ECSE 426 Final Project Report

# SPI Protocol Implementation

The Texas Instrumentals CC2500 Low-Cost Low-Power 2.4 GHz RF Transceiver was used to communicate between two microcontrollers. The RF chip was connected to the microcontroller via serial peripheral interface (SPI). Software had to be written to implement the SPI communication.

On the grand scale, the SPI protocol functions using as illustrated by the following diagram (Figure #):



Figure : SPI Lines

The master controls the clock (SCK). CSn is the chip select line (active low), while MOSI and MISO are the lines used for sending and receiving data.  
These lines correspond to specific pins on the RF chip and the microcontroller, and they had to be physically connected using wires. Figure # illustrates how the pins had to be connected:  


Figure : SPI pins mapping on the iNemo and the CC2500

The CC2500 chip had certain specifications and requirements for SPI communication. They were outlined in “Design Note DN503” provided on the Texas Instruments website.

The document specified some critical information, such as the maximum operating frequency, the reset procedure, and how communication functioned in general (e.g. how to perform read/write operations, how to send strobe commands and how to interpret the status byte that was sent back after each write).

Using this information, it was possible to determine how the software was supposed to function. For example, it was possible to determine the SPI clock frequency. Writing data to the SPI bus (outputting via MOSI) was only allowed when the chip is ready, that is, when MISO is low. Consequently, the code had to check for this condition before performing any read or write operations. CSn had to be pulled low before any operation, and pushed high only after the operation was complete.

It was necessary to validate the code to ensure that it conforms to the specifications. This was achieved using an oscilloscope during the initial stages of implementation and by observing the produced waveforms. This allowed us to check for:

* The Clock operation
* The CSn
* MISO and MOSI

Some bugs were found and eliminated thanks to this debugging approach. For example, it was observed that CSn was going high before MISO finished its operation. After some tweaking of the code (checking flag statuses), proper operation was eventually achieved.

Once this step was complete, writing to and reading from registers on the RF chip was validated. This was done by simply writing to a register and checking back the value, ensuring that it is the same. The status register was also checked.

**RF Communication**

The ultimate goal was to perform RF communication between the two microcontrollers. To do so, the CC2500 chip had to be connected, initialized and properly configured in order to perform its function.

The “CC2500: Low-Cost Low-Power 2.4 GHz RF Transceiver” document provided by Texas Instruments was referenced to understand and implement RF communication using the RF chip.

The chip has several states of operation. They are outlined in Figure #:



Figure : State Diagram of the CC2500

Switching between states was done by sending command strobes to the chip via SPI.  
When in transmit mode, the chip would broadcast the contents of the FIFO buffer. When in receive mode, it would store received packets inside the FIFO buffer. The size of the buffer is 64 bytes. Physically, it is the same buffer shared for read and for write, with the size of each specified in the configuration.

Proper handling of underflow and overflow had to be implemented. When in any of those modes, the buffer had to be explicitly flushed, after which the state would change to idle.

Before sending or receiving any data, the oscillator would have to stabilize. The status byte indicates the state, and it can be checked to ensure the state is the desired one.

The values of the configuration registers had to be tweaked for the group’s needs. More specifically, the packet size, the channel, and the operations to perform when done sending/receiving had to be specified. The interrupt was also configured.

For the purposes of this project, one byte was enough to encode all the needed information for communication between the two microcontrollers. For simplicity and reliability, the same byte was sent 32 times, and the mode of the received bytes was taken to determine the correct byte. The packet size chosen was therefore 32 bytes. When a packet was received, the interrupt line would be raised. For simplicity, MISO was used as an interrupt line. This was possible, because whenever an interrupt was raised, CSn would have to be high. Hence, as long as this condition was checked, the line functioned as an interrupt line.

Testing was performed by having one of the chips broadcast and the other one listen. The values stored in the buffer were then examined to confirm that the correct byte was received. Sometimes one or two bytes would be wrong, but generally speaking the results were very consistent. The interrupt line functioned flawlessly and would be raised even when just a single packet was sent.

# Game Protocol

The project required two-way communication between the two microcontrollers. For this purpose, a protocol had to be designed and implemented.

Several commands were defined. They were designed to use one hot encoding, and were the bytes sent and received via the RF chip.

Each microcontroller had the ability to initiate communication. As soon as one microcontroller initiates communication, the other microcontroller would enter a complementary state to that of the initiator. In broader terms, there were two branches to the protocol – one for the initiator and one for the slave. This behaviour was implemented by having both microcontrollers stay in an idle/wait state. While in the wait state, the microcontrollers would both do the following:

* Wait for a Communication Request
* Wait for a Sync Gesture.

The one that gets the Sync Gesture first is the one that becomes the communication initiator, and the one that sends a communication request. The one that receives a communication request becomes the slave.

At every stage, the microcontroller would have some kind of timer for fallback. If the expected action does not occur within a specified period of time, the microcontroller would exit the loop and fall back to its idle/wait state. As an example, when a communication request is sent, the expected response is a communication acknowledge. Therefore, the microcontroller would enter a loop, continuously sending the request and listening for the acknowledge, but if no acknowledge is received within a certain amount of time, it would go back to the wait state.

Gestures are acquired independently and in parallel with the communication. Latching for a move begins as soon as the communication begins, and if no move has been acquired by the time it is needed, the microcontroller continues to check until a certain timeout.

In general, it can be said that the two microcontrollers are taking turns in sending each other commands. There is the initial handshake stage, where the initiator sends in a request and the slave sends back an acknowledge. There is the move and result exchange stage, where the slave sends its move to the initiator, the initiator compares it with its own, determines the result, and sends the result to the slave. Finally, there’s the terminal stage, during which the slave sends back the result it received from the master and the master sends an acknowledge. The general flow of the communication is illustrated in Figure #:



Figure : Communication Flow