected to /dev/pts/188 (label IO-base)"
```

Serial Options

```
-serial <arg>
```

By default, the QEMU connects the invoking terminal to UART0 to provide user I/O (see Non-Graphical I/O Option, page 18 for more information.)

You can override this behavior by providing at least one explicit `-serial` argument.

The following table lists the supported values for `<arg>`:

<table>
<thead>
<tr>
<th><code>&lt;arg&gt;</code></th>
<th>Effects</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>/dev/null</code></td>
<td>Disconnect this particular serial.</td>
</tr>
<tr>
<td><code>mon:stdio</code></td>
<td>Connect this serial and monitor to the terminal.</td>
</tr>
<tr>
<td><code>stdio</code></td>
<td>Connect this serial to terminal.</td>
</tr>
<tr>
<td><code>telnet::&lt;port&gt;,server, nowait</code></td>
<td>Create a localhost telnet server on <code>&lt;port&gt;</code> for the serial connection. It can be accessed by: <code>telnet localhost &lt;port&gt;</code>.</td>
</tr>
<tr>
<td><code>chardev: dev</code></td>
<td>Connects serial to a backend; for example, to a socket, pipe, or terminal.</td>
</tr>
</tbody>
</table>
**Serial Command Examples**

The following are some of the common non-default serial setups.

- Disconnect all serials: `-serial /dev/null -serial /dev/null`
- Connect UART1 to the terminal and ignore UART0: `-serial /dev/null -serial mon:stdio`
- Connect UART0 to terminal and UART1 to telnet: `-serial mon:stdio -serial telnet::1234,server,nowait`
- Connect UART0 to chardev socket: `-serial chardev:terminal`

*Note:* `terminal` is the `chardev` device ID. See details the **Chardev Options, page 22**.

**Monitor Options**

- `-monitor:` specifies where to send the QEMU monitor. Generally, this is sent to the standard I/O which can be done with the following command:

  `-monitor chardev:terminal`

**Networking Options**

`-net nic -net user -tftp <directory>`

This connects GEM0 to a virtual network, with a TFTP server hosting the argument directory. The TFTP server IP is `10.0.2.2`. The guest software can configure the machine to an IP on the same subnet (for example `10.0.2.4`) and communicate. The following command connects GEM3 of the ZCU102 board to the user network:

`-nt nic -net nic -net nic -net user`

See the QEMU public documentation for more comprehensive listing of QEMU networking options.

**Port Redirection**

Adding the following command makes every packet in/out of host-port to redirect to target-port of guest. For example, to get connected to guest using telnet, one can redirect the port 23 of guest to any free port of the host.

`-redir tcp:<host-port>::<guest-ip>::<target-port>`

**Example**

`-redir tcp:1440:10.0.2.15:23`
**Tap Mode (Requires Sudo)**

Tap network is similar to bridge network; it allows the guest to communicate with host DHCP and DNS. This makes it also a real device on a network.

Unlike user mode, in tap mode, networking guest is directly accessible without any port redirection/forwarding. The following is an example:

```
-net nic -net nic -net nic -net nic -net tap,downscript=no
```

Before running QEMU ensure that you have the `qemu-ifup` script available in `/etc/`. Follow the instructions in this link to set up tap network.

**Debug Options**

- **QEMU Arguments: Enabling and using the GDB stub:**
  
  ```
  -gdb tcp::<host_name>::<port> -S
  ```

  Where:

  - `-gdb`: Creates a GDB stub on the local host at the specified port.
  - `-S`: Causes the emulation to start in the pause state. This allows you to attach a debugger before software starts executing. You can attach your GDB to QEMU as follows: `(gdb) target remote :<port>`

  On the GDB host, use the GDB that corresponds to your build toolchain; for example:

  - `aarch64-none-elf-gdb` or `aarch64-linux-gnu-gdb` for debugging A53 code.
  
    Or:

  - `arm-none-eabi-gdb` for R5 software.

  QEMU emulation can be resumed using a continue in GDB, as shown in the following command:

