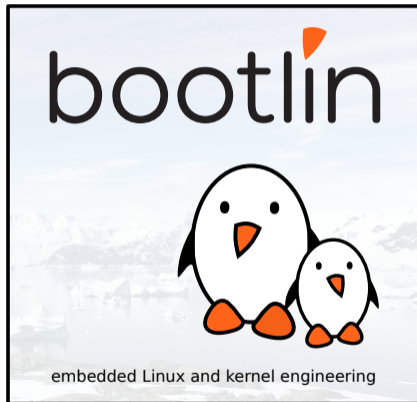




Getting started with Buildroot

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Corrections, suggestions, contributions and translations are welcome!





- ▶ CTO/Embedded Linux engineer at Bootlin
 - ▶ Embedded Linux **expertise**
 - ▶ **Development**, consulting and training
 - ▶ Strong open-source focus
 - ▶ Freely available training materials
- ▶ Co-maintainer of **Buildroot**
- ▶ Living in **Toulouse**, France



Pre-built
binary Linux
distributions

- + Readily available
 - Large, usually 100+ MB
 - Not available for all architectures
 - Not easy to customize
 - Generally require native compilation



Manual
system
building

- + Smaller and flexible
- Very hard to handle cross-compilation and dependencies
- Not reproducible
- No benefit from other people's work



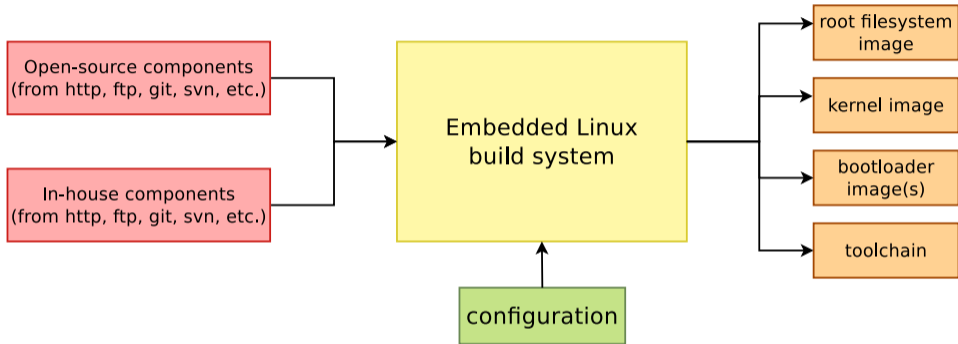
Building an embedded Linux system

Embedded
Linux
build systems

- + Small and flexible
- + Reproducible, handles cross-compilation and dependencies
- + Available for virtually all architectures
 - One tool to learn
 - Build time



