



# **MPLAB<sup>®</sup> C18 C COMPILER LIBRARIES**

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# MPLAB® C18 C Compiler Libraries

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## Preface

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### NOTICE TO CUSTOMERS

All documentation becomes dated, and this manual is no exception. Microchip tools and documentation are constantly evolving to meet customer needs, so some actual dialogs and/or tool descriptions may differ from those in this document. Please refer to our web site ([www.microchip.com](http://www.microchip.com)) to obtain the latest documentation available.

Documents are identified with a “DS” number. This number is located on the bottom of each page, in front of the page number. The numbering convention for the DS number is “DSXXXXXA”, where “XXXXX” is the document number and “A” is the revision level of the document.

For the most up-to-date information on development tools, see the MPLAB® IDE on-line help. Select the Help menu, and then Topics to open a list of available on-line help files.

## INTRODUCTION

The purpose of this document is to provide detailed information on the libraries and precompiled object files that may be used with Microchip's MPLAB® C18 C Compiler.

## DOCUMENT LAYOUT

The document layout is as follows:

- **Chapter 1: Overview** – describes the libraries and precompiled object files available.
- **Chapter 2: Hardware Peripheral Functions** – describes each hardware peripheral library function.
- **Chapter 3: Software Peripheral Library** – describes each software peripheral library function.
- **Chapter 4: General Software Library** – describes each general software library function.
- **Chapter 5: Math Library** – discusses the math library functions.
- **Glossary** – A glossary of terms used in this guide.
- **Index** – Cross-reference listing of terms, features and sections of this document.

## CONVENTIONS USED IN THIS GUIDE

This manual uses the following documentation conventions:

### DOCUMENTATION CONVENTIONS

Description	Represents	Examples
<b>Arial font:</b>		
Italic characters	Referenced books	<i>MPLAB® IDE User's Guide</i>
<b>Courier font:</b>		
Plain Courier	Sample source code	<code>#define START</code>
	Filenames	<code>autoexec.bat</code>
	File paths	<code>c:\mcc18\h</code>
	Keywords	<code>_asm, _endasm, static</code>
	Command-line options	<code>-Opa+, -Opa-</code>
Italic Courier	A variable argument	<i>file.o</i> , where <i>file</i> can be any valid filename
<code>0bnnnn</code>	A binary number where <i>n</i> is a binary digit	<code>0b00100, 0b10</code>
<code>0xnnnn</code>	A hexadecimal number where <i>n</i> is a hexadecimal digit	<code>0xFFFF, 0x007A</code>
Square brackets [ ]	Optional arguments	<code>mcc18 [options] file [options]</code>
Curly brackets and pipe character: {   }	Choice of mutually exclusive arguments; an OR selection	<code>errorlevel {0 1}</code>
Ellipses...	Replaces repeated text	<code>var_name [, var_name...]</code>
	Represents code supplied by user	<code>void main (void) { ... }</code>

## RECOMMENDED READING

For more information on included libraries and precompiled object files for the compilers, the operation of MPLAB IDE and the use of other tools, the following are recommended reading.

### **readme.c18**

For the latest information on using MPLAB C18 C Compiler, read the readme.c18 file (ASCII text) included with the software. This readme file contains update information that may not be included in this document.

### **readme.xxx**

For the latest information on other Microchip tools (MPLAB IDE, MPLINK™ linker, etc.), read the associated readme files (ASCII text file) included with the software.

### **MPLAB® C18 C Compiler Getting Started Guide (DS51295)**

Describes how to install the MPLAB C18 compiler, how to write simple programs and how to use the MPLAB IDE with the compiler.

### **MPLAB® C18 C Compiler User's Guide (DS51288)**

Comprehensive guide that describes the operation and features of Microchip's MPLAB C18 C compiler for PIC18 devices.

### **MPLAB® IDE Quick Start Guide (DS51281)**

Describes how to set up the MPLAB IDE software and use it to create projects and program devices.

## **MPASM™ Assembler, MPLINK™ Object Linker, and MPLIB™ Object Librarian User's Guide (DS33014)**

Describes how to use the Microchip PICmicro® microcontroller (MCU) assembler (MPASM), linker (MPLINK) and librarian (MPLIB).

## **PICmicro® 18C MCU Family Reference Manual (DS39500)**

Focuses on the Enhanced MCU family of devices. The operation of the Enhanced MCU family architecture and peripheral modules is explained but does not cover the specifics of each device.

## **PIC18 Device Data Sheets and Application Notes**

Data sheets describe the operation and electrical specifications of PIC18 devices. Application notes describe how to use PIC18 devices.

To obtain any of the above listed documents, visit the Microchip web site ([www.microchip.com](http://www.microchip.com)) to retrieve these documents in Adobe Acrobat (.pdf) format.

## **THE MICROCHIP WEB SITE**

Microchip provides online support via our web site at [www.microchip.com](http://www.microchip.com). This web site is used as a means to make files and information easily available to customers. Accessible by using your favorite Internet browser, the web site contains the following information:

- **Product Support** – Data sheets and errata, application notes and sample programs, design resources, user's guides and hardware support documents, latest software releases and archived software
- **General Technical Support** – Frequently Asked Questions (FAQ), technical support requests, online discussion groups, Microchip consultant program member listing
- **Business of Microchip** – Product selector and ordering guides, latest Microchip press releases, listing of seminars and events, listings of Microchip sales offices, distributors and factory representatives

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The Development Systems product group categories are:

- **Compilers** – The latest information on Microchip C compilers and other language tools. These include the MPLAB C18 and MPLAB C30 C compilers; MPASM™ and MPLAB ASM30 assemblers; MPLINK™ and MPLAB LINK30 object linkers; and MPLIB™ and MPLAB LIB30 object librarians.
- **Emulators** – The latest information on Microchip in-circuit emulators. This includes the MPLAB ICE 2000 and MPLAB ICE 4000.
- **In-Circuit Debuggers** – The latest information on the Microchip in-circuit debugger, MPLAB ICD 2.
- **MPLAB® IDE** – The latest information on Microchip MPLAB IDE, the Windows® Integrated Development Environment for development systems tools. This list is focused on the MPLAB IDE, MPLAB SIM simulator, MPLAB IDE Project Manager and general editing and debugging features.
- **Programmers** – The latest information on Microchip programmers. These include the MPLAB PM3 and PRO MATE® II device programmers and the PICSTART® Plus and PICKit® development programmers.

## CUSTOMER SUPPORT

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- Distributor or Representative
- Local Sales Office
- Field Application Engineer (FAE)
- Technical Support
- Development Systems Information Line

Customers should contact their distributor, representative or field application engineer (FAE) for support. Local sales offices are also available to help customers. A listing of sales offices and locations is included in the back of this document.

Technical support is available through the web site at: <http://support.microchip.com>

In addition, there is a Development Systems Information Line which lists the latest versions of Microchip's development systems software products. This line also provides information on how customers can receive currently available upgrade kits.

The Development Systems Information Line numbers are:

1-800-755-2345 – United States and most of Canada

1-480-792-7302 – Other International Locations



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## Chapter 1. Overview

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### 1.1 INTRODUCTION

This chapter gives an overview of the MPLAB C18 library files and precompiled object files that can be included in an application.

### 1.2 MPLAB C18 LIBRARIES OVERVIEW

A library is a collection of functions grouped for reference and ease of linking. See the *MPASM™ Assembler*, *MPLINK™ Object Linker*, *MPLIB™ Object Librarian User's Guide* (DS33014) for more information about creating and maintaining libraries.

The MPLAB C18 libraries are included in the `lib` subdirectory of the installation. These can be linked directly into an application using the MPLINK linker.

These files were precompiled in the `c:\mcc18\src` directory at Microchip. The directory `src\traditional` contains the files for Non-extended mode and `src\extended` contains the files for Extended mode. If you chose **not** to install the compiler and related files in the `c:\mcc18` directory, source code from the libraries will not show in the linker listing file and cannot be stepped through when using MPLAB IDE.

To include the library code in the `.lst` file and to be able to single step through library functions, follow the instructions in **Section 1.3.3**, **Section 1.4.3** and **Section 1.5.3** to rebuild the libraries using the supplied batch files (`.bat`) found in the `src`, `src\traditional` and `src\extended` directories.

### 1.3 START-UP CODE

#### 1.3.1 Overview

Three versions of start-up code are provided with MPLAB C18, with varying levels of initialization. The `c018*.o` object files are for use with the compiler operating in the Non-extended mode. The `c018*_e.o` object files are for use with the compiler when operating in Extended mode. In increasing order of complexity, they are:

`c018.o/c018_e.o` initializes the C software stack and jumps to the start of the application function, `main()`.

`c018i.o/c018i_e.o` performs all of the same tasks as `c018.o/c018_e.o` and also assigns the appropriate values to initialized data prior to calling the user's application. Initialization is required if global or static variables are set to a value when they are defined. This is the start-up code that is included in the linker script files that are provided with MPLAB C18.

`c018iz.o/c018iz_e.o` performs all of the same tasks as `c018i.o/c018i_e.o` and also assigns zero to all uninitialized variables, as is required for strict ANSI compliance.

## 1.3.2 Source Code

The source code for the start-up routines may be found in the `src\traditional\startup` and `src\extended\startup` subdirectories of the compiler installation.

## 1.3.3 Rebuilding

The batch file `makestartup.bat` may be used to rebuild the start-up code and copy the generated object files to the `lib` directory.

Before rebuilding the start-up code with `makestartup.bat`, verify that MPLAB C18 (`mcc18.exe`) is in your path.

## 1.4 PROCESSOR-INDEPENDENT LIBRARY

### 1.4.1 Overview

The standard C library (`c18.lib` or `c18_e.lib`) provides functions that are supported by the core PIC18 architecture: those that are supported across all processors in the family. These functions are described in the following chapters:

- General Software Library, Chapter 4.
- Math Libraries, Chapter 5.

### 1.4.2 Source Code

The source code for the functions in the standard C library may be found in the following subdirectories of the compiler installation:

- `src\traditional\math`
- `src\extended\math`
- `src\traditional\delays`
- `src\extended\delays`
- `src\traditional\stdclib`
- `src\extended\stdclib`

### 1.4.3 Rebuilding

The batch file `makec18.bat` may be used to rebuild the processor-independent library. Before invoking this batch file, verify that the following tools are in your path:

- MPLAB C18 (`mcc18.exe`)
- MPASM assembler (`mpasm.exe`)
- MPLIB librarian (`mplib.exe`)

Also prior to rebuilding the standard C library, be sure that the environment variable `MCC_INCLUDE` is set to the path of the MPLAB C18 include files (e.g., `c:\mcc18\h`).

## 1.5 PROCESSOR-SPECIFIC LIBRARIES

### 1.5.1 Overview

The processor-specific library files contain definitions that may vary across individual members of the PIC18 family. This includes all of the peripheral routines and the Special Function Register (SFR) definitions. The peripheral routines that are provided include both those designed to use the hardware peripherals and those that implement a peripheral interface using general purpose I/O lines. The functions included in the processor-specific libraries are described in the following chapters:

- **Chapter 2. “Hardware Peripheral Functions”**
- **Chapter 3. “Software Peripheral Library”**

The processor-specific libraries are named:

*p processor.lib* – Non-extended mode processor-specific library

*p processor\_e.lib* – Extended mode processor-specific library

For example, the library file for the PIC18F4620 is named *p18f4620.lib* for the Non-extended version of the library and *p18f4620\_e.lib* for the Extended version of the library.