  ```
  (gdb) c
  ```

  Breakpoints can be inserted as normal. Either symbolic function names, file lines, or text memory addresses can be used. See the *ARM Information Center [Ref 15]* for more information.
Debug-Related Monitor Commands

You can use a range of QEMU monitor commands to access helpful debug information and perform some basic operations. The following are a few of the more commonly used options. See Non-Graphical I/O Option, page 18 for information on accessing the monitor.

Stopping and resuming the VM:

(qemu) stop
(qemu) c

These commands stop and resume the emulation, respectively.

If QEMU is started with the -S argument, you can use the c command to commence emulation.

Display Options

The QEMU display option emulates a virtual monitor for the display applications.

IMPORTANT: To make use of the Display option, do not pass the -no graphic argument in the command line; it restricts the ability to create a display console.

CAUTION! PetaLinux QEMU does Not include SDL support for Display Monitor Emulation, It is recommended that you build QEMU from source with SDL enabled. See Building QEMU from Source, page 32.

The following command option, when passed on the QEMU command line, creates a VNC session through which you can view the display console:

-vnc <hostname>:<display>

For example, the command -vnc localhost:1 connects to a VNC session using VNC viewer on localhost:1, where 1 represents the display ID. In this way you can have \( n \) number of display monitors open.

Using TightVNC and RealVNC

In both TightVNC and RealVNC you can open the monitor using following command:

vncviewer localhost:<display id>

To open monitor for a different server, enable port forwarding using the following command:

ssh <target-host> -L <localhost-port>:localhost:<target-host-port>:<target-host-port>
For example, if the QEMU display id is 1, it should map to TCP port 5901. Then, run the port forwarding command as follows:

```
ssh qemu-host -L 5901:localhost:5901
```

Now use the same vncviewer command to open the display.

**IMPORTANT:** RealVNC does not directly work. Follow the workaround in the following link.

### Listening on a VNC Session

You can connect to a display at any time using the `-vnc <hostname>:<display>` command; however, if you need the QEMU to wait until it is connected to a VNC session, configure the QEMU to work with a *listening* VNC session.

```
-vnc <hostname>:<tcp port number>,reverse
```

For example, `-vnc localhost:5501,reverse`, will be able to connect to a listening VNC session with display-id 1.

**Note:** The TCP port number for display ID 1 maps as 5500+d, where d is the display ID.

Running the VNC viewer with `-listen 1` results in the host listening for connections on the VNC session with display 1.

### Listing and Selecting CPUs in the System

From the QEMU Monitor Console, use the following commands:

```
(qemu) info cpus
(qemu) cpu <value>
```

Example for ZynqMP:

- The `info cpus` lists out the CPUs in the system and indicated the currently selected CPU. In a normal setup there are six CPUs: 4 x A53 and 2 x R5. QEMU has the concept of a currently selected CPU with respect to some monitor commands. This is very similar to GDBs concept of a currently selected thread.
- Change the selected CPU using the `cpu <value>` command; where `<value>` is a number from 0 to 5 that corresponds to the QEMU CPU indexes.
- CPUs with an asterisk (*) are currently selected.

See CPU Enumeration, page 14 for information on how QEMU CPU indexes match the Zynq UltraScale+ MPSoC platform CPUs.
Inspecting CPU State

(qemu) info registers

The info registers command dumps out useful information about the current CPU (such as registers and current EL) for R5 CPUs. R15 is the program counter.

See the ARM Architecture reference manuals for the meaning of specific pieces of information.

Inspecting Physical Memory

(qemu) (xp | x) <addr>
(qemu) memsave <addr> <length> <file>

Use these commands to dump memory data. The x or xp command can be used to read a single address:

- xp: (qemu) xp 0x1234F00D
  - x uses virtual addresses for the currently selected cpu
  - xp uses physical addresses
- The memsave command saves a buffer of specified length (<length>) and address (<addr>) to a file specified by <file>, where <file> is the data buffer as raw binary data.

For example: (qemu) memsave 0xc0ae1a80 16384 dumpmem.logbuf

Linux Kernel Logbuf Extraction

The following instructions are directly applicable to booting Linux Zynq® UltraScale+™ MPSoC QEMU. There is more information available at Linux Kernel Logbuf Extraction [Ref 19].

Examples for Single Arch

This section provides some example complete fully elaborated QEMU command lines. Substitute particular arguments to suite your application as needed. See the Command Line Argument Manual for further details of each options. For each command, it is assumed the current working directory is a PetaLinux project root.

You can run the commands without a PetaLinux project but file paths of boot components will need to be adjusted.

See Storage Media, page 19 as required for details on how to generate storage media files for QSPI, NAND, and SD.
FSBL as an Application on A53-0

In each of the following examples, FSBL is run as the application; however, these command line formats are applicable to other standalone software. Substituting the FSBL ELF file for another standalone application is valid.

A53-0 FSBL in JTAG Mode

```bash
gemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=./images/linux/zynqmp_a53_fsbl.elf,cpu-num=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4
```

A53-0 FSBL in QSPI Boot Mode (Single)

```bash
gemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=./images/linux/zynqmp_a53_fsbl.elf,cpu-num=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-drive file=gemu_qspi.bin,if=mtd,format=raw,index=0\ 
-boot mode=1
```

A53-0 FSBL in QSPI Boot Mode (Dual Parallel)