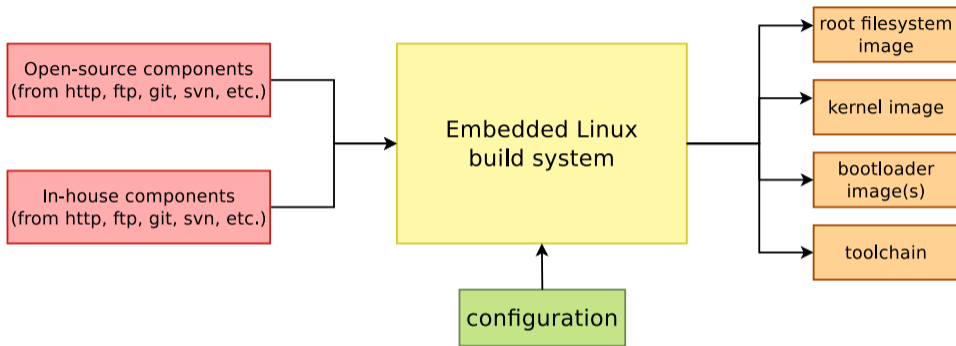
Embedded Linux build system: principle



- ▶ Building from source → lot of flexibility



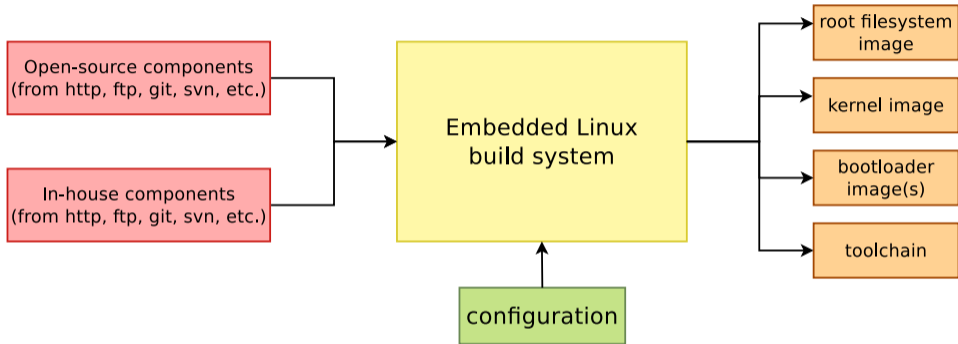
Embedded Linux build system: principle



- ▶ Building from source → lot of flexibility
- ▶ Cross-compilation → leveraging fast build machines



Embedded Linux build system: principle



- ▶ Building from source → lot of flexibility
- ▶ Cross-compilation → leveraging fast build machines
- ▶ Recipes for building components → easy



Buildroot at a glance

- ▶ Is an **embedded Linux build system**, builds from source:
 - ▶ cross-compilation toolchain
 - ▶ root filesystem with many libraries/applications, cross-built
 - ▶ kernel and bootloader images
- ▶ **Fast**, simple root filesystem in minutes
- ▶ **Easy** to use and understand: kconfig and make
- ▶ **Small** root filesystem, default 2 MB
- ▶ More than **2500 packages** available
- ▶ Generates filesystem images, not a distribution
- ▶ Vendor neutral
- ▶ Active community, stable releases every 3 months
- ▶ Started in 2001, oldest still maintained build system
- ▶ <http://buildroot.org>





Today's lab

- ▶ **Step 1:** do a minimal build for the PocketBeagle, with just a bootloader, Linux kernel and minimal root filesystem. Generate a ready-to-use SD card image.
- ▶ **Step 2:** enable network over USB and SSH connectivity using Dropbear. Shows how to use a rootfs overlay and how to add packages.
- ▶ **Step 3:** customize the Linux kernel configuration, compile a small application that uses the GPIO, first manually, and then using a new Buildroot package
- ▶ **Don't hesitate to request help and ask questions!**

Step 1

Minimal build for the PocketBeagle



Cloning Buildroot

```
$ git clone git://git.busybox.net/buildroot
$ cd buildroot
```

Note: if cloning is too slow, you can use `buildroot.tar.xz` from the USB stick.

Create a branch based on the latest LTS

```
$ git checkout -b ede-lab 2019.02.6
```

Get one U-Boot integration improvement

We need to cherry-pick one more recent commit, to be able to pass arbitrary variables to the U-Boot build:

```
$ git cherry-pick cc151c3993090a52d1fef8532f52d74ee6d924c9
```



Starting the configuration

- ▶ Buildroot has a large number of pre-defined configuration files for popular HW platforms:
`make list-defconfigs`
- ▶ For learning purposes, we are going to create our own configuration from scratch for the Pocket Beagle

```
$ make menuconfig
```

```
/home/thomas/projets/buildroot/.config - Buildroot 2018.02 Configuration

Buildroot 2018.02 Configuration
Arrow keys navigate the menu. <Enter> selects submenus ---> (or empty
submenus ----). Highlighted letters are hotkeys. Pressing <Y> selects a
feature, while <N> excludes a feature. Press <Esc><Esc> to exit, <?> for
Help, </> for Search. Legend: [*] feature is selected [ ] feature is

Target options --->
Build options --->
Toolchain --->
System configuration --->
Kernel --->
Target packages --->
Filesystem images --->
Bootloaders --->
Host utilities --->
Legacy config options --->

<Select> < Exit > < Help > < Save > < Load >
```



- ▶ **Target architecture:** *ARM (little endian)*
- ▶ **Target architecture variant:** *Cortex-A8*



- ▶ **Global patch directories:** `board/e-ale/pocketbeagle/patches/`
- ▶ We will need to apply one patch to Linux to improve the PocketBeagle Device Tree description. Buildroot automatically applies patches from *global patch directories* subfolders named after Buildroot packages.
- ▶ We will add those patches once we are done with the configuration.