### 1.5.2 Source Code

The source code for the processor-specific libraries may be found in the following subdirectories of the compiler installation:

- `src\traditional\pmc`
- `src\extended\pmc`
- `src\traditional\proc`
- `src\extended\proc`

### 1.5.3 Rebuilding

The batch file `makeplib.bat` may be used to rebuild the processor-specific libraries. Before invoking this batch file, verify that the following tools are in your path:

- MPLAB C18 (`mcc18.exe`)
- MPASM assembler (`mpasm.exe`)
- MPLIB librarian (`mplib.exe`)

Also prior to invoking `makeplib.bat`, be sure that the environment variable `MCC_INCLUDE` is set to the path of the MPLAB C18 include files (e.g., `c:\mcc18\h`).

NOTES:

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## Chapter 2. Hardware Peripheral Functions

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### 2.1 INTRODUCTION

This chapter documents the hardware peripheral functions found in the processor-specific libraries. The source code for all of these functions is included with MPLAB C18 in the `src\traditional\pmc` and `src\extended\pmc` subdirectories of the compiler installation.

See the *MPASM™ Assembler*, *MPLINK™ Object Linker*, *MPLIB™ Object Librarian User's Guide* (DS33014) for more information about managing libraries using the MPLIB librarian.

The following peripherals are supported by MPLAB C18 library routines:

- A/D Converter (**Section 2.2 “A/D Converter Functions”**)
- Input Capture (**Section 2.3 “Input Capture Functions”**)
- I<sup>2</sup>C™ (**Section 2.4 “I<sup>2</sup>C™ Functions”**)
- I/O Ports (**Section 2.5 “I/O Port Functions”**)
- Microwire (**Section 2.6 “Microwire Functions”**)
- Pulse-Width Modulation (PWM) (**Section 2.7 “Pulse-Width Modulation Functions”**)
- SPI™ (**Section 2.8 “SPI™ Functions”**)
- Timer (**Section 2.9 “Timer Functions”**)
- USART (**Section 2.10 “USART Functions”**)

### 2.2 A/D CONVERTER FUNCTIONS

The A/D peripheral is supported with the following functions:

**TABLE 2-1: A/D CONVERTER FUNCTIONS**

Function	Description
BusyADC	Is A/D converter currently performing a conversion?
CloseADC	Disable the A/D converter.
ConvertADC	Start an A/D conversion.
OpenADC	Configure the A/D convertor.
ReadADC	Read the results of an A/D conversion.
SetChanADC	Select A/D channel to be used.

## 2.2.1 Function Descriptions

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### BusyADC

---

**Function:** Is the A/D converter currently performing a conversion?  
**Include:** `adc.h`  
**Prototype:** `char BusyADC( void );`  
**Remarks:** This function indicates if the A/D peripheral is in the process of converting a value.  
**Return Value:** 1 if the A/D peripheral is performing a conversion.  
0 if the A/D peripheral isn't performing a conversion.  
**File Name:** `adcbusy.c`

---

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### CloseADC

---

**Function:** Disable the A/D converter.  
**Include:** `adc.h`  
**Prototype:** `void CloseADC( void );`  
**Remarks:** This function disables the A/D convertor and A/D interrupt mechanism.  
**File Name:** `adcclose.c`

---

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### ConvertADC

---

**Function:** Starts the A/D conversion process.  
**Include:** `adc.h`  
**Prototype:** `void ConvertADC( void );`  
**Remarks:** This function starts an A/D conversion. The `BusyADC()` function may be used to detect completion of the conversion.  
**File Name:** `adcconv.c`

---

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### OpenADC

#### PIC18CXX2, PIC18FXX2, PIC18FXX8, PIC18FXX39

---

**Function:** Configure the A/D convertor.  
**Include:** `adc.h`  
**Prototype:** `void OpenADC( unsigned char config,  
  unsigned char config2 );`  
**Arguments:** *config*  
A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.  
**A/D clock source:**  

<code>ADC_FOSC_2</code>	FOSC / 2
<code>ADC_FOSC_4</code>	FOSC / 4
<code>ADC_FOSC_8</code>	FOSC / 8
<code>ADC_FOSC_16</code>	FOSC / 16
<code>ADC_FOSC_32</code>	FOSC / 32
<code>ADC_FOSC_64</code>	FOSC / 64
<code>ADC_FOSC_RC</code>	Internal RC Oscillator

  
**A/D result justification:**  

<code>ADC_RIGHT_JUST</code>	Result in Least Significant bits
<code>ADC_LEFT_JUST</code>	Result in Most Significant bits

---

## OpenADC

### PIC18CXX2, PIC18FXX2, PIC18FXX8, PIC18FXX39 (Continued)

#### A/D voltage reference source:

ADC_8ANA_0REF	VREF+=VDD, VREF-=VSS, All analog channels
ADC_7ANA_1REF	AN3=VREF+, All analog channels except AN3
ADC_6ANA_2REF	AN3=VREF+, AN2=VREF
ADC_6ANA_0REF	VREF+=VDD, VREF-=VSS
ADC_5ANA_1REF	AN3=VREF+, VREF-=VSS
ADC_5ANA_0REF	VREF+=VDD, VREF-=VSS
ADC_4ANA_2REF	AN3=VREF+, AN2=VREF-
ADC_4ANA_1REF	AN3=VREF+
ADC_3ANA_2REF	AN3=VREF+, AN2=VREF-
ADC_3ANA_0REF	VREF+=VDD, VREF-=VSS
ADC_2ANA_2REF	AN3=VREF+, AN2=VREF-
ADC_2ANA_1REF	AN3=VREF+
ADC_1ANA_2REF	AN3=VREF+, AN2=VREF-, AN0=A
ADC_1ANA_0REF	AN0 is analog input
ADC_0ANA_0REF	All digital I/O

#### *config2*

A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.

#### Channel:

ADC_CH0	Channel 0
ADC_CH1	Channel 1
ADC_CH2	Channel 2
ADC_CH3	Channel 3
ADC_CH4	Channel 4
ADC_CH5	Channel 5
ADC_CH6	Channel 6
ADC_CH7	Channel 7

#### A/D Interrupts:

ADC_INT_ON	Interrupts enabled
ADC_INT_OFF	Interrupts disabled

#### Remarks:

This function resets the A/D peripheral to the POR state and configures the A/D-related Special Function Registers (SFRs) according to the options specified.

#### File Name:

`adcopen.c`

#### Code Example:

```
OpenADC( ADC_FOSC_32    &
         ADC_RIGHT_JUST &
         ADC_1ANA_0REF,
         ADC_CH0        &
         ADC_INT_OFF    );
```

---

## OpenADC PIC18C658/858, PIC18C601/801, PIC18F6X20, PIC18F8X20

---

**Function:** Configure the A/D convertor.

**Include:** `adc.h`

**Prototype:** `void OpenADC( unsigned char config,  
unsigned char config2 );`

**Arguments:** *config*

A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.

### A/D clock source:

<code>ADC_FOSC_2</code>	FOSC / 2
<code>ADC_FOSC_4</code>	FOSC / 4
<code>ADC_FOSC_8</code>	FOSC / 8
<code>ADC_FOSC_16</code>	FOSC / 16
<code>ADC_FOSC_32</code>	FOSC / 32
<code>ADC_FOSC_64</code>	FOSC / 64
<code>ADC_FOSC_RC</code>	Internal RC Oscillator

### A/D result justification:

<code>ADC_RIGHT_JUST</code>	Result in Least Significant bits
<code>ADC_LEFT_JUST</code>	Result in Most Significant bits

### A/D port configuration:

<code>ADC_0ANA</code>	All digital	
<code>ADC_1ANA</code>	analog:AN0	digital:AN1-AN15
<code>ADC_2ANA</code>	analog:AN0-AN1	digital:AN2-AN15
<code>ADC_3ANA</code>	analog:AN0-AN2	digital:AN3-AN15
<code>ADC_4ANA</code>	analog:AN0-AN3	digital:AN4-AN15
<code>ADC_5ANA</code>	analog:AN0-AN4	digital:AN5-AN15
<code>ADC_6ANA</code>	analog:AN0-AN5	digital:AN6-AN15
<code>ADC_7ANA</code>	analog:AN0-AN6	digital:AN7-AN15
<code>ADC_8ANA</code>	analog:AN0-AN7	digital:AN8-AN15
<code>ADC_9ANA</code>	analog:AN0-AN8	digital:AN9-AN15
<code>ADC_10ANA</code>	analog:AN0-AN9	digital:AN10-AN15
<code>ADC_11ANA</code>	analog:AN0-AN10	digital:AN11-AN15
<code>ADC_12ANA</code>	analog:AN0-AN11	digital:AN12-AN15
<code>ADC_13ANA</code>	analog:AN0-AN12	digital:AN13-AN15
<code>ADC_14ANA</code>	analog:AN0-AN13	digital:AN14-AN15
<code>ADC_15ANA</code>	All analog	

### *config2*

A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.



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## OpenADC PIC18C658/858, PIC18C601/801, PIC18F6X20, PIC18F8X20 (Continued)

---

### Channel:

ADC_CH0	Channel 0
ADC_CH1	Channel 1
ADC_CH2	Channel 2
ADC_CH3	Channel 3
ADC_CH4	Channel 4
ADC_CH5	Channel 5
ADC_CH6	Channel 6
ADC_CH7	Channel 7
ADC_CH8	Channel 8
ADC_CH9	Channel 9
ADC_CH10	Channel 10
ADC_CH11	Channel 11
ADC_CH12	Channel 12
ADC_CH13	Channel 13
ADC_CH14	Channel 14
ADC_CH15	Channel 15

### A/D Interrupts:

ADC_INT_ON	Interrupts enabled
ADC_INT_OFF	Interrupts disabled

### A/D VREF+ configuration:

ADC_VREFPLUS_VDD	VREF+ = AVDD
ADC_VREFPLUS_EXT	VREF+ = external

### A/D VREF- configuration:

ADC_VREFMINUS_VSS	VREF- = AVSS
ADC_VREFMINUS_EXT	VREF- = external

### Remarks:

This function resets the A/D-related registers to the POR state and then configures the clock, result format, voltage reference, port and channel.

### File Name:

adcopen.c

### Code Example:

```
OpenADC( ADC_FOSC_32    &
         ADC_RIGHT_JUST &
         ADC_14ANA,
         ADC_CH0         &
         ADC_INT_OFF     ) ;
```

---

## OpenADC All Other Processors

---

**Function:** Configure the A/D convertor.

**Include:** `adc.h`

**Prototype:** `void OpenADC(unsigned char config,  
                  unsigned char config2 ,  
                  unsigned char portconfig);`

**Arguments:** *config*

A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.

### A/D clock source:

<code>ADC_FOSC_2</code>	FOSC / 2
<code>ADC_FOSC_4</code>	FOSC / 4
<code>ADC_FOSC_8</code>	FOSC / 8
<code>ADC_FOSC_16</code>	FOSC / 16
<code>ADC_FOSC_32</code>	FOSC / 32
<code>ADC_FOSC_64</code>	FOSC / 64
<code>ADC_FOSC_RC</code>	Internal RC Oscillator

### A/D result justification:

<code>ADC_RIGHT_JUST</code>	Result in Least Significant bits
<code>ADC_LEFT_JUST</code>	Result in Most Significant bits

### A/D acquisition time select:

<code>ADC_0_TAD</code>	0 Tad
<code>ADC_2_TAD</code>	2 Tad
<code>ADC_4_TAD</code>	4 Tad
<code>ADC_6_TAD</code>	6 Tad
<code>ADC_8_TAD</code>	8 Tad
<code>ADC_12_TAD</code>	12 Tad
<code>ADC_16_TAD</code>	16 Tad
<code>ADC_20_TAD</code>	20 Tad

### *config2*

A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file `adc.h`.