```bash
gemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=./images/linux/zynqmp_a53_fsbl.elf,cpu-num=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-drive file=gemu_qspi_high.bin,if=mtd,format=raw,index=0\ 
-drive file=gemu_qspi_low.bin,if=mtd,format=raw,index=1\ 
-boot mode=1
```

A53-0 FSBL in SD Boot Mode

```bash
gemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=./images/linux/zynqmp_a53_fsbl.elf,cpu-num=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-drive file=gemu_sd.img,if=sd,format=raw,index=0\ 
-boot mode=3
```

FSBL as an Application on R5-0

In each of the following examples, FSBL is run as the application. These command line format are however applicable to other standalone software. Substituting the FSBL ELF file for another standalone application is valid.

R5-0 FSBL in JTAG Mode

```bash
gemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=zyngmp_r5_fsbl.elf,cpu-num=4 \
-device loader,addr=0xff5e023c,data=0x80008fde,data-len=4 \
-device loader,addr=0xff9a0000,data=0x80000218,data-len=4
```
R5-0 FSBL in QSPI Boot Mode (Single)

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
  -dtb ./images/linux/zynqmp-qemu-arm.dtb \
  -device loader,file=zynqmp_r5_fsbl.elf,cpu-num=4 \
  -device loader,addr=0xff5e023c,data=0x80008fde,data-len=4 \
  -device loader,addr=0xff9a0000,data=0x80000218,data-len=4 \
  -drive file=qemu_qspi.bin,if=mtd,format=raw,index=0  
  -boot mode=1
```

R5-0 FSBL in QSPI Boot Mode (Dual Parallel)

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
  -dtb ./images/linux/zynqmp-qemu-arm.dtb \
  -device loader,file=zynqmp_r5_fsbl.elf,cpu=num=4 \
  -device loader.addr=0xff5e023c,data=0x80008fde,data-len=4 \
  -device loader.addr=0xff9a0000,data=0x80000218,data-len=4 \
  -drive file=qemu_qspi_high.bin,if=mtd,format=raw,index=0 \n  -drive file=qemu_qspi_low.bin,if=mtd,format=raw,index=1  
  -boot mode=1
```

R5-0 FSBL in SD Boot Mode

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
  -dtb ./images/linux/zynqmp-qemu-arm.dtb \
  -device loader,file=zynqmp_r5_fsbl.elf,cpu=num=4 \
  -device loader.addr=0xff5e023c,data=0x80008fde,data-len=4 \
  -device loader.addr=0xff9a0000,data=0x80000218,data-len=4 \
  -drive file=qemu_sd.img,if=sd,format=raw,index=0  
  -boot mode=3
```

R5 Lockstep FSBL

Only one example is provided for lock step, although all boot bodes are valid. See the previous example command line arguments for storage media and boot mode that could be applied to this command line. This specific example is JTAG boot mode:

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
  -dtb ./images/linux/zynqmp-qemu-arm.dtb \
  -device loader,file=zynqmp_r5_fsbl.elf,cpu=4 \
  -device loader.addr=0xff5e023c,data=0x80008fde,data \n  -len=4
```
Running PMU and ARM QEMU

The following examples runs two instances of QEMU, one emulating the PS part of Cortex-A53s and Cortex-R5s and another is the PMU in a Microblaze™ device.

**Note:** DTBs used for single and present multiarch model are different.

1. Set up the ARM instance by typing the following commands:

```shell
qemu-system-aarch64 -M arm-generic-fdt -nographic \
    -dtb <proj>/pre-built/linux/images/zynqmp-qemu-multiarch-arm.dtb \
    -device loader,file=<proj>/pre-built/linux/images/bl31.elf,cpu-num=0 \
    -device loader,file=<proj>/pre-built/linux/images/u-boot.elf \
    -global xlnx,zynqmp-boot.cpu-num=0 \n    -global xlnx,zynqmp-boot.use-pmufw=true \n    -machine-path <any-folder-path> -gdb tcp::9000
```

2. Set up a PMU instance by typing the following commands:

```shell
qemu-system-microblazeel -M microblaze-fdt -nographic \n    -dtb <proj>/pre-built/linux/images/zynqmp-qemu-multiarch-pmu.dtb \n    -kernel <proj>/pre-built/linux/images/pmu_rom_qemu_sha3.elf \n    -device loader,file=<proj>/pre-built/linux/images/pmufw.elf \n    -machine-path <any-folder-path> -gdb tcp::9005
```

Users can connect to ARM QEMU using the XSDB `connect` command. See Building QEMU from Source in Chapter 3 for more information.

Building QEMU from Source

QEMU source code is available on the [github](https://github.com) link [Ref 17]. The following are the build steps:

1. Clone QEMU, and update the sub-modules, dtc and pixman.

   **IMPORTANT:** *Make sure to install the build dependencies before starting the build.*

   For Ubuntu, use `apt-get build-dep qemu`.

   Its recommended to do an out-of-tree build.

2. Make an empty folder outside of the source folder, and change into the new folder.
3. Run the following configure command:

```bash
<QEMU_SOURCE_PATH>/configure
--target-list="aarch64-softmmu,microblazeel-softmmu,arm-softmmu" \  
  --enable-debug \  
  --forceINTERNAL-fdt \  
  --extra-cflags="-DXILINX_SPIPS_ERR_DEBUG=2 \  
    -DM25P80_ERR_DEBUG=2 \  
    -DNAND_ERR_DEBUG=1 \  
    -DARASAN_NFC_ERR_DEBUG=1 \  
    -DSDHC_DEBUG \  
    -DFDT_GENERIC_UTIL_ERR_DEBUG=2 \  
    -DCADENCE_GEM_ERR_DEBUG \  
    -DCONFIG_FDT " \  
  --disable-werror \  
  --enable-fdt \  
  --enable-sdl
```

4. Run `make -j16`.

QEMU binaries are available at:

- `<build_path>/aarch64-softmmu/qemu-system-aarch64`
- `<build_path>/microblazeel-softmmu/qemu-system-microblazeel`

You might need to install additional libraries based on your configuration inputs.
Using XSDB with QEMU

Introduction

The Xilinx® system debugger (XSDB) lets you download and debug application on the QEMU platform.

Using the XSDB, you can do the following:

- Download and run a bare-metal application ELF
- Suspend and resume a processor
- Debug using breakpoints
- Read and write registers

Connecting QEMU

XSDB connects to QEMU GDB by using remote ports.

While passing arguments to load and run QEMU running, attach a GDB client by appending the option: `-gdb tcp::<port-num>` to QEMU command line.

The following is the total command:

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb ./images/linux/zynqmp-qemu-arm.dtb -gdb tcp::1440
```

**Note:** Port number is not specific; it can be any free port.

With QEMU running, connect the QEMU using the XSDB `gdbremote` command shown in the following command line:

```
gdbremote connect <hostname>::<port-num>
```

**Note:** The hostname can be localhost or the name of the server or an IP address upon which QEMU is running.
Chapter 4: Using XSDB with QEMU

Downloading and Running with XSDB

Download and run with XSDB on available targets by selecting a target and loading an ELF. The targets or ta command shows the available targets (processors) on board.

For example, the command lists all the targets as shown:

```
xsdbbox
  1  GdbClient (xhdl3763:6678)
  2  pl
     3  Cortex-A53 #0 (Suspended)
     4  Cortex-A53 #1 (Suspended)
     5  Cortex-A53 #2 (Suspended)
     6  Cortex-A53 #3 (Suspended)
  7  p2
     8  Cortex-R5 #0 (Suspended)
     9  Cortex-R5 #1 (Suspended)
```

- `ta <target-number>`: Connects to the respective targets.
  
  **Note:** These are not the same numbers that QEMU uses for CPUs internally.

- `dow <elf file path>`: Downloads the specified ELF and sets the PC value to the corresponding targets.
  
  **Note:** Before downloading and running ELFs, take the processors out of reset. This requires a few more commands to get started. The following table shows the processor, command, and address to provide.

<table>
<thead>
<tr>
<th>Processor</th>
<th>Command and Address</th>
</tr>
</thead>
<tbody>
<tr>
<td>Cortex®-A53</td>
<td>mwr 0xfd1a0104 0</td>
</tr>
<tr>
<td>Cortex-R5</td>
<td>mwr 0xff5e023c 0x00008fde</td>
</tr>
<tr>
<td></td>
<td>mwr 0xff9a0000 0x00000218</td>
</tr>
</tbody>
</table>

Stopping and Starting Execution

- `con`: Start a command execution.
- `stop`: Stop a command execution.
Chapter 4: Using XSDB with QEMU

Using Breakpoints

You can add, list and remove breakpoints using the following commands:

- `bpadd`: Set a breakpoint.
  - Example: `bpadd -addr &<function-name>/<address>
- `bplist`: Lists all breakpoints.
- `bpremove`: Remove Breakpoint.
  - Example: `bpremove <breakpoint number>

For more information on using breakpoints see the “XSDB” topic in the Xilinx Software Development Kit help [Ref 2].

