

I'm not a robot




```
FileStream WriteAsyncBeginWrite FileStream stream = new FileStream("in.txt", FileMode.OpenOrCreate, FileAccess.ReadWrite, FileShare.ReadWrite, 1024, FileOptions.Asynchronous);byte[] byteData = new byte[80961024 * 4];Task task = stream.WriteAsync(byteData, 0, byteData.Length);FileStreamStreamWriterStreamWriterWriteAsyncFileStream stream = new FileStream("in.txt", FileMode.OpenOrCreate,FileAccess.ReadWrite, FileShare.ReadWrite, 1024, FileOptions.Asynchronous); char[] byteData = new char[80961024 * 4];var sw = new StreamWriter(stream);Task task = sw.WriteAsync(byteData, 0, byteData.Length);FileStreamStreamWriterStreamWriterWriteAsyncFileStream stream = new FileStream("in.txt", FileMode.OpenOrCreate,FileAccess.ReadWrite, FileShare.ReadWrite, 1024, FileOptions.Asynchronous); char[] byteData = new char[80961024 * 4];var sw = new StreamWriter(stream);Task task = sw.WriteAsync(byteData, 0, byteData.Length);
protected memory. This is often an indication that other memory is corruptat Microsoft.Win32.Native.CoTaskMemFree(IntPtr ptr) at ... C#C++ ... Ma 2019-07-22 10:50:36 ... liangliang_2006 2007-08-09 10:38:16 teechart7builder6Access violation at address in module 'Project1.exe' Read of address 000000.TChart50cpu985121G512 ... YJZ_0305
2006-03-19 03:11:40 FC4FortranFortran ... 2017-01-23 10:17:49 Unix.P73writen() if ( (nwritten = write(fd, ptr, nleft)) addr=0xF800025C, data=0x00000001 =====BOOT_MODE REG = 0x00000001WARNING: [Xicom 50-100] The current boot mode is QSPI.If flash programming fails, configure device for JTAG boot mode and try again.===== mrd->addr=0xF8007080, data=0x30800100 ===== mrd->addr=0xF8000B18, data=0x00000000 =====Downloading FSBL...Running FSBL...Finished running FSBL===== mrd->addr=0xF8000110, data=0x000FA220 =====READ: ARM_PLL_CFG (0xF8000110) = 0x000FA220===== mrd->addr=0xF8000100, data=0x00028008
=====READ: ARM_PLL_CTRL (0xF8000100) = 0x00028008===== mrd->addr=0xF8000120, data=0x1F000200 =====READ: ARM_CLK_CTRL (0xF8000120) = 0x1F000200===== mrd->addr=0xF8000118, data=0x000FA240 =====READ: IO_PLL_CFG (0xF8000118) = 0x000FA240===== mrd->addr=0xF8000108, data=0x00030008
=====READ: IO_PLL_CTRL (0xF8000108) = 0x00030008Info: Remapping 256KB of on-chip-memory RAM memory to 0xFFFC0000,===== mrd->addr=0xF8000008, data=0x00000000 ===== mwr->addr=0xF8000008, data=0x0000DF0D =====MASKWRITE: addr=0xF8000008, mask=0x0000FFFF, newData=0x0000DF0D===== mwr->addr=0xF8000010, data=0x000001FF ===== mrd->addr=0xF8000004, data=0x00000000 ===== mwr->addr=0xF8000004, data=0x0000767B =====MASKWRITE: addr=0xF8000004, mask=0x0000FFFF, newData=0x0000767BProblem in running ubootFlash programming initialization failed.ERROR: Flash Operation Failed ...
jiangrains 2009-07-21 05:58:59 creatfdwritereadread error !: Bad file descriptor #include#include#includeint main(){ int fd; if(fd=creat("file1.c",S_IRWXU)==-1){ perror("creat error !"); exit(0); }else{ /int fd=open("file1.c",O_RDWR); if(write(fd,"ni hao !",sizeof("ni hao !"))==-1){ perror("write error !"); exit(0); }else{ if(write(fd,"jiangdunchuan !",sizeof("jiangdunchuan !"))==-1){ perror("error !"); exit(0); } printf("successful !"); } char buff[100]; /int fd2=open("file1.c",O_RDWR); if(read(fd,buff,100)==-1){ perror("read error !"); exit(0); }else{ printf("%s",buff); printf("ok"); } } return 0; } read error !: Bad file descriptorfd2readread(fd2,buff,100)==-1 ...
cwwei20122012 2015-08-13 10:13:30 init(ioctl:0can0 can_ifindex = 7set can0 sock loopback unable:0set can0 do not receiver own message:0bind can0 sock:0send(sending-->id:11, dlc:1, data:20 idsend fail! CAN-----void CanComm::init(void)(int ret,struct sockaddr_can addr,struct ifreq ifr; s = socket(PF_CAN, SOCK_RAW, CAN_RAW);if(s == -1){ DEBUG printf("invalid socket");exit(1);}strcpy(ifr_name, "can0");ret = ioctl(s, SIOCGIFINDEX, &ifr); DEBUG printf("ioctl:%d", ret); DEBUG printf("can0 can_ifindex = %x",ifr.ifr_ifindex);addr.can_family = AF_CAN;addr.can_ifindex = ifr.ifr_ifindex; int loopback = 0; /* 0 = disabled, 1 = enabled (default) */ret = setsockopt(s, SOL_CAN_RAW, CAN_RAW_LOOPBACK, &loopback, sizeof(loopback)); // Setting loopback options DEBUG printf("set can0 sock loopback unable:%d", ret); int recv_own_msgs = 0; /* 0 = disabled (default), 1 = enabled */ret = setsockopt(s, SOL_CAN_RAW, CAN_RAW_RECV_OWN_MSGS, &recv_own_msgs, sizeof(recv_own_msgs));printf("set can0 do not receiver own message:%d", ret); bind(s, (struct sockaddr *)&addr, sizeof(addr)); DEBUG printf("bind can0 sock:%d", ret); void CanComm::send(void){struct can_frame frame; frame.can_id = canid;frame.can_dlc = 1;frame.data[0] = 20; _DEBUG printf("sending-->id:%d, dlc:%d, data:%d", frame.can_id,frame.can_dlc,frame.data[0]);int nbytes = write(s, &frame, sizeof(frame));if(nbytes != sizeof(frame))_DEBUG printf("send fail!");} ...
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