### Channel:

<code>ADC_CH0</code>	Channel 0
<code>ADC_CH1</code>	Channel 1
<code>ADC_CH2</code>	Channel 2
<code>ADC_CH3</code>	Channel 3
<code>ADC_CH4</code>	Channel 4
<code>ADC_CH5</code>	Channel 5
<code>ADC_CH6</code>	Channel 6
<code>ADC_CH7</code>	Channel 7
<code>ADC_CH8</code>	Channel 8
<code>ADC_CH9</code>	Channel 9
<code>ADC_CH10</code>	Channel 10
<code>ADC_CH11</code>	Channel 11
<code>ADC_CH12</code>	Channel 12
<code>ADC_CH13</code>	Channel 13
<code>ADC_CH14</code>	Channel 14
<code>ADC_CH15</code>	Channel 15

---

## OpenADC All Other Processors (Continued)

---

### A/D Interrupts:

ADC_INT_ON	Interrupts enabled
ADC_INT_OFF	Interrupts disabled

### A/D voltage configuration:

ADC_VREFPLUS_VDD	VREF+ = AVDD
ADC_VREFPLUS_EXT	VREF+ = external
ADC_VREFMINUS_VDD	VREF- = AVDD
ADC_VREFMINUS_EXT	VREF- = external

### *portconfig*

The value of portconfig is any value from 0 to 127 inclusive for the PIC18F1220/1320 and 0 to 15 inclusive for all other processors. This is the value of bits 0 through 6 or bits 0 through 3 of the ADCON1 register, which are the port configuration bits.

**Remarks:** This function resets the A/D-related registers to the POR state and then configures the clock, result format, voltage reference, port and channel.

**File Name:** adcopen.c

**Code Example:**

```
OpenADC( ADC_FOSC_32    &
          ADC_RIGHT_JUST &
          ADC_12_TAD,
          ADC_CH0        &
          ADC_INT_OFF, 15 );
```

---

## ReadADC

---

**Function:** Read the result of an A/D conversion.

**Include:** adc.h

**Prototype:** int ReadADC( void );

**Remarks:** This function reads the 16-bit result of an A/D conversion.

**Return Value:** This function returns the 16-bit signed result of the A/D conversion. Based on the configuration of the A/D converter (e.g., using the OpenADC() function), the result will be contained in the Least Significant or Most Significant bits of the 16-bit result.

**File Name:** adcread.c

---

## SetChanADC

---

**Function:** Select the channel used as input to the A/D converter.

**Include:** `adc.h`

**Prototype:** `void SetChanADC( unsigned char channel );`

**Arguments:** *channel*  
One of the following values (defined in `adc.h`):

<code>ADC_CH0</code>	Channel 0
<code>ADC_CH1</code>	Channel 1
<code>ADC_CH2</code>	Channel 2
<code>ADC_CH3</code>	Channel 3
<code>ADC_CH4</code>	Channel 4
<code>ADC_CH5</code>	Channel 5
<code>ADC_CH6</code>	Channel 6
<code>ADC_CH7</code>	Channel 7
<code>ADC_CH8</code>	Channel 8
<code>ADC_CH9</code>	Channel 9
<code>ADC_CH10</code>	Channel 10
<code>ADC_CH11</code>	Channel 11

**Remarks:** Selects the pin that will be used as input to the A/D converter.

**File Name:** `adcsetch.c`

**Code Example:** `SetChanADC( ADC_CH0 );`

### 2.2.2 Example Use of the A/D Converter Routines

```
#include <p18C452.h>
#include <adc.h>
#include <stdlib.h>
#include <delays.h>

int result;

void main( void )
{
    // configure A/D convertor
    OpenADC( ADC_FOSC_32 & ADC_RIGHT_JUST & ADC_8ANA_0REF,
            ADC_CH0 & ADC_INT_OFF );

    Delay10TCYx( 5 );    // Delay for 50TCY
    ConvertADC();        // Start conversion
    while( BusyADC() );  // Wait for completion
    result = ReadADC();   // Read result
    CloseADC();          // Disable A/D converter
}
```

## 2.3 INPUT CAPTURE FUNCTIONS

The capture peripheral is supported with the following functions:

**TABLE 2-2: INPUT CAPTURE FUNCTIONS**

Function	Description
CloseCapture $x$	Disable capture peripheral $x$ .
OpenCapture $x$	Configure capture peripheral $x$ .
ReadCapture $x$	Read a value from capture peripheral $x$ .
CloseECapture $x$ <sup>(1)</sup>	Disable enhanced capture peripheral $x$ .
OpenECapture $x$ <sup>(1)</sup>	Configure enhanced capture peripheral $x$ .
ReadECapture $x$ <sup>(1)</sup>	Read a value from enhanced capture peripheral $x$ .

**Note 1:** The enhanced capture functions are only available on those devices with an ECCPxCON register.

### 2.3.1 Function Descriptions

**CloseCapture1**  
**CloseCapture2**  
**CloseCapture3**  
**CloseCapture4**  
**CloseCapture5**  
**CloseECapture1**

<b>Function:</b>	Disable input capture $x$ .
<b>Include:</b>	capture.h
<b>Prototype:</b>	<pre>void CloseCapture1( void ); void CloseCapture2( void ); void CloseCapture3( void ); void CloseCapture4( void ); void CloseCapture5( void ); void CloseECapture1( void );</pre>
<b>Remarks:</b>	This function disables the interrupt corresponding to the specified input capture.
<b>File Name:</b>	<pre>cp1close.c cp2close.c cp3close.c cp4close.c cp5close.c ep1close.c</pre>

OpenCapture1  
 OpenCapture2  
 OpenCapture3  
 OpenCapture4  
 OpenCapture5  
 OpenECapture1

---

**Function:** Configure and enable input capture x.

**Include:** capture.h

**Prototype:**

```
void OpenCapture1( unsigned char config );
void OpenCapture2( unsigned char config );
void OpenCapture3( unsigned char config );
void OpenCapture4( unsigned char config );
void OpenCapture5( unsigned char config );
void OpenECapture1( unsigned char config );
```

**Arguments:** *config*  
 A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file capture.h:

**Enable CCP Interrupts:**

CAPTURE_INT_ON	Interrupts Enabled
CAPTURE_INT_OFF	Interrupts Disabled

**Interrupt Trigger (replace x with CCP module number):**

Cx EVERY_FALL_EDGE	Interrupt on every falling edge
Cx EVERY_RISE_EDGE	Interrupt on every rising edge
Cx EVERY_4_RISE_EDGE	Interrupt on every 4th rising edge
Cx EVERY_16_RISE_EDGE	Interrupt on every 16th rising edge
EC1 EVERY_FALL_EDGE	Interrupt on every falling edge (enhanced)
EC1 EVERY_RISE_EDGE	Interrupt on every rising edge (enhanced)
EC1 EVERY_4_RISE_EDGE	Interrupt on every 4th rising edge (enhanced)
EC1 EVERY_16_RISE_EDGE	Interrupt on every 16th rising edge (enhanced)

**Remarks:** This function first resets the capture module to the POR state and then configures the input capture for the specified edge detection.

The capture functions use a structure, defined in capture.h, to indicate overflow status of each of the capture modules. This structure is called CapStatus and has the following bit fields:

```
Cap1OVF
Cap2OVF
Cap3OVF
Cap4OVF
Cap5OVF
ECap1OVF
```

In addition to opening the capture, the appropriate timer module must be enabled before any of the captures will operate. See the data sheet for CCP and timer interconnect configurations and **Section 2.9 “Timer Functions”** for the arguments used with CCP in OpenTimer3.

---

**OpenCapture1**  
**OpenCapture2**  
**OpenCapture3**  
**OpenCapture4**  
**OpenCapture5**  
**OpenECapture1 (Continued)**

---

**File Name:** cp1open.c  
cp2open.c  
cp3open.c  
cp4open.c  
cp5open.c  
ep1open.c

**Code Example:** `OpenCapture1( CAPTURE_INT_ON &  
C1_EVERY_4_RISE_EDGE );`

---

---

**ReadCapture1**  
**ReadCapture2**  
**ReadCapture3**  
**ReadCapture4**  
**ReadCapture5**  
**ReadECapture1**

---

**Function:** Read the result of a capture event from the specified input capture.

**Include:** capture.h

**Prototype:** `unsigned int ReadCapture1( void );  
unsigned int ReadCapture2( void );  
unsigned int ReadCapture3( void );  
unsigned int ReadCapture4( void );  
unsigned int ReadCapture5( void );  
unsigned int ReadECapture1( void );`

**Remarks:** This function reads the value of the respective input capture's SFRs.

**Return Value:** This function returns the result of the capture event.

**File Name:** cp1read.c  
cp2read.c  
cp3read.c  
cp4read.c  
cp5read.c  
ep1read.c

## 2.3.2 Example Use of the Capture Routines

This example demonstrates the use of the capture library routines in a “polled” (not interrupt-driven) environment.

```
#include <p18C452.h>
#include <capture.h>
#include <timers.h>
#include <usart.h>
#include <stdlib.h>

void main(void)
{
    unsigned int result;
    char str[7];

    // Configure Capture1
    OpenCapture1( C1_EVERY_4_RISE_EDGE &
                  CAPTURE_INT_OFF );

    // Configure Timer3
    OpenTimer3( TIMER_INT_OFF &
                T3_SOURCE_INT );

    // Configure USART
    OpenUSART( USART_TX_INT_OFF &
               USART_RX_INT_OFF &
               USART_ASYNC_MODE &
               USART_EIGHT_BIT &
               USART_CONT_RX,
               25 );

    while(!PIR1bits.CCP1IF); // Wait for event
    result = ReadCapture1(); // read result
    ultoa(result, str);      // convert to string

    // Write the string out to the USART if
    // an overflow condition has not occurred.
    if(!CapStatus.Cap1OVF)
    {
        putsUSART(str);
    }

    // Clean up
    CloseCapture1();
    CloseTimer3();
    CloseUSART();
}
```



## 2.4 I<sup>2</sup>C™ FUNCTIONS

The following routines are provided for devices with a single I<sup>2</sup>C peripheral:

**TABLE 2-3: SINGLE I<sup>2</sup>C™ PERIPHERAL FUNCTIONS**

Function	Description
AckI2C	Generate I <sup>2</sup> C™ bus <i>Acknowledge</i> condition.
CloseI2C	Disable the SSP module.
DataRdyI2C	Is the data available in the I <sup>2</sup> C buffer?
getcI2C	Read a single byte from the I <sup>2</sup> C bus.
getsI2C	Read a string from the I <sup>2</sup> C bus operating in master I <sup>2</sup> C mode.
IdleI2C	Loop until I <sup>2</sup> C bus is idle.
NotAckI2C	Generate I <sup>2</sup> C bus <i>Not Acknowledge</i> condition.
OpenI2C	Configure the SSP module.
putcI2C	Write a single byte to the I <sup>2</sup> C bus.
putsI2C	Write a string to the I <sup>2</sup> C bus operating in either Master or Slave mode.
ReadI2C	Read a single byte from the I <sup>2</sup> C bus.
RestartI2C	Generate an I <sup>2</sup> C bus <i>Restart</i> condition.
StartI2C	Generate an I <sup>2</sup> C bus <i>Start</i> condition.
StopI2C	Generate an I <sup>2</sup> C bus <i>Stop</i> condition.
WriteI2C	Write a single byte to the I <sup>2</sup> C bus.