Reading and Writing to Memory Registers

You can read and write to the memory of the peripherals and the DDR and OCM memory in the debugger using the `mrd` and `mwr` commands.

**Note:** Stop the processors when performing memory operations.

**Commands**

- `mrd <addr>`: Read memory
- `mwr <addr> <value>`: Write to memory

**Limitations**

- Reset of processors command is not supported. Instead, QEMU can be restarted or use `system_reset` in the QEMU monitor.
- PL bitstream loading is not supported as shown in XSDB help.
- Changing memory maps is not supported.
- JTAG is not supported.
Co-Simulating With QEMU

Introduction

The Xilinx® QEMU can connect to external simulation environments to simulate larger and mixed simulation systems. This functionality allows you to model the Processing System (PS) in QEMU and the Programmable Logic (PL) design in an Verilog or VHDL (RTL) or SystemC simulator. It also allows you to connect multiple QEMU instances to each other. These processes are all connected through a communication protocol called Remote-Port (RP).

Remote-Port

The underlying mechanism that QEMU uses to connect to external simulation environments is through remote-port (RP). Remote-Port is a protocol/framework that uses sockets and shared-memory to communicate transactions and synchronize time between simulators.

libsystemctlm-soc

You do not need to interface directly with Remote-Port. Xilinx provides abstractions for SystemC/TLM-2.0 that encapsulate your SystemC/TLM-2.0 module, allowing it to connect to remote QEMU instances. These modules use Remote-Port. SystemC/TLM-2.0 users can, therefore, treat QEMU as any other standard SystemC/TLM-2.0 module.

These abstractions are in the libsystemctlm-soc repository [Ref 20].

For an example of wrapping your SystemC application, see the SystemC/TLM-2.0 co-simulation demonstration [Ref 21].
SystemC/TLM-2.0 Co-Simulation Demo

This demo is written using standard, compliant SystemC/TLM-2.0 APIs. You can run the demo on any SystemC/TLM-2.0 simulator that is compliant with Accellera Systems Initiative (ASI) industry standard specifications. This open source reference implementation of the simulator is tested and verified with Accellera’s standard.

The SystemC/TLM-2.0 co-simulation demonstration [Ref 21] provides an example project that demonstrates how to use libsystemctlm-soc to connect custom SystemC/TLM-2.0 and RTL models to QEMU.

The examples in this demonstration show how QEMU models the PS aspect of both Zynq®-7000 devices and Zynq UltraScale+™ devices while SystemC/TLM-2.0 and RTL models can be used to model the custom PL logic.

---

Co-Simulating with QEMU

Generating Required Device Trees

You need to instruct QEMU to co-simulate with other simulation environments. This can be done by editing the hardware device tree passed into QEMU using the `-hw-dtb` option.

**Note:** The hardware device tree is specific to QEMU, and should not be confused with Linux guest device tree.

For more information on this process, see the QEMU wiki [Ref 11] and the device tree repository [Ref 22].

Extra Command Line Options

- `-machine-path`: Specifies a directory where QEMU creates shared memory files and named UNIX sockets.

- `-sync-quantum`: Specifies the TLM synchronization quantum in nanoseconds (only used if `-icount` is enabled).

- `-icount`: Enables virtual instruction counter with $2^N$ clock ticks per instruction; enables aligning the host and virtual clocks or disables real-time CPU sleeping.
Useful starting values for icount:

- Zynq UltraScale+ MPSoC devices: 1
- Zynq-7000 devices: 7

As you lower the sync-quantum, the modeling speed decreases, but the accuracy increases. A general starting value is 100000.

**Example Extra Options**

```
-icount 1 -sync-quantum 100000
```

**Example QEMU Command**

```
qemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb <path to dtb build form qemu-devicetrees repo> \
-device loader,file=<proj_dir>/images/linux/bl31.elf,cpu=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-device loader,file=<proj_dir>/images/linux/u-boot..elf \
-tftp images/linux/ -machine-path <soc_dir> -icount 1 \ 
-sync-quantum 100000
```

**Note:** Use the same sync-quantum number for the other simulators.

**Example Simulator Command**

When the QEMU command shown above runs successfully, QEMU waits for SystemC/TLM-2.0 connection on the socket created in the directory that was supplied by the -machine-path argument. You must use the same socket path while running the SystemC application, as follows:

```
./demo-app unix:<socket path> <sync-quantum number>
```

More details on how to build and run the SystemC demo application are in systemctlm-cosim-demo repository [Ref 21].
Chapter 6

Using Boot Images on QEMU

Introduction

This section details some end-to-end image generation and QEMU boot flows.