- ▶ **Toolchain type:** *External toolchain*
- ▶ Buildroot supports:
 - ▶ *Internal toolchain:* Buildroot builds a cross-compilation toolchain from scratch. Flexible, but additional build time needed.
 - ▶ *External toolchain:* Buildroot downloads and uses a pre-built cross-compilation toolchain.
- ▶ On ARM, the ARM-provided toolchain (*Arm ARM 2018.11*) is automatically chosen by default as an external toolchain.



menuconfig: System configuration

- ▶ **System host name:** `ede`
- ▶ **System banner:** `Hello EDE`
- ▶ **Init system:** keep the default of `Busybox`, Buildroot also supports `systemd`, `sysvinit`.
- ▶ **/dev management:** keep the default of `devtmpfs`, Buildroot also supports `udev`, `systemd`, etc.



- ▶ Enable **Linux Kernel**
- ▶ **Kernel version:** *Custom version*
- ▶ **Kernel version:** *5.3*
- ▶ No need to specify a path to patches, we are already using the *global patch directory mechanism*
- ▶ **Defconfig name:** `omap2plus`
- ▶ Enable **Build a Device Tree Blob**
- ▶ **In-tree Device Tree Source file names:** `am335x-pocketbeagle`



- ▶ Since **Busybox** is chosen as init system, it is already forcefully selected.
- ▶ **Busybox** provides all we need for a minimal Linux system, so no need to enable other packages.
- ▶ You can have a look at the choice of 2500+ packages, we'll use a few more in the next steps.



- ▶ Enable **ext2/3/4 root filesystem**, and select the `ext4` variant
- ▶ Disable **tar the root filesystem**



- ▶ Enable **U-Boot**
- ▶ **Build system:** *Kconfig*. We use a modern U-Boot!
- ▶ **Custom version:** *2019.10*
 - ▶ Using a fixed version instead of the default version allows to ensure our build will always build that specific version we have tested.
- ▶ **Board defconfig:** `am335x_evm`
- ▶ **U-Boot binary format:** `u-boot.img`. Indeed, U-Boot itself will be the second stage bootloader.
- ▶ Enable **U-Boot needs dtc**
- ▶ Enable **Install U-Boot SPL binary image**. This enables building the first stage bootloader.
- ▶ Set **U-Boot SPL/TPL binary image name** to *MLO*, the name required on AM335x.
- ▶ Set **Custom make options** to `DEVICE_TREE=am335x-pocketbeagle`



Adding the patches

- ▶ Before starting the build, we need to add the Linux kernel and U-Boot patches needed to support the Pocket Beagle.
- ▶ Create the folder `board/ede/pocketbeagle/patches/` that we referenced as a *global patch directory*
- ▶ Copy to this folder the contents of the `patches/` folder of the USB stick.

```
$ tree board/e-ale/pocketbeagle/  
board/e-ale/pocketbeagle/  
- patches  
  - linux  
    - 0001-ARM-dts-describe-the-MCP23S18-connected-on-Pocket-Be.patch
```



Pre-populating the download folder

- ▶ By default, Buildroot caches all the downloaded tarballs in `d1/`
- ▶ In order to speed up the build process and avoid long download times, we are going to pre-populate this download folder.
- ▶ Copy the `d1/` folder from the USB stick to the Buildroot source directory.



Doing the build

To run the build, do:

```
make 2>&1 | tee build.log
```

This allows to complete log of the build output.

Alternatively, there is a wrapper script provided by Buildroot:

```
$ ./utils/brmake
```

The build will take a while (14-15 minutes on your instructor machine), because the `omap2plus_defconfig` kernel configuration has a LOT of features enabled.



During the build: exploring the build output

- ▶ All the output produced by Buildroot is stored in `output/`
- ▶ Can be customized using `O=` for out-of-tree build
- ▶ `output/` contains
 - ▶ `output/build`, with one sub-directory for the source code of each component
 - ▶ `output/host`, which contains all native utilities needed for the build, including the cross-compiler
 - ▶ `output/host/<tuple>/sysroot`, which contains all the headers and libraries built for the target
 - ▶ `output/target`, which contains *almost* the target root filesystem
 - ▶ `output/images`, the final images
- ▶ `dl/` contains downloaded artifacts, can be customized by the `BR2_DL_DIR` env. variable



During the build: summarized build process

1. Check core dependencies
2. For each selected package, after taking care of its dependencies: download, extract, patch, configure, build, install
 - ▶ To `target/` for target apps and libs
 - ▶ To `host/<tuple>/sysroot` for target libs
 - ▶ To `host/` for native apps and libs
 - ▶ Filesystem skeleton and toolchain are handled as regular packages
3. Copy *rootfs overlay*
4. Call *post build* scripts
5. Generate the root filesystem image
6. Call *post image* scripts



Build finished: what do we have ?