The following routines are provided for devices with multiple I<sup>2</sup>C peripherals:

**TABLE 2-4: MULTIPLE I<sup>2</sup>C™ PERIPHERAL FUNCTIONS**

Function	Description
AckI2Cx	Generate I <sup>2</sup> Cx bus <i>Acknowledge</i> condition.
CloseI2Cx	Disable the SS x module.
DataRdyI2Cx	Is the data available in the I <sup>2</sup> Cx buffer?
getcI2Cx	Read a single byte from the I <sup>2</sup> Cx bus.
getsI2Cx	Read a string from the I <sup>2</sup> Cx bus operating in master I <sup>2</sup> C mode.
IdleI2Cx	Loop until I <sup>2</sup> Cx bus is idle.
NotAckI2Cx	Generate I <sup>2</sup> Cx bus <i>Not Acknowledge</i> condition.
OpenI2Cx	Configure the SSPx module.
putcI2Cx	Write a single byte to the I <sup>2</sup> Cx bus.
putsI2Cx	Write a string to the I <sup>2</sup> Cx bus operating in either Master or Slave mode.
ReadI2Cx	Read a single byte from the I <sup>2</sup> Cx bus.
RestartI2Cx	Generate an I <sup>2</sup> Cx bus <i>Restart</i> condition.
StartI2Cx	Generate an I <sup>2</sup> Cx bus <i>Start</i> condition.
StopI2Cx	Generate an I <sup>2</sup> Cx bus <i>Stop</i> condition.
WriteI2Cx	Write a single byte to the I <sup>2</sup> Cx bus.

The following functions are also provided for interfacing with an EE memory device such as the Microchip 24LC01B using the I<sup>2</sup>C interface:

**TABLE 2-5: INTERFACE FUNCTIONS FOR EE MEMORY DEVICES**

Function	Description
EEAckPolling $\mathbf{x}$	Generate the Acknowledge polling sequence.
EEByteWrite $\mathbf{x}$	Write a single byte.
EECurrentAddrRead $\mathbf{x}$	Read a single byte from the next location.
EEPageWrite $\mathbf{x}$	Write a string of data.
EERandomRead $\mathbf{x}$	Read a single byte from an arbitrary address.
EESequentialRead $\mathbf{x}$	Read a string of data.

## 2.4.1 Function Descriptions

---

### AckI2C

### AckI2C1

### AckI2C2

---

**Function:** Generate I<sup>2</sup>C bus *Acknowledge* condition.

**Include:** i2c.h

**Prototype:**  
void AckI2C( void );  
void AckI2C1( void );  
void AckI2C2( void );

**Remarks:** This function generates an I<sup>2</sup>C $\mathbf{x}$  bus *Acknowledge* condition.

**File Name:**  
i2c\_ack.c  
i2c1ack.c  
i2c2ack.c

---

### CloseI2C

### CloseI2C1

### CloseI2C2

---

**Function:** Disable the SSP $\mathbf{x}$  module.

**Include:** i2c.h

**Prototype:**  
void CloseI2C( void );  
void CloseI2C1( void );  
void CloseI2C2( void );

**Remarks:** This function disables the SSP $\mathbf{x}$  module.

**File Name:**  
i2c\_close.c  
i2c1close.c  
i2c2close.c

---

---

## DataRdyI2C

### DataRdyI2C1

### DataRdyI2C2

---

**Function:** Is data available in the I<sup>2</sup>C<sub>x</sub> buffer?

**Include:** i2c.h

**Prototype:**  
unsigned char DataRdyI2C( void );  
unsigned char DataRdyI2C1( void );  
unsigned char DataRdyI2C2( void );

**Remarks:** Determines if there is a byte to be read in the SSP<sub>x</sub> buffer.

**Return Value:** 1 if there is data in the SSP<sub>x</sub> buffer  
0 if there is no data in the SSP<sub>x</sub> buffer

**File Name:** i2c\_dtrd.c  
i2c1dtrd.c  
i2c2dtrd.c

**Code Example:**  
if (DataRdyI2C())  
{  
    var = getcI2C();  
}

---

---

## getcI2C

### getcI2C1

### getcI2C2

---

getcI2Cx is defined as ReadI2Cx. See **ReadI2Cx**.

---

---

## getsI2C

### getsI2C1

### getsI2C2

---

**Function:** Read a fixed length string from the I<sup>2</sup>C<sub>x</sub> bus operating in master I<sup>2</sup>C mode.

**Include:** i2c.h

**Prototype:**  
unsigned char getsI2C(  
    unsigned char \* *rdptr*,  
    unsigned char *length* );  
unsigned char getsI2C1(  
    unsigned char \* *rdptr*,  
    unsigned char *length* );  
unsigned char getsI2C2(  
    unsigned char \* *rdptr*,  
    unsigned char *length* );

**Arguments:** *rdptr*  
Character type pointer to PICmicro MCU RAM for storage of data read from I<sup>2</sup>C device.  
*length*  
Number of bytes to read from I<sup>2</sup>C<sub>x</sub> device.

**Remarks:** This routine reads a predefined data string length from the I<sup>2</sup>C<sub>x</sub> bus.

---

---

## getsI2C

## getsI2C1

## getsI2C2 (Continued)

---

**Return Value:** 0 if all bytes have been sent  
-1 if a bus collision has occurred

**File Name:** i2c\_gets.c  
i2c1gets.c  
i2c2gets.c

**Code Example:** unsigned char string[15];  
getsI2C(string, 15);

---

## IdleI2C

## IdleI2C1

## IdleI2C2

---

**Function:** Loop until I<sup>2</sup>Cx bus is Idle.

**Include:** i2c.h

**Prototype:** void IdleI2C( void );

**Remarks:** This function checks the state of the I<sup>2</sup>C peripheral and waits for the bus to become available. The IdleI2C function is required since the hardware I<sup>2</sup>C peripheral does not allow for spooling of bus sequences. The I<sup>2</sup>C peripheral must be in an Idle state before an I<sup>2</sup>C operation can be initiated or a write collision will be generated.

**File Name:** idlei2c.c

---

## NotAckI2C

## NotAckI2C1

## NotAckI2C2

---

**Function:** Generate I<sup>2</sup>Cx bus *Not Acknowledge* condition.

**Include:** i2c.h

**Prototype:** void NotAckI2C( void );  
void NotAckI2C1( void );  
void NotAckI2C2( void );

**Remarks:** This function generates an I<sup>2</sup>Cx bus *Not Acknowledge* condition.

**File Name:** i2c\_nack.c  
i2c1nack.c  
i2c2nack.c

---

---

## OpenI2C

### OpenI2C1

### OpenI2C2

---

**Function:** Configure the SSP $x$  module.

**Include:** `i2c.h`

**Prototype:**

```
void OpenI2C( unsigned char sync_mode,
              unsigned char slew );
void OpenI2C1( unsigned char sync_mode,
               unsigned char slew );
void OpenI2C2( unsigned char sync_mode,
               unsigned char slew );
```

**Arguments:** *sync\_mode*

One of the following values, defined in `i2c.h`:

SLAVE_7	I <sup>2</sup> C Slave mode, 7-bit address
SLAVE_10	I <sup>2</sup> C Slave mode, 10-bit address
MASTER	I <sup>2</sup> C Master mode

*slew*

One of the following values, defined in `i2c.h`:

SLEW_OFF	Slew rate disabled for 100 kHz mode
SLEW_ON	Slew rate enabled for 400 kHz mode

**Remarks:** OpenI2C $x$  resets the SSP $x$  module to the POR state and then configures the module for Master/Slave mode and the selected slew rate.

**File Name:** `i2c_open.c`  
`i2c1open.c`  
`i2c2open.c`

**Code Example:** `OpenI2C(MASTER, SLEW_ON);`

---

## putcI2C

### putcI2C1

### putcI2C2

---

putcI2C $x$  is defines as Writel2C $x$ . See **Writel2C $x$** .

---

## putsI2C

## putsI2C1

## putsI2C2

---

<b>Function:</b>	Write a data string to the I <sup>2</sup> Cx bus operating in either Master or Slave mode.
<b>Include:</b>	i2c.h
<b>Prototype:</b>	<pre>unsigned char putsI2C(     unsigned char *wrptr ); unsigned char putsI2C1(     unsigned char *wrptr ); unsigned char putsI2C2(     unsigned char *wrptr );</pre>
<b>Arguments:</b>	<b>wrptr</b> Pointer to data that will be written to the I <sup>2</sup> C bus.
<b>Remarks:</b>	This routine writes a data string to the I <sup>2</sup> Cx bus until a null character is reached. The null character itself is not transmitted. This routine can operate in both Master or Slave mode.
<b>Return Value:</b>	<b>Master I<sup>2</sup>C mode:</b> 0 if the null character was reached in the data string -2 if the slave I <sup>2</sup> Cx device responded with a <i>NOT ACK</i> -3 if a write collision occurred <b>Slave I<sup>2</sup>C mode:</b> 0 if the null character was reached in the data string -2 if the master I <sup>2</sup> Cx device responded with a <i>NOT ACK</i> which terminated the data transfer
<b>File Name:</b>	i2c_puts.c i2c1puts.c i2c2puts.c
<b>Code Example:</b>	<pre>unsigned char string[] = "data to send"; putsI2C(string);</pre>

---

## ReadI2C

## ReadI2C1

## ReadI2C2

## getcI2C

## getcI2C1

## getcI2C2

---

<b>Function:</b>	Read a single byte from the I <sup>2</sup> Cx bus.
<b>Include:</b>	i2c.h
<b>Prototype:</b>	<pre>unsigned char ReadI2C ( void ); unsigned char ReadI2C1 ( void ); unsigned char ReadI2C2 ( void ); unsigned char getcI2C ( void ); unsigned char getcI2C1 ( void ); unsigned char getcI2C2 ( void );</pre>
<b>Remarks:</b>	This function reads in a single byte from the I <sup>2</sup> Cx bus. getcI2Cx is defined to be ReadI2Cx in i2c.h.
<b>Return Value:</b>	The data byte read from the I <sup>2</sup> Cx bus.

---

---

## ReadI2C

### ReadI2C1

### ReadI2C2

### getI2C

### getI2C1

### getI2C2 (Continued)

---

**File Name:** i2c\_read.c  
i2c1read.c  
i2c2read.c  
# define in i2c.h  
# define in i2c.h  
# define in i2c.h

**Code Example:** unsigned char value;  
value = ReadI2C();

---

## RestartI2C

### RestartI2C1

### RestartI2C2

---

**Function:** Generate an I<sup>2</sup>Cx bus *Restart* condition.

**Include:** i2c.h

**Prototype:** void RestartI2C( void );  
void RestartI2C1( void );  
void RestartI2C2( void );

**Remarks:** This function generates an I<sup>2</sup>Cx bus *Restart* condition.

**File Name:** i2c\_rstr.c  
i2c1rstr.c  
i2c2rstr.c

---

## StartI2C

### StartI2C1

### StartI2C2

---

**Function:** Generate an I<sup>2</sup>Cx bus *Start* condition.

**Include:** i2c.h

**Prototype:** void StartI2C( void );  
void StartI2C1( void );  
void StartI2C2( void );

**Remarks:** This function generates a I<sup>2</sup>Cx bus *Start* condition.

**File Name:** i2c\_start.c  
i2c1start.c  
i2c2start.c

---

---

## StopI2C

### StopI2C1

### StopI2C2

---

**Function:** Generate I<sup>2</sup>Cx bus *Stop* condition.

**Include:** i2c.h

**Prototype:**  
void StopI2C( void );  
void StopI2C1( void );  
void StopI2C2( void );

**Remarks:** This function generates an I<sup>2</sup>Cx bus *Stop* condition.

**File Name:** i2c\_stop.c  
i2c1stop.c  
i2c2stop.c

---

## Writel2C

### Writel2C1

### Writel2C2

### putcI2C

### putcI2C1

### putcI2C2

---

**Function:** Write a single byte to the I<sup>2</sup>Cx bus device.

**Include:** i2c.h

**Prototype:**  
unsigned char WriteI2C(  
    unsigned char **data\_out** );  
unsigned char WriteI2C1(  
    unsigned char **data\_out** );  
unsigned char WriteI2C2(  
    unsigned char **data\_out** );  
unsigned char putcI2C(  
    unsigned char **data\_out** );  
unsigned char putcI2C1(  
    unsigned char **data\_out** );  
unsigned char putcI2C2(  
    unsigned char **data\_out** );

**Arguments:** **data\_out**  
A single data byte to be written to the I<sup>2</sup>Cx bus device.

**Remarks:** This function writes out a single data byte to the I<sup>2</sup>Cx bus device.  
putcI2Cx is defined to be Writel2Cx in i2c.h.