The standard FSBL, ATF, U-Boot, and Linux boot flow is the example in each case.

This specific use case is similar to PetaLinux, and you can access it more simply using the PetaLinux tool suite. This section details the lower-level tools available for complex boot flows should they be required for greater customization.

This section does not cover building the boot products. See the Zynq® UltraScale+™ MPSOC Software Developers Guide (UG1137) [Ref 1] for information on how to build the following:

- FSBL
- U-Boot
- ARM trusted firmware (ATF)
- Linux image (Kernel plus RAM disk)
- Device tree binary (DTB)
- BOOT.bin

*Note:* (This is different from the hardware DTB that is passed to QEMU command lines.)

It is assumed all of these boot products are available. You can build all of the listed images in a standard PetaLinux project.

In the example, FSBL, ATF (*bl31.elf*), U-Boot runs on an A53 as shown in the BIF file. U-boot loads the Kernel onto A53.

The following run commands point to the `<proj_dir>/images/linux/` folder for all the boot products. You can also use a pre-built area.
Chapter 6: Using Boot Images on QEMU

Using SD for Boot

1. Create the SD image:

   dd if=/dev/zero of=qemu_sd.img bs=128M count=1
   mkfs.vfat -F 32 qemu_sd.img
   mcopy -i qemu_sd.img BOOT.BIN ::/
   mcopy -i qemu_sd.img Image ::/
   mcopy -i qemu_sd.img system.dtb ::/

2. Boot the image on QEMU:

   qemu-system-aarch64 -M arm-generic-fdt -nographic \
   -device loader,file=<proj_dir>/images/linux/ron_a53_fsbl.elf,cpu-num=0 \
   -dtb <proj_dir>/images/linux/zynqmp-qemu-arm.dtb \
   -device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
   -drive file=qemu_sd.img,if=sd,format=raw,index=0 \
   -boot mode=3

   Note: Even though the FSBL is packed in the SD image, it should be passed over the command line as a runnable ELF because QEMU does not contain the boot ROM.

Using QSPI for Boot

1. Create the QSPI boot image(s) for either or both single flash mode and dual parallel mode.

   Single Flash Mode

   dd if=/dev/zero of=qemu_qspi.bin bs=64M count=1
   dd if=BOOT.BIN of=qemu_qspi.bin bs=1 seek=0 conv=notrunc

   Dual Parallel Mode

   dd if=/dev/zero bs=128M count=1 of=qemu_qspi_tmp.bin
   dd if=BOOT.BIN of=qemu_qspi_tmp.bin bs=1 seek=0 conv=notrunc
   flash_strip_bw qemu_qspi_tmp.bin qemu_qspi_low.bin qemu_qspi_high.bin

2. Boot either the single or dual image(s) on QEMU.

   Single Flash Mode

   qemu-system-aarch64 -M arm-generic-fdt -nographic \
   -dtb <proj_dir>/images/linux/zynqmp-qemu-arm.dtb \
   -device loader,file=<proj_dir>/images/linux/zynqmp_a53_fsbl.elf,cpu-num=0 \
   -device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
   -drive file=qemu_qspi.bin,if=mtd,format=raw,index=0 \
   -boot mode=1
Chapter 6: Using Boot Images on QEMU

Dual Parallel Mode

```bash
qemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb <proj_dir>/images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=<proj_dir>/images/linux/zynqmp_a53_fsbl.elf,cpu=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-drive file=qemu_qspi_high.bin,if=mtd,format=raw,index=0\n-drive file=qemu_qspi_low.bin,if=mtd,format=raw,index=1
-boot mode=1
```

**TIP:** See the Storage Media for more information on flash_strip_bw.

---

**Using TFTP for Boot**

In the normal JTAG boot mode, petalinux-build command has the required images in the images/linux/ directory (or) a prebuilt path (for example: pre-built/linux/images/).

1. Point QEMU to the ./images/linux directory for tftp boot.
2. Use the following command for TFTP boot.

```bash
qemu-system-aarch64 -M arm-generic-fdt -nographic \
-dtb <proj_dir>/images/linux/zynqmp-qemu-arm.dtb \
-device loader,file=<proj_dir>/images/linux/bl31.elf,cpu-num=0 \
-device loader,addr=0xfd1a0104,data=0x8000000e,data-len=4 \
-device loader,file=<proj_dir>/images/linux/u-boot..elf \n-net nic -net nic -net nic -net nic \
-net user,t 
-tftp images/linux/
```

**IMPORTANT:** The /TFTP folder should contain the Image and the system.dtb.

**TIP:** Image Creation Steps for SD and EMMC are the same.
Chapter 6: Using Boot Images on QEMU

SD-Card Partitioning and Loading an Ubuntu-core File System

The following are the steps to create an SD card image.