- ▶ `ls output/images`
 - ▶ `MLO`, the first stage bootloader
 - ▶ `u-boot.img`, the second stage bootloader
 - ▶ `zImage`, the Linux kernel image
 - ▶ `am335x-pocketbeagle.dtb`, the Linux kernel Device Tree Blob
 - ▶ `rootfs.ext4`, the root filesystem image
- ▶ → this doesn't give us a bootable SD card image
- ▶ Let's create one using *genimage*



SD card image with genimage: intro

- ▶ Tool from *Pengutronix*
- ▶ Given a configuration file, creates a block device image with a partition table and filesystems
- ▶ Need to be called at the very end of the build: we will run it in a *post image* script
- ▶ Our SD card image will have:
 - ▶ One FAT partition with bootloader, kernel image and Device Tree
 - ▶ One ext4 partition with the root filesystem



SD card image with genimage: configuration

- ▶ In `menuconfig`
 - ▶ **System configuration** → **Custom scripts to run after creation filesystem images**, set to `board/ede/pocketbeagle/post-image.sh`
 - ▶ **Host utilities**, enable `host genimage`, `host mtools`, `host dosfstools`. This will make sure those tools are built for the build machine
- ▶ Copy `genimage.cfg`, `post-image.sh` and `uEnv.txt` from the USB stick to `board/ede/pocketbeagle`
 - ▶ `genimage.cfg`, *genimage* configuration file, have a look at it
 - ▶ `post-image.sh`, shell script that calls *genimage* with the appropriate arguments
 - ▶ `uEnv.txt`, U-Boot script to boot the system



SD card image: building and booting

- ▶ Start the build again with `make`
- ▶ It will only build a few additional tools (genimage, etc.) and produce the SD card image
- ▶ The SD card image will be `output/images/sdcard.img`
- ▶ Transfer to your SD card

```
$ sudo dd if=output/images/sdcard.img of=/dev/mmcblk0 bs=1M
```

- ▶ Insert the SD card in the PocketBeagle, and boot it (serial port at 115200 bps)
- ▶ Login as `root`, no password.
- ▶ System weights 18.4 MB, of which 12.1 MB are kernel modules



Storing our Buildroot configuration persistently

- ▶ Our current configuration is stored in `.config`
 - ▶ Will be lost upon `make distclean`
 - ▶ Or if we create a different configuration for a different project
- ▶ Save it as a *defconfig* file:

```
$ make BR2_DEFCONFIG=configs/ede_pocketbeagle_defconfig savedefconfig
```

- ▶ And have a look at `configs/ede_pocketbeagle_defconfig`

Step 2

Network connectivity over USB: SSH



Network configuration: using a rootfs overlay

- ▶ To enable network over USB, we will need:
 - ▶ An init script that loads the relevant kernel modules and uses *configs* to set up the USB gadget device. It will be installed as `/etc/init.d/S30usb gadget`.
 - ▶ A customized `/etc/network/interfaces` file
- ▶ We will use a **root filesystem overlay** to add those customizations to the root filesystem.
- ▶ In `menuconfig`
 - ▶ **System configuration**, set **Root filesystem overlay directories** to `board/ede/pocketbeagle/overlay/`
 - ▶ **System configuration**, set **Root password** to a non-empty one
 - ▶ **Target packages, Networking applications**, enable `dropbear`
- ▶ Copy the contents of `overlay/` from the USB stick to `board/ede/pocketbeagle/overlay/`, and of course, have a look at it!



Using the network

- ▶ Restart the build

```
$ make 2>&1 | tee build.log
```

- ▶ Reflash the SD card
- ▶ Boot
- ▶ On your PC, configure the new network interface with the IP address 192.168.42.1
- ▶ If you're using network manager:

```
$ nmcli con add con-name buildroot-target type ethernet \  
  ifname enp57s0u1u6u4 ip4 192.168.42.1/24
```