**Return Value:** 0 if the write was successful  
-1 if there was a write collision

**File Name:** i2c\_write.c  
i2c1write.c  
i2c2write.c  
#define in i2c.h  
#define in i2c.h  
#define in i2c.h

**Code Example:** WriteI2C('a');

---



## 2.4.2 EE Memory Device Interface Function Descriptions

---

### EEAckPolling

### EEAckPolling1

### EEAckPolling2

---

<b>Function:</b>	Generate the Acknowledge polling sequence for Microchip EE I <sup>2</sup> C memory devices.
<b>Include:</b>	i2c.h
<b>Prototype:</b>	<pre>unsigned char EEAckPolling(     unsigned char <b>control</b> ); unsigned char EEAckPolling1(     unsigned char <b>control</b> ); unsigned char EEAckPolling2(     unsigned char <b>control</b> );</pre>
<b>Arguments:</b>	<b>control</b> EEPROM control / bus device select address byte.
<b>Remarks:</b>	This function is used to generate the Acknowledge polling sequence for EE I <sup>2</sup> C memory devices that utilize Acknowledge polling.
<b>Return Value:</b>	0 if there were no errors -1 if there was a bus collision error -3 if there was a write collision error
<b>File Name:</b>	i2c_ecap.c i2c1ecap.c i2c2ecap.c
<b>Code Example:</b>	<pre>temp = EEAckPolling(0xA0);</pre>

---

### EEByteWrite

### EEByteWrite1

### EEByteWrite2

---

<b>Function:</b>	Write a single byte to the I <sup>2</sup> Cx bus.
<b>Include:</b>	i2c.h
<b>Prototype:</b>	<pre>unsigned char EEByteWrite(     unsigned char <b>control</b>,     unsigned char <b>address</b>,     unsigned char <b>data</b> ); unsigned char EEByteWrite1(     unsigned char <b>control</b>,     unsigned char <b>address</b>,     unsigned char <b>data</b> ); unsigned char EEByteWrite2(     unsigned char <b>control</b>,     unsigned char <b>address</b>,     unsigned char <b>data</b> );</pre>
<b>Arguments:</b>	<b>control</b> EEPROM control / bus device select address byte. <b>address</b> EEPROM internal address location. <b>data</b> Data to write to EEPROM address specified in function parameter address.

---

---

## EEByteWrite

## EEByteWrite1

## EEByteWrite2 (Continued)

---

<b>Remarks:</b>	This function writes a single data byte to the I <sup>2</sup> Cx bus. This routine can be used for any Microchip I <sup>2</sup> C EE memory device which requires only 1 byte of address information.
<b>Return Value:</b>	0 if there were no errors -1 if there was a bus collision error -2 if there was a NOT ACK error -3 if there was a write collision error
<b>File Name:</b>	i2c_ecbw.c i2c1ecbw.c i2c2ecbw.c
<b>Code Example:</b>	<pre>temp = EEByteWrite(0xA0, 0x30, 0xA5);</pre>

---

## EECurrentAddRead

## EECurrentAddRead1

## EECurrentAddRead2

---

<b>Function:</b>	Read a single byte from the I <sup>2</sup> Cx bus.
<b>Include:</b>	i2c.h
<b>Prototype:</b>	<pre>unsigned int EECurrentAddRead(     unsigned char <b>control</b> ); unsigned int EECurrentAddRead1(     unsigned char <b>control</b> ); unsigned int EECurrentAddRead2(     unsigned char <b>control</b> );</pre>
<b>Arguments:</b>	<b>control</b> EEPROM control / bus device select address byte.
<b>Remarks:</b>	This function reads in a single byte from the I <sup>2</sup> Cx bus. The address location of the data to read is that of the current pointer within the I <sup>2</sup> C EE device. The memory device contains an address counter that maintains the address of the last word accessed, incremented by one.
<b>Return Value:</b>	-1 if a bus collision error occurred -2 if a NOT ACK error occurred -3 if a write collision error occurred Otherwise, the result is returned as an unsigned 16-bit quantity. Since the buffer itself is only 8-bits wide, this means that the Most Significant Byte will be zero and the Least Significant Byte will contain the read buffer contents.
<b>File Name:</b>	i2c_eecr.c i2c1eecr.c i2c2eecr.c
<b>Code Example:</b>	<pre>temp = EECurrentAddRead(0xA1);</pre>

---

---

## EEPageWrite

## EEPageWrite1

## EEPageWrite2

---

**Function:** Write a string of data to the EE device from the I<sup>2</sup>Cx bus.

**Include:** `i2c.h`

**Prototype:**

```
unsigned char EEPageWrite(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * wrptr );  
unsigned char EEPageWrite1(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * wrptr );  
unsigned char EEPageWrite2(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * wrptr );
```

**Arguments:**

**control**  
EEPROM control / bus device select address byte.

**address**  
EEPROM internal address location.

**wrptr**  
Character type pointer in PICmicro MCU RAM. The data objects pointed to by *wrptr* will be written to the EE device.

**Remarks:** This function writes a null terminated string of data to the I<sup>2</sup>C EE memory device. The null character itself is not transmitted.

**Return Value:**

- 0 if there were no errors
- 1 if there was a bus collision error
- 2 if there was a NOT ACK error
- 3 if there was a write collision error

**File Name:**

- `i2c_eepw.c`
- `i2c1eepw.c`
- `i2c2eepw.c`

**Code Example:** `temp = EEPageWrite(0xA0, 0x70, wrptr);`

---

## EERandomRead

## EERandomRead1

## EERandomRead2

---

**Function:** Read a single byte from the I<sup>2</sup>Cx bus.

**Include:** i2c.h

**Prototype:**

```
unsigned int EERandomRead(  
    unsigned char control,  
    unsigned char address );  
unsigned int EERandomRead1(  
    unsigned char control,  
    unsigned char address );  
unsigned int EERandomRead2(  
    unsigned char control,  
    unsigned char address );
```

**Arguments:**

**control**  
EEPROM control / bus device select address byte.

**address**  
EEPROM internal address location.

**Remarks:** This function reads in a single byte from the I<sup>2</sup>Cx bus. The routine can be used for Microchip I<sup>2</sup>C EE memory devices which only require 1 byte of address information.

**Return Value:** The return value contains the value read in the Least Significant Byte and the error condition in the Most Significant Byte. The error condition is:

- 1 if there was a bus collision error
- 2 if there was a NOT ACK error
- 3 if there was a write collision error

**File Name:**

i2c\_eerr.c  
i2cleerr.c  
i2c2eerr.c

**Code Example:**

```
unsigned int temp;  
temp = EERandomRead(0xA0,0x30);
```

## EESequentialRead

## EESequentialRead1

## EESequentialRead2

---

**Function:** Read a string of data from the I<sup>2</sup>Cx bus.

**Include:** i2c.h

**Prototype:**

```
unsigned char EESequentialRead(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * rdptr,  
    unsigned char length );  
unsigned char EESequentialRead1(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * rdptr,  
    unsigned char length );  
unsigned char EESequentialRead2(  
    unsigned char control,  
    unsigned char address,  
    unsigned char * rdptr,  
    unsigned char length );
```

**Arguments:**

**control**  
EEPROM control / bus device select address byte.

**address**  
EEPROM internal address location.

**rdptr**  
Character type pointer to PICmicro MCU RAM area for placement of data read from EEPROM device.

**length**  
Number of bytes to read from EEPROM device.

**Remarks:** This function reads in a predefined string length of data from the I<sup>2</sup>Cx bus. The routine can be used for Microchip I<sup>2</sup>C EE memory devices which only require 1 byte of address information.

**Return Value:** 0 if there were no errors  
-1 if there was a bus collision error  
-2 if there was a NOT ACK error  
-3 if there was a write collision error

**File Name:** i2c\_eesr.c  
i2cleesr.c  
i2c2eesr.c

**Code Example:**

```
unsigned char err;  
err = EESequentialRead(0xA0,  
                        0x70,  
                        rdptr,  
                        15);
```

## 2.4.3 Example of Use

The following is a simple code example illustrating the SSP module configured for I<sup>2</sup>C master communication. The routine illustrates I<sup>2</sup>C communications with a Microchip 24LC01B I<sup>2</sup>C EE memory device.

```
#include "p18cxx.h"
#include "i2c.h"

unsigned char arraywr[] = {1,2,3,4,5,6,7,8,0};
unsigned char arrayrd[20];

//*****
void main(void)
{
    OpenI2C(MASTER, SLEW_ON); // Initialize I2C module
    SSPADD = 9;                //400kHz Baud clock(9) @16MHz
                                //100kHz Baud clock(39) @16MHz

    while(1)
    {
        EEByteWrite(0xA0, 0x30, 0xA5);
        EEAckPolling(0xA0);
        EECurrentAddrRead(0xA0);
        EEPAGEWRITE(0xA0, 0x70, arraywr);
        EEAckPolling(0xA0);
        EESequentialRead(0xA0, 0x70, arrayrd, 20);
        EERandomRead(0xA0, 0x30);
    }
}
```

## 2.5 I/O PORT FUNCTIONS

PORTB is supported with the following functions:

**TABLE 2-6: I/O PORT FUNCTIONS**

Function	Description
ClosePORTB	Disable the interrupts and internal pull-up resistors for PORTB.
CloseRBxINT	Disable interrupts for PORTB pin <i>x</i> .
DisablePullups	Disable the internal pull-up resistors on PORTB.
EnablePullups	Enable the internal pull-up resistors on PORTB.
OpenPORTB	Configure the interrupts and internal pull-up resistors on PORTB.
OpenRBxINT	Enable interrupts for PORTB pin <i>x</i> .