1. Create a dummy container using `qemu-img`. The `qemu-img` is a utility used to create disk images for using with QEMU. It comes with Ubuntu packages and is also packaged with PetaLinux tools.

   `qemu-img create <Image name> <size>

   For example: The command, `qemu-img create sd.img 2G`, creates a 2G raw disk, with no partitions present.

2. Create the network back end with `qemu-nbd` and `nbd-client`.

   The `qemu-nbd` command creates a disk network block server making it an network block device, so that it can be connected with `nbd-client`.

   For example:
   
   - `qemu-nbd -p 4444 sd.img &` makes a network block device server, instructing the client to use port 4444 to connect.
   - `nbd-client localhost 4444 /dev/nbd0` connects to the created network block server. It can be accessed using the `/dev/nbd0` node.

3. Create partitions using `fdisk`, a text-based tool used to create partitions on a disk.

   Also, you could use `gparted`, a GUI-based partitioning tool.

   `fdisk /dev/nbd0` connects to the block device.

4. Create partitions, mostly two primary partitions are required.

   - One is bootable partition for keeping `BOOT.BIN`, `Image`, and the `system.dtb`.
   - Another is the partition for `rootfs`.

   A bootable flag can be toggled using `fdisk`. Ensure that there is least 100Mb in the bootable partition to have enough space.

5. Write the partition table and exit.
6. Format the partitions. Always format the bootable partition using FAT file systems. The second partition can be ext2/ext4.

For example:

```
mkfs.vfat -F 32 /dev/nbd0p1l formats the first partitions using FAT.
mkfs.ext4 /dev/nb0p2 formats the second partition using ext4.
```

7. Mount the partitions and copy the necessary files. Load the Image file without initramfs, by de-selecting the [Initial RAM filesystem and RAM disk (initramfs/initrd) support] option located in General Setup in menuconfig.

   **Note:** This step in not required if performing switch-root.

8. Extract the ubuntu-core available for arm64 in to the second partition.

   **TIP:** The ubuntu-core is located on the Ubuntu-Core release page.

9. Un-mount the partition and disconnect the nbd connection using the following command: nbd-client-d /dev/nbd0.

10. Ensure that the bootargs points to appropriate device for root, which is the following:

    ```
    root=/dev/mmcblk0p2 rw rootfstype=ext4.
    ```

---

### Adding New Devices to the Design

QEMU has limited device models; you can use the device model if it is available in QEMU source by directly adding the bindings into the device tree.

The following is an example of adding a SI57X I2C controlled clock generator to one of the I2C buses:

```c
&i2cswitch{
  i2c@03 {
    #address-cells = <1>;
    #size-cells = <0>;
    reg = <3>;
    si570_21 clock-generator@5e {
      compatible = "silabs,si57x";
      reg = <0x5d>;
      temperature-stability=<50>;
    };
  };
};
```
The compatible string is QEMU device, TYPE_NAME.

- `reg` represents the I2C address of the slave.
- `temperature-stability` is the property that the device expects to be set before device initialization happens.

See the Property structure in the device model to know what properties must be added.

An example of the Property structure for SI570 is as follows:

```c
static Property si57x_properties[] = {
    DEFINE_PROP_UINT16("temperature-stability", Si57xState, temp_stab, TEMP_STAB_50PPM),
    DEFINE_PROP_END_OF_LIST(),
```
Additional Resources and Legal Notices

Xilinx Resources
For support resources such as Answers, Documentation, Downloads, and Forums, see Xilinx Support.

Solution Centers
See the Xilinx Solution Centers for support on devices, software tools, and intellectual property at all stages of the design cycle. Topics include design assistance, advisories, and Vivado Design Suite Documentation.

Documentation Navigator and Design Hubs
Xilinx® Documentation Navigator provides access to Xilinx documents, videos, and support resources, which you can filter and search to find information. To open the Xilinx Documentation Navigator (DocNav):

- From the Vivado IDE, select Help > Documentation and Tutorials.
- On Windows, select Start > All Programs > Xilinx Design Tools > DocNav.
- At the Linux command prompt, enter docnav.

Xilinx Design Hubs provide links to documentation organized by design tasks and other topics, which you can use to learn key concepts and address frequently asked questions. To access the Design Hubs:

- In the Xilinx Documentation Navigator, click the Design Hubs View tab.
- On the Xilinx website, see the Design Hubs page.