- ▶ SSH into the board, from your PC:

```
$ ssh root@192.168.42.2
```

Step 3

Developing an application



Adding libgpiod and GPIO support

- ▶ We are going to write a demo application based on the `libgpiod` library, to manipulate GPIOs.
- ▶ Let's first add this library in your Buildroot configuration, in `menuconfig`, enable `BR2_PACKAGE_LIBGPIOD` and its tools.
- ▶ We also need to enable the GPIO kernel driver, using the option `CONFIG_PINCTRL_MCP23S08`. To do this, run `make linux-menuconfig`, which will open up the Linux kernel *menuconfig*, and enable the driver.
 - ▶ Note: this change would be lost during a `make clean`. To make it persistent, using a configuration file fragment would be appropriate.
- ▶ Run `make` to rebuild the system, reflash on the SD card, and reboot



- ▶ We can list the list the GPIO chips using `gpiodetect`:

```
# gpiodetect
```

- ▶ We can use the GPIOs using `gpioset`:

```
# gpioset gpiochip4 0=0  
# gpioset gpiochip4 1=0  
# gpioset gpiochip4 1=1  
# gpioset gpiochip4 0=1
```



Cross-compiling a simple application

- ▶ Let's now build a simple application to see how to use the Buildroot cross-compiler
- ▶ Copy the `ede-gpio-app` folder from the USB stick side-by-side with Buildroot:

```
- buildroot/  
- ede-gpio-app/  
  - ede-gpio-app.c  
  - Makefile
```

- ▶ To build the application:

```
$ ./output/host/bin/arm-linux-gnueabi-hf-gcc -o ede-gpio-app \  
  ../ede-gpio-app/ede-gpio-app.c -lgpiod
```



Running the application on the target

- ▶ Copy it to the target:

```
$ scp ede-gpio-app root@192.168.42.2:
```

- ▶ And run it:

```
# ./ede-gpio-app
```



Buildroot package for our application

- ▶ Building manually is fine for quick experiments, but we definitely want the build process to be fully automated by Buildroot.
- ▶ In order to do this, one can create new **packages** for the different applications/libraries that should be compiled and installed in the target root filesystem.
- ▶ A package in Buildroot consists of:
 - ▶ `package/<pkg>/Config.in`, describing the configuration options, in the *kconfig* syntax
 - ▶ `package/<pkg>/<pkg>.mk`, describing how to download, build and install the package, written in *make*
 - ▶ `package/<pkg>/<pkg>.hash`, containing hashes to validate that the downloaded have the expected contents
 - ▶ `package/<pkg>/*.patch`, patches to apply to the package source code, if needed



package/ede-gpio-app/Config.in

```
config BR2_PACKAGE_EDE_GPIO_APP
    bool "ede-gpio-app"
    depends on BR2_TOOLCHAIN_HEADERS_AT_LEAST_4_8 # libgpiod
    select BR2_PACKAGE_LIBGPIOD
    help
        This is the EDE GPIO demo application.

comment "ede-gpio-app needs kernel headers >= 4.8"
    depends on !BR2_TOOLCHAIN_HEADERS_AT_LEAST_4_8
```



Creating the package: including Config.in

package/Config.in

```
...  
    source "package/ede-gpio-app/Config.in"  
...
```

You can run `make menuconfig`, and see that your new option is there!



Creating the package: ede-gpio-app.mk

package/ede-gpio-app/ede-gpio-app.mk

```
#####  
#  
# ede-gpio-app  
#  
#####  
  
EDE_GPIO_APP_SITE = $(TOPDIR)/../ede-gpio-app  
EDE_GPIO_APP_SITE_METHOD = local  
EDE_GPIO_APP_DEPENDENCIES = libgpiod  
  
define EDE_GPIO_APP_BUILD_CMDS  
    $(TARGET_MAKE_ENV) $(MAKE) $(TARGET_CONFIGURE_OPTS) -C $(@D)  
endef  
  
define EDE_GPIO_APP_INSTALL_TARGET_CMDS  
    $(TARGET_MAKE_ENV) $(MAKE) $(TARGET_CONFIGURE_OPTS) -C $(@D) \  
        DESTDIR=$(TARGET_DIR) install  
endef  
  
$(eval $(generic-package))
```



Creating the package: using it

- ▶ Enable your new package in `make menuconfig`
- ▶ Run the build with `make`
- ▶ Reflash your SD card and reboot
- ▶ Your new application is in `/usr/bin` on the target



- ▶ Extensive manual: <https://buildroot.org/downloads/manual/manual.html>
- ▶ 3-day training course, with freely available materials:
<https://bootlin.com/training/buildroot/>
- ▶ Mailing list: <http://lists.busybox.net/pipermail/buildroot/>
- ▶ IRC channel: `buildroot` on Freenode