## 2.5.1 Function Descriptions

---

### ClosePORTB

---

**Function:** Disable the interrupts and internal pull-up resistors for PORTB.  
**Include:** portb.h  
**Prototype:** void ClosePORTB( void );  
**Remarks:** This function disables the PORTB interrupt-on-change and the internal pull-up resistors.  
**File Name:** pbclose.c

---

### CloseRB0INT

### CloseRB1INT

### CloseRB2INT

---

**Function:** Disable the interrupts for the specified PORTB pin.  
**Include:** portb.h  
**Prototype:** void CloseRB0INT( void );  
void CloseRB1INT( void );  
void CloseRB2INT( void );  
**Remarks:** This function disables the PORTB interrupt-on-change.  
**File Name:** rb0close.c  
rb1close.c  
rb2close.c

---

---

### DisablePullups

---

**Function:** Disable the internal pull-up resistors on PORTB.  
**Include:** portb.h  
**Prototype:** void DisablePullups( void );  
**Remarks:** This function disables the internal pull-up resistors on PORTB.  
**File Name:** pulldis.c

---

---

### EnablePullups

---

**Function:** Enable the internal pull-up resistors on PORTB.  
**Include:** portb.h  
**Prototype:** void EnablePullups( void );  
**Remarks:** This function enables the internal pull-up resistors on PORTB.  
**File Name:** pullen.c

---

---

## OpenPORTB

---

<b>Function:</b>	Configure the interrupts and internal pull-up resistors on PORTB.								
<b>Include:</b>	portb.h								
<b>Prototype:</b>	void OpenPORTB( unsigned char <i>config</i> );								
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file portb.h.</p> <p><b>Interrupt-on-change:</b></p> <table><tr><td>PORTB_CHANGE_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>PORTB_CHANGE_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Enable Pullups:</b></p> <table><tr><td>PORTB_PULLUPS_ON</td><td>pull-up resistors enabled</td></tr><tr><td>PORTB_PULLUPS_OFF</td><td>pull-up resistors disabled</td></tr></table>	PORTB_CHANGE_INT_ON	Interrupt enabled	PORTB_CHANGE_INT_OFF	Interrupt disabled	PORTB_PULLUPS_ON	pull-up resistors enabled	PORTB_PULLUPS_OFF	pull-up resistors disabled
PORTB_CHANGE_INT_ON	Interrupt enabled								
PORTB_CHANGE_INT_OFF	Interrupt disabled								
PORTB_PULLUPS_ON	pull-up resistors enabled								
PORTB_PULLUPS_OFF	pull-up resistors disabled								
<b>Remarks:</b>	This function configures the interrupts and internal pull-up resistors on PORTB.								
<b>File Name:</b>	pbopen.c								
<b>Code Example:</b>	OpenPORTB( PORTB_CHANGE_INT_ON & PORTB_PULLUPS_ON );								

---

## OpenRB0INT OpenRB1INT OpenRB2INT

---

<b>Function:</b>	Enable interrupts for the specified PORTB pin.												
<b>Include:</b>	portb.h												
<b>Prototype:</b>	void OpenRB0INT( unsigned char <i>config</i> ); void OpenRB1INT( unsigned char <i>config</i> ); void OpenRB2INT( unsigned char <i>config</i> );												
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file portb.h.</p> <p><b>Interrupt-on-change:</b></p> <table><tr><td>PORTB_CHANGE_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>PORTB_CHANGE_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Interrupt-on-edge:</b></p> <table><tr><td>RISING_EDGE_INT</td><td>Interrupt on rising edge</td></tr><tr><td>FALLING_EDGE_INT</td><td>Interrupt on falling edge</td></tr></table> <p><b>Enable Pullups:</b></p> <table><tr><td>PORTB_PULLUPS_ON</td><td>pull-up resistors enabled</td></tr><tr><td>PORTB_PULLUPS_OFF</td><td>pull-up resistors disabled</td></tr></table>	PORTB_CHANGE_INT_ON	Interrupt enabled	PORTB_CHANGE_INT_OFF	Interrupt disabled	RISING_EDGE_INT	Interrupt on rising edge	FALLING_EDGE_INT	Interrupt on falling edge	PORTB_PULLUPS_ON	pull-up resistors enabled	PORTB_PULLUPS_OFF	pull-up resistors disabled
PORTB_CHANGE_INT_ON	Interrupt enabled												
PORTB_CHANGE_INT_OFF	Interrupt disabled												
RISING_EDGE_INT	Interrupt on rising edge												
FALLING_EDGE_INT	Interrupt on falling edge												
PORTB_PULLUPS_ON	pull-up resistors enabled												
PORTB_PULLUPS_OFF	pull-up resistors disabled												
<b>Remarks:</b>	This function configures the interrupts and internal pull-up resistors on PORTB.												
<b>File Name:</b>	rb0open.c rb1open.c rb2open.c												
<b>Code Example:</b>	OpenRB0INT( PORTB_CHANGE_INT_ON & RISING_EDGE_INT & PORTB_PULLUPS_ON );												



## 2.6 MICROWIRE FUNCTIONS

The following routines are provided for devices with a single Microwire peripheral:

**TABLE 2-7: SINGLE MICROWIRE PERIPHERAL FUNCTIONS**

Function	Description
CloseMWire	Disable the SSP module used for Microwire communication.
DataRdyMWire	Indicate completion of the internal write cycle.
getcMWire	Read a byte from the Microwire device.
getsMWire	Read a string from the Microwire device.
OpenMWire	Configure the SSP module for Microwire use.
putcMWire	Write a byte to the Microwire device.
ReadMWire	Read a byte from the Microwire device.
WriteMWire	Write a byte to the Microwire device.

The following routines are provided for devices with multiple Microwire peripherals:

**TABLE 2-8: MULTIPLE MICROWIRE PERIPHERAL FUNCTIONS**

Function	Description
CloseMWire $x$	Disable the SSP $x$ module used for Microwire communication.
DataRdyMWire $x$	Indicate completion of the internal write cycle.
getcMWire $x$	Read a byte from the Microwire device.
getsMWire $x$	Read a string from the Microwire device.
OpenMWire $x$	Configure the SSP $x$ module for Microwire use.
putcMWire $x$	Write a byte to the Microwire device.
ReadMWire $x$	Read a byte from the Microwire device.
WriteMWire $x$	Write a byte to the Microwire device.

### 2.6.1 Function Descriptions

#### CloseMWire

#### CloseMWire1

#### CloseMWire2

<b>Function:</b>	Disable the SSP $x$ module.
<b>Include:</b>	mwire.h
<b>Prototype:</b>	void CloseMWire( void ); void CloseMWire1( void ); void CloseMWire2( void );
<b>Remarks:</b>	Pin I/O returns under control of the TRISC and LATC register settings.
<b>File Name:</b>	mw_close.c mw1close.c mw2close.c

---

## DataRdyMwire

### DataRdyMwire1

### DataRdyMwire2

---

<b>Function:</b>	Indicate whether the Microwire $x$ device has completed the internal write cycle.
<b>Include:</b>	mwire.h
<b>Prototype:</b>	<pre>unsigned char DataRdyMwire( void ); unsigned char DataRdyMwire1( void ); unsigned char DataRdyMwire2( void );</pre>
<b>Remarks:</b>	Determines if Microwire $x$ device is ready.
<b>Return Value:</b>	1 if the Microwire $x$ device is ready 0 if the internal write cycle is not complete or a bus error occurred
<b>File Name:</b>	mw_drdy.c mw1drdy.c mw2drdy.c
<b>Code Example:</b>	<pre>while (!DataRdyMwire());</pre>

---

## getcMwire

### getcMwire1

### getcMwire2

---

getcMwire $x$  is defined as ReadMwire $x$ . See **ReadMwire $x$** .

---

## getsMwire

### getsMwire1

### getsMwire2

---

<b>Function:</b>	Read a string from the Microwire $x$ device.
<b>Include:</b>	mwire.h
<b>Prototype:</b>	<pre>void getsMwire( unsigned char * <i>rdptr</i>,                 unsigned char <i>length</i>); void getsMwire1( unsigned char * <i>rdptr</i>,                 unsigned char <i>length</i>); void getsMwire2( unsigned char * <i>rdptr</i>,                 unsigned char <i>length</i>);</pre>
<b>Arguments:</b>	<b><i>rdptr</i></b> Pointer to PICmicro MCU RAM for placement of data read from Microwire $x$ device. <b><i>length</i></b> Number of bytes to read from Microwire $x$ device.
<b>Remarks:</b>	This function is used to read a predetermined length of data from a Microwire $x$ device. Before using this function, a Read $x$ command with the appropriate address must be issued.
<b>File Name:</b>	mw_gets.c mw1gets.c mw2gets.c
<b>Code Example:</b>	<pre>unsigned char arrayrd[LENGTH]; putcMwire(READ); putcMwire(address); getsMwire(arrayrd, LENGTH);</pre>

---

---

## OpenMwire

### OpenMwire1

### OpenMwire2

---

**Function:** Configure the SSP $x$  module.

**Include:** mwire.h

**Prototype:** void OpenMwire(  
                    unsigned char *sync\_mode* );

**Arguments:** *sync\_mode*  
One of the following values defined in mwire.h:  
                    MWIRE\_FOSC\_4                    clock = FOSC/4  
                    MWIRE\_FOSC\_16                   clock = FOSC/16  
                    MWIRE\_FOSC\_64                   clock = FOSC/64  
                    MWIRE\_FOSC\_TMR2                clock = TMR2 output/2

**Remarks:** OpenMwire $x$  resets the SSP $x$  module to the POR state and then configures the module for Microwire communications.

**File Name:** mw\_open.c  
                    mw1open.c  
                    mw2open.c

**Code Example:** OpenMwire(MWIRE\_FOSC\_16);

---

## putcMwire

### putcMwire1

### putcMwire2

---

putcMwire $x$  is defined as WriteMwire $x$ . See **WriteMwire $x$** .

---

## ReadMwire

## ReadMwire1

## ReadMwire2

## getcMwire

## getcMwire1

## getcMwire2

---

**Function:** Read a byte from a Microwire $x$  device.

**Include:** mwire.h

**Prototype:**

```
unsigned char ReadMwire(  
    unsigned char high_byte,  
    unsigned char low_byte );  
unsigned char ReadMwire1(  
    unsigned char high_byte,  
    unsigned char low_byte );  
unsigned char ReadMwire2(  
    unsigned char high_byte,  
    unsigned char low_byte );  
unsigned char getcMwire(  
    unsigned char high_byte,  
    unsigned char low_byte );  
unsigned char getcMwire1(  
    unsigned char high_byte,  
    unsigned char low_byte );  
unsigned char getcMwire2(  
    unsigned char high_byte,  
    unsigned char low_byte );
```

**Arguments:**

*high\_byte*  
First byte of 16-bit instruction word.

*low\_byte*  
Second byte of 16-bit instruction word.

**Remarks:** This function reads in a single byte from a Microwire $x$  device. The Start bit, opcode and address compose the high and low bytes passed into this function. getcMwire $x$  is defined to be ReadMwire $x$  in mwire.h.

**Return Value:** The return value is the data byte read from the Microwire $x$  device.

**File Name:**

mw\_read.c  
mw1read.c  
mw2read.c  
#define in mwire.h  
#define in mwire.h  
#define in mwire.h

**Code Example:** ReadMwire(0x03, 0x00);

**WriteMwire**

**WriteMwire1**

**WriteMwire2**

**putcMwire**

**putcMwire1**

**putcMwire2**

---

**Function:** This function is used to write out a single data byte (one character).

**Include:** mwire.h

**Prototype:**

```
unsigned char WriteMwire(  
    unsigned char data_out );  
unsigned char WriteMwire1(  
    unsigned char data_out );  
unsigned char WriteMwire2(  
    unsigned char data_out );  
unsigned char putcMwire(  
    unsigned char data_out );  
unsigned char putcMwire1(  
    unsigned char data_out );  
unsigned char putcMwire2(  
    unsigned char data_out );
```

**Arguments:** **data\_out**  
Single byte of data to write to Microwire $x$  device.

**Remarks:** This function writes out single data byte to a Microwire $x$  device utilizing the SSP $x$  module. putcMwire $x$  is defined to be WriteMwire $x$  in mwire.h.