Note: For more information on Documentation Navigator, see the Documentation Navigator page on the Xilinx website.
Appendix A: Additional Resources and Legal Notices

References

Zynq Documentation:
1. Zynq UltraScale+ MPSoC Software Developers Guide (UG1137)
2. Xilinx Software Developer Kit Help (UG782) (Includes XSDB)
3. OS and Libraries Document Collection (UG643)
4. Xilinx Third-Party Licensing Guide (UG763)
5. UltraScale Architecture and Product Overview (DS890)
7. Zynq UltraScale+ Registers User Guide (UG1087)
8. PetaLinux Tools
9. Vivado Design Suite Documentation
10. UltraScale Architecture Video Tutorials

Wiki Sites and GIT Hub Resources
11. QEMU wiki
12. Zynq MPSoC XEN wiki
13. GNU FTP
14. Zynq MPSoC Non-Secure Boot and Zynq MPSoC Secure Boot
15. ARM Information Center
16. Using GIT
17. GIT Hub
18. OpenAMP wiki
19. QEMU Linux Kernel Logbuf Extraction
20. libsystemctlmsoc Repository
21. SystemC/TLM 2.0 Co-simulation Demo Repository
22. Device Tree Repository
Please Read: Important Legal Notices

The information disclosed to you hereunder (the “Materials”) is provided solely for the selection and use of Xilinx products. To the maximum extent permitted by applicable law: (1) Materials are made available “AS IS” and with all faults, Xilinx hereby DISCLAIMS ALL WARRANTIES AND CONDITIONS, EXPRESS, IMPLIED, OR STATUTORY, INCLUDING BUT NOT LIMITED TO WARRANTIES OF MERCHANTABILITY, NON-INFRINGEMENT, OR FITNESS FOR ANY PARTICULAR PURPOSE; and (2) Xilinx shall not be liable (whether in contract or tort, including negligence, or under any other theory of liability) for any loss or damage of any kind or nature related to, arising under, or in connection with, the Materials (including your use of the Materials), including for any direct, indirect, special, incidental, or consequential loss or damage (including loss of data, profits, goodwill, or any type of loss or damage suffered as a result of any action brought by a third-party) even if such damage or loss was reasonably foreseeable or Xilinx had been advised of the possibility of the same. Xilinx assumes no obligation to correct any errors contained in the Materials or to notify you of updates to the Materials or to product specifications. You may not reproduce, modify, distribute, or publicly display the Materials without prior written consent. Certain products are subject to the terms and conditions of Xilinx’s limited warranty, please refer to Xilinx’s Terms of Sale which can be viewed at https://www.xilinx.com/legal.htm#tos; IP cores may be subject to warranty and support terms contained in a license issued to you by Xilinx. Xilinx products are not designed or intended to be fail-safe or for use in any application requiring fail-safe performance; you assume sole risk and liability for use of Xilinx products in such critical applications, please refer to Xilinx’s Terms of Sale which can be viewed at https://www.xilinx.com/legal.htm#tos.

AUTOMOTIVE APPLICATIONS DISCLAIMER

AUTOMOTIVE PRODUCTS (IDENTIFIED AS “XA” IN THE PART NUMBER) ARE NOT WARRANTED FOR USE IN THE DEPLOYMENT OF AIRBAGS OR FOR USE IN APPLICATIONS THAT AFFECT CONTROL OF A VEHICLE (“SAFETY APPLICATION”) UNLESS THERE IS A SAFETY CONCEPT OR REDUNDANCY FEATURE CONSISTENT WITH THE ISO 26262 AUTOMOTIVE SAFETY STANDARD (“SAFETY DESIGN”). CUSTOMER SHALL, PRIOR TO USING OR DISTRIBUTING ANY SYSTEMS THAT INCORPORATE PRODUCTS, THOROUGHLY TEST SUCH SYSTEMS FOR SAFETY PURPOSES. USE OF PRODUCTS IN A SAFETY APPLICATION WITHOUT A SAFETY DESIGN IS FULLY AT THE RISK OF CUSTOMER, SUBJECT ONLY TO APPLICABLE LAWS AND REGULATIONS GOVERNING LIMITATIONS ON PRODUCT LIABILITY.

AMBA, AMBA Designer, ARM, ARM1176JZ-S, CoreSight, Cortex, PrimeCell, and MPCore are trademarks of ARM in the EU and other countries. MATLAB and Simulink are registered trademarks of The MathWorks, Inc. PCI, PCI Express are trademarks of PCI-SIG and used under license.

© Copyright 2015-2017 Xilinx, Inc. Xilinx, the Xilinx logo, Artix, ISE, Kintex, Spartan, Virtex, Vivado, Zynq, and other designated brands included herein are trademarks of Xilinx in the United States and other countries. All other trademarks are the property of their respective owners.