**Return Value:** 0 if the write was successful  
-1 if there was a write collision

**File Name:** mw\_write.c  
mw1write.c  
mw2write.c  
#define in mwire.h  
#define in mwire.h  
#define in mwire.h

**Code Example:** WriteMwire(0x55);

## 2.6.2 Example of Use

The following is a simple code example illustrating the SSP module communicating with a Microchip 93LC66 Microwire EE memory device.

```
#include "p18cxxx.h"
#include "mwire.h"

// 93LC66 x 8
// FUNCTION Prototypes
void main(void);
void ew_enable(void);
void erase_all(void);
void busy_poll(void);
void write_all(unsigned char data);
void byte_read(unsigned char address);
void read_mult(unsigned char address,
               unsigned char *rdptr,
               unsigned char length);
void write_byte(unsigned char address,
                unsigned char data);

// VARIABLE Definitions
unsigned char arrayrd[20];
unsigned char var;

// DEFINE 93LC66 MACROS -- see datasheet for details
#define READ    0x0C
#define WRITE   0x0A
#define ERASE    0x0E
#define EWEN1   0x09
#define EWEN2   0x80
#define ERAL1   0x09
#define ERAL2   0x00
#define WRAL1   0x08
#define WRAL2   0x80
#define EWDS1   0x08
#define EWDS2   0x00
#define W_CS    LATCbits.LATC2

void main(void)
{
    TRISCbits.TRISC2 = 0;
    W_CS = 0;                //ensure CS is negated
    OpenMWire(MWIRE_FOSC_16); //enable SSP peripheral
    ew_enable();             //send erase/write enable
    write_byte(0x13, 0x34); //write byte (address, data)
    busy_poll();
    Nop();
    byte_read(0x13);         //read single byte (address)
    read_mult(0x10, arrayrd, 10); //read multiple bytes
    erase_all();             //erase entire array
    CloseMWire();            //disable SSP peripheral
}
```

```
void ew_enable(void)
{
    W_CS = 1;          //assert chip select
    putcMwire(EWEN1); //enable write command byte 1
    putcMwire(EWEN2); //enable write command byte 2
    W_CS = 0;          //negate chip select
}

void busy_poll(void)
{
    W_CS = 1;
    while(! DataRdyMwire() );
    W_CS = 0;
}

void write_byte(unsigned char address,
                unsigned char data)
{
    W_CS = 1;
    putcMwire(WRITE); //write command
    putcMwire(address); //address
    putcMwire(data); //write single byte
    W_CS = 0;
}

void byte_read(unsigned char address)
{
    W_CS = 1;
    getcMwire(READ,address); //read one byte
    W_CS = 0;
}

void read_mult(unsigned char address,
               unsigned char *rdptr,
               unsigned char length)
{
    W_CS = 1;
    putcMwire(READ); //read command
    putcMwire(address); //address (A7 - A0)
    getsMwire(rdptr, length); //read multiple bytes
    W_CS = 0;
}

void erase_all(void)
{
    W_CS = 1;
    putcMwire(ERAL1); //erase all command byte 1
    putcMwire(ERAL2); //erase all command byte 2
    W_CS = 0;
}
```

## 2.7 PULSE-WIDTH MODULATION FUNCTIONS

The PWM peripheral is supported with the following functions:

**TABLE 2-9: PWM FUNCTIONS**

Function	Description
ClosePWM $x$	Disable PWM channel $x$ .
OpenPWM $x$	Configure PWM channel $x$ .
SetDCPWM $x$	Write a new duty cycle value to PWM channel $x$ .
SetOutputPWM $x$	Sets the PWM output configuration bits for ECCP $x$ .
CloseEPWM $x$ <sup>(1)</sup>	Disable enhanced PWM channel $x$ .
OpenEPWM $x$ <sup>(1)</sup>	Configure enhanced PWM channel $x$ .
SetDCEPWM $x$ <sup>(1)</sup>	Write a new duty cycle value to enhanced PWM channel $x$ .
SetOutputEPWM $x$ <sup>(1)</sup>	Sets the enhanced PWM output configuration bits for ECCP $x$ .

**Note 1:** The enhanced PWM functions are only available on those devices with an ECCPxCON register.

### 2.7.1 Function Descriptions

**ClosePWM1**  
**ClosePWM2**  
**ClosePWM3**  
**ClosePWM4**  
**ClosePWM5**  
**CloseEPWM1**

<b>Function:</b>	Disable PWM channel.
<b>Include:</b>	pwm.h
<b>Prototype:</b>	<pre>void ClosePWM1( void ); void ClosePWM2( void ); void ClosePWM3( void ); void ClosePWM4( void ); void ClosePWM5( void ); void CloseEPWM1( void );</pre>
<b>Remarks:</b>	This function disables the specified PWM channel.
<b>File Name:</b>	<pre>pw1close.c pw2close.c pw3close.c pw4close.c pw5close.c ew1close.c</pre>



OpenPWM1  
OpenPWM2  
OpenPWM3  
OpenPWM4  
OpenPWM5  
OpenEPWM1

---

**Function:** Configure PWM channel.

**Include:** pwm.h

**Prototype:**

```
void OpenPWM1( char period );  
void OpenPWM2( char period );  
void OpenPWM3( char period );  
void OpenPWM4( char period );  
void OpenPWM5( char period );  
void OpenEPWM1( char period );
```

**Arguments:** *period*

Can be any value from 0x00 to 0xff. This value determines the PWM frequency by using the following formula:

$\text{PWM period} = [(period) + 1] \times 4 \times \text{Tosc} \times \text{TMR2 prescaler}$

**Remarks:** This function configures the specified PWM channel for period and for time base. PWM uses only Timer2.

In addition to opening the PWM, Timer2 must also be opened with an **OpenTimer2(...)** statement before the PWM will operate.

**File Name:**

```
pw1open.c  
pw2open.c  
pw3open.c  
pw4open.c  
pw5open.c  
ew1open.c
```

**Code Example:** `OpenPWM1(0xff);`

---

SetDCPWM1  
SetDCPWM2  
SetDCPWM3  
SetDCPWM4  
SetDCPWM5  
SetDCEPWM1

---

**Function:** Write a new duty cycle value to the specified PWM channel duty-cycle registers.

**Include:** pwm.h

**Prototype:**

```
void SetDCPWM1( unsigned int dutycycle );  
void SetDCPWM2( unsigned int dutycycle );  
void SetDCPWM3( unsigned int dutycycle );  
void SetDCPWM4( unsigned int dutycycle );  
void SetDCPWM5( unsigned int dutycycle );  
void SetDCEPWM1( unsigned int dutycycle );
```

**Arguments:** *dutycycle*

The value of *dutycycle* can be any 10-bit number. Only the lower 10-bits of *dutycycle* are written into the duty cycle registers. The duty cycle, or more specifically the high time of the PWM waveform, can be calculated from the following formula:

$$\text{PWM x Duty cycle} = (\text{DCx}<9:0>) \times \text{Tosc}$$

where DCx<9:0> is the 10-bit value specified in the call to this function.

**Remarks:** This function writes the new value for *dutycycle* to the specified PWM channel duty cycle registers.

The maximum resolution of the PWM waveform can be calculated from the period using the following formula:

$$\text{Resolution (bits)} = \log(\text{Fosc/Fpwm}) / \log(2)$$

**File Name:**

```
pw1setdc.c  
pw2setdc.c  
pw3setdc.c  
pw4setdc.c  
pw5setdc.c  
ew1setdc.c
```

**Code Example:** SetDCPWM1 ( 0 ) ;

---

**SetOutputPWM1**  
**SetOutputPWM2**  
**SetOutputPWM3**  
**SetOutputEPWM1**

---

**Function:** Sets the PWM output configuration bits for ECCP.

**Include:** pwm.h

**Prototype:**

```
void SetOutputPWM1 (  
    unsigned char outputconfig,  
    unsigned char outputmode);  
void SetOutputPWM2 (  
    unsigned char outputconfig,  
    unsigned char outputmode);  
void SetOutputPWM3 (  
    unsigned char outputconfig,  
    unsigned char outputmode);  
void SetOutputEPWM1 (  
    unsigned char outputconfig,  
    unsigned char outputmode);
```

**Arguments:** *outputconfig*  
The value of outputconfig can be any one of the following values (defined in pwm.h):

SINGLE_OUT	single output
FULL_OUT_FWD	full-bridge output forward
HALF_OUT	half-bridge output
FULL_OUT_REV	full-bridge output reverse

***outputmode***

The value of outputmode can be any one of the following values (defined in pwm.h):

PWM_MODE_1	P1A and P1C active-high, P1B and P1D active-high
PWM_MODE_2	P1A and P1C active-high, P1B and P1D active-low
PWM_MODE_3	P1A and P1C active-low, P1B and P1D active-high
PWM_MODE_4	P1A and P1C active-low, P1B and P1D active-low

**Remarks:** This is only applicable to those devices with Extended or Enhanced CCP (ECCP).

**File Name:** pw1setoc.c  
pw2setoc.c  
pw3setoc.c  
ew1setoc.c

**Code Example:** SetOutputPWM1 (SINGLE\_OUT, PWM\_MODE\_1);

## 2.8 SPI™ FUNCTIONS

The following routines are provided for devices with a single SPI peripheral:

**TABLE 2-10: SINGLE SPI™ PERIPHERAL FUNCTIONS**

Function	Description
CloseSPI	Disable the SSP module used for SPI™ communications.
DataRdySPI	Determine if a new value is available from the SPI buffer.
getcSPI	Read a byte from the SPI bus.
getsSPI	Read a string from the SPI bus.
OpenSPI	Initialize the SSP module used for SPI communications.
putcSPI	Write a byte to the SPI bus.
putsSPI	Write a string to the SPI bus.
ReadSPI	Read a byte from the SPI bus.
WriteSPI	Write a byte to the SPI bus.

The following routines are provided for devices with multiple SPI peripherals:

**TABLE 2-11: MULTIPLE SPI™ PERIPHERAL FUNCTIONS**

Function	Description
CloseSPIx	Disable the SSPx module used for SPI™ communications.
DataRdySPIx	Determine if a new value is available from the SPIx buffer.
getcSPIx	Read a byte from the SPIx bus.
getsSPIx	Read a string from the SPIx bus.
OpenSPIx	Initialize the SSPx module used for SPI communications.
putcSPIx	Write a byte to the SPIx bus.
putsSPIx	Write a string to the SPIx bus.
ReadSPIx	Read a byte from the SPIx bus.
WriteSPIx	Write a byte to the SPIx bus.

## 2.8.1 Function Descriptions

---

### CloseSPI

#### CloseSPI1

#### CloseSPI2

---

**Function:** Disable the SSPx module.

**Include:** `spi.h`

**Prototype:**  
`void CloseSPI( void );`  
`void CloseSPI1( void );`  
`void CloseSPI2( void );`

**Remarks:** This function disables the SSPx module. Pin I/O returns under the control of the appropriate TRIS and LAT registers.

**File Name:** `spi_clos.c`  
`spi1clos.c`  
`spi2clos.c`

---

### DataRdySPI

#### DataRdySPI1

#### DataRdySPI2

---

**Function:** Determine if the SSPBUFx contains data.

**Include:** `spi.h`

**Prototype:**  
`unsigned char DataRdySPI( void );`  
`unsigned char DataRdySPI1( void );`  
`unsigned char DataRdySPI2( void );`

**Remarks:** This function determines if there is a byte to be read from the SSPBUFx register.

**Return Value:** 0 if there is no data in the SSPBUFx register  
1 if there is data in the SSPBUFx register

**File Name:** `spi_dtrd.c`  
`spi1dtrd.c`  
`spi2dtrd.c`

**Code Example:** `while (!DataRdySPI());`

---

### getcSPI

#### getcSPI1

#### getcSPI2

---

getcSPIx is defined as ReadSPIx. See **ReadSPIx**.

---

## getsSPI

## getsSPI1

## getsSPI2

---

<b>Function:</b>	Read a string from the SPIx bus.
<b>Include:</b>	spi.h
<b>Prototype:</b>	<pre>void getsSPI( unsigned char *rdptr,                unsigned char length ); void getsSPI1( unsigned char *rdptr,                unsigned char length ); void getsSPI2( unsigned char *rdptr,                unsigned char length );</pre>
<b>Arguments:</b>	<p><b>rdptr</b> Pointer to location to store data read from SPIx device.</p> <p><b>length</b> Number of bytes to read from SPIx device.</p>
<b>Remarks:</b>	This function reads in a predetermined data string length from the SPIx bus.
<b>File Name:</b>	spi_gets.c spilgets.c spi2gets.c
<b>Code Example:</b>	<pre>unsigned char wrptr[10]; getsSPI(wrptr, 10);</pre>

---

## OpenSPI

## OpenSPI1

## OpenSPI2

---

<b>Function:</b>	Initialize the SSPx module.																				
<b>Include:</b>	spi.h																				
<b>Prototype:</b>	<pre>void OpenSPI( unsigned char sync_mode,                unsigned char bus_mode,                unsigned char smp_phase ); void OpenSPI1( unsigned char sync_mode,                unsigned char bus_mode,                unsigned char smp_phase ); void OpenSPI2( unsigned char sync_mode,                unsigned char bus_mode,                unsigned char smp_phase );</pre>																				
<b>Arguments:</b>	<p><b>sync_mode</b> One of the following values, defined in spi.h:</p> <table><tr><td>SPI_FOSC_4</td><td>SPI Master mode, clock = FOSC/4</td></tr><tr><td>SPI_FOSC_16</td><td>SPI Master mode, clock = FOSC/16</td></tr><tr><td>SPI_FOSC_64</td><td>SPI Master mode, clock = FOSC/64</td></tr><tr><td>SPI_FOSC_TMR2</td><td>SPI Master mode, clock = TMR2 output/2</td></tr><tr><td>SLV_SSON</td><td>SPI Slave mode, /SS pin control enabled</td></tr><tr><td>SLV_SSOFF</td><td>SPI Slave mode, /SS pin control disabled</td></tr></table> <p><b>bus_mode</b> One of the following values, defined in spi.h:</p> <table><tr><td>MODE_00</td><td>Setting for SPI bus Mode 0,0</td></tr><tr><td>MODE_01</td><td>Setting for SPI bus Mode 0,1</td></tr><tr><td>MODE_10</td><td>Setting for SPI bus Mode 1,0</td></tr><tr><td>MODE_11</td><td>Setting for SPI bus Mode 1,1</td></tr></table>	SPI_FOSC_4	SPI Master mode, clock = FOSC/4	SPI_FOSC_16	SPI Master mode, clock = FOSC/16	SPI_FOSC_64	SPI Master mode, clock = FOSC/64	SPI_FOSC_TMR2	SPI Master mode, clock = TMR2 output/2	SLV_SSON	SPI Slave mode, /SS pin control enabled	SLV_SSOFF	SPI Slave mode, /SS pin control disabled	MODE_00	Setting for SPI bus Mode 0,0	MODE_01	Setting for SPI bus Mode 0,1	MODE_10	Setting for SPI bus Mode 1,0	MODE_11	Setting for SPI bus Mode 1,1
SPI_FOSC_4	SPI Master mode, clock = FOSC/4																				
SPI_FOSC_16	SPI Master mode, clock = FOSC/16																				
SPI_FOSC_64	SPI Master mode, clock = FOSC/64																				
SPI_FOSC_TMR2	SPI Master mode, clock = TMR2 output/2																				
SLV_SSON	SPI Slave mode, /SS pin control enabled																				
SLV_SSOFF	SPI Slave mode, /SS pin control disabled																				
MODE_00	Setting for SPI bus Mode 0,0																				
MODE_01	Setting for SPI bus Mode 0,1																				
MODE_10	Setting for SPI bus Mode 1,0																				
MODE_11	Setting for SPI bus Mode 1,1																				

---

---

## OpenSPI

### OpenSPI1

### OpenSPI2 (Continued)

---

#### *smp\_phase*

One of the following values, defined in `spi.h`:

SMPEND                      Input data sample at end of data out  
SMPMID                      Input data sample at middle of data out

**Remarks:** This function sets up the SSPx module for use with a SPIx bus device.

**File Name:** `spi_open.c`  
`spilopen.c`  
`spi2open.c`

**Code Example:** `OpenSPI(SPI_FOSC_16, MODE_00, SMPEND);`

---

## putcSPI

### putcSPI1

### putcSPI2

---

putcSPIx is defined as WriteSPIx. See **WriteSPIx**.

---

## putsSPI

### putsSPI1

### putsSPI2

---

**Function:** Write a string to the SPIx bus.

**Include:** `spi.h`

**Prototype:** `void putsSPI( unsigned char *wrptr );`  
`void putsSPI1( unsigned char *wrptr );`  
`void putsSPI2( unsigned char *wrptr );`

**Arguments:** *wrptr*  
Pointer to value that will be written to the SPIx bus.

**Remarks:** This function writes out a data string to the SPIx bus device. The routine is terminated by reading a null character in the data string (the null character is not written to the bus).

**File Name:** `spi_puts.c`  
`spilputs.c`  
`spi2puts.c`

**Code Example:** `unsigned char wrptr[] = "Hello!";`  
`putsSPI(wrptr);`

---

---

## ReadSPI

## ReadSPI1

## ReadSPI2

## getcSPI

## getcSPI1

## getcSPI2

---

**Function:** Read a byte from the SPIx bus.

**Include:** spi.h

**Prototype:**

```
unsigned char ReadSPI( void );
unsigned char ReadSPI1( void );
unsigned char ReadSPI2( void );
unsigned char getcSPI( void );
unsigned char getcSPI1( void );
unsigned char getcSPI2( void );
```

**Remarks:** This function initiates a SPIx bus cycle for the acquisition of a byte of data. getcSPIx is defined to be ReadSPIx in spi.h.

**Return Value:** This function returns a byte of data read during a SPIx read cycle.

**File Name:**

```
spi_read.c
spilread.c
spi2read.c
#define in spi.h
#define in spi.h
#define in spi.h
```

**Code Example:**

```
char x;
x = ReadSPI();
```



---

## WriteSPI

## WriteSPI1

## WriteSPI2

## putcSPI

## putcSPI1

## putcSPI2

---

**Function:** Write a byte to the SPIx bus.

**Include:** spi.h

**Prototype:**

```
unsigned char WriteSPI(  
    unsigned char data_out );  
unsigned char WriteSPI1(  
    unsigned char data_out );  
unsigned char WriteSPI2(  
    unsigned char data_out );  
unsigned char putcSPI(  
    unsigned char data_out );  
unsigned char putcSPI1(  
    unsigned char data_out );  
unsigned char putcSPI2(  
    unsigned char data_out );
```

**Arguments:** *data\_out*  
Value to be written to the SPIx bus.

**Remarks:** This function writes a single data byte out and then checks for a write collision. putcSPIx is defined to be WriteSPIx in spi.h.

**Return Value:** 0 if no write collision occurred  
-1 if a write collision occurred

**File Name:** spi\_writ.c  
spi1writ.c  
spi2writ.c  
#define in spi.h  
#define in spi.h  
#define in spi.h

**Code Example:** WriteSPI('a');

## 2.8.2 Example of Use

The following example demonstrates the use of an SSP module to communicate with a Microchip 25C080 SPI EE memory device.

```
#include <p18cxxx.h>
#include <spi.h>

// FUNCTION Prototypes
void main(void);
void set_wren(void);
void busy_polling(void);
unsigned char status_read(void);
void status_write(unsigned char data);
void byte_write(unsigned char addhigh,
                unsigned char addlow,
                unsigned char data);
void page_write(unsigned char addhigh,
                unsigned char addlow,
                unsigned char *wrptr);
void array_read(unsigned char addhigh,
                unsigned char addlow,
                unsigned char *rdptr,
                unsigned char count);
unsigned char byte_read(unsigned char addhigh,
                       unsigned char addlow);

// VARIABLE Definitions
unsigned char arraywr[] = {1,2,3,4,5,6,7,8,9,10,11,12,13,14,15,16,0};

//25C040/080/160 page write size
unsigned char arrayrd[16];
unsigned char var;

#define SPI_CS LATCbits.LATC2

//*****
void main(void)
{
    TRISCbits.TRISC2 = 0;
    SPI_CS = 1; // ensure SPI memory device
               // Chip Select is reset
    OpenSPI(SPI_FOSC_16, MODE_00, SMPEND);
    set_wren();
    status_write(0);

    busy_polling();
    set_wren();
    byte_write(0x00, 0x61, 'E');

    busy_polling();
    var = byte_read(0x00, 0x61);

    set_wren();
    page_write(0x00, 0x30, arraywr);
    busy_polling();

    array_read(0x00, 0x30, arrayrd, 16);
    var = status_read();
}
```

```
    CloseSPI();
    while(1);
}

void set_wren(void)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_WREN);    //send write enable command
    SPI_CS = 1;                //negate chip select
}

void page_write (unsigned char addhigh,
                 unsigned char addlow,
                 unsigned char *wrptr)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_WRITE);   //send write command
    var = putcSPI(addhigh);     //send high byte of address
    var = putcSPI(addlow);      //send low byte of address
    putcSPI(wrptr);             //send data byte
    SPI_CS = 1;                //negate chip select
}

void array_read (unsigned char addhigh,
                 unsigned char addlow,
                 unsigned char *rdptr,
                 unsigned char count)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_READ);    //send read command
    var = putcSPI(addhigh);     //send high byte of address
    var = putcSPI(addlow);      //send low byte of address
    getsSPI(rdptr, count);      //read multiple bytes
    SPI_CS = 1;
}

void byte_write (unsigned char addhigh,
                 unsigned char addlow,
                 unsigned char data)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_WRITE);   //send write command
    var = putcSPI(addhigh);     //send high byte of address
    var = putcSPI(addlow);      //send low byte of address
    var = putcSPI(data);        //send data byte
    SPI_CS = 1;                //negate chip select
}

unsigned char byte_read (unsigned char addhigh,
                        unsigned char addlow)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_READ);    //send read command
    var = putcSPI(addhigh);     //send high byte of address
    var = putcSPI(addlow);      //send low byte of address
    var = getcSPI();            //read single byte
    SPI_CS = 1;
    return (var);
}
```

```
unsigned char status_read (void)
{
    SPI_CS = 0;                //assert chip select
    var = putcSPI(SPI_RDSR); //send read status command
    var = getcSPI();           //read data byte
    SPI_CS = 1;                //negate chip select
    return (var);
}

void status_write (unsigned char data)
{
    SPI_CS = 0;
    var = putcSPI(SPI_WRSR); //write status command
    var = putcSPI(data);     //status byte to write
    SPI_CS = 1;              //negate chip select
}

void busy_polling (void)
{
    do
    {
        SPI_CS = 0;                //assert chip select
        var = putcSPI(SPI_RDSR); //send read status command
        var = getcSPI();           //read data byte
        SPI_CS = 1;                //negate chip select
    } while (var & 0x01);          //stay in loop until !busy
}
```

## 2.9 TIMER FUNCTIONS

The timer peripherals are supported with the following functions:

**TABLE 2-12: TIMER FUNCTIONS**

Function	Description
CloseTimer $x$	Disable timer $x$ .
OpenTimer $x$	Configure and enable timer $x$ .
ReadTimer $x$	Read the value of timer $x$ .
WriteTimer $x$	Write a value into timer $x$ .

### 2.9.1 Function Descriptions

**CloseTimer0**  
**CloseTimer1**  
**CloseTimer2**  
**CloseTimer3**  
**CloseTimer4**

---

<b>Function:</b>	Disable the specified timer.
<b>Include:</b>	timers.h
<b>Prototype:</b>	<pre>void CloseTimer0( void ); void CloseTimer1( void ); void CloseTimer2( void ); void CloseTimer3( void ); void CloseTimer4( void );</pre>
<b>Remarks:</b>	This function disables the interrupt and the specified timer.
<b>File Name:</b>	<pre>t0close.c t1close.c t2close.c t3close.c t4close.c</pre>

---

## OpenTimer0

---

<b>Function:</b>	Configure and enable timer0.																																		
<b>Include:</b>	timers.h																																		
<b>Prototype:</b>	void OpenTimer0( unsigned char <i>config</i> );																																		
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file <code>timers.h</code>.</p> <p><b>Enable Timer0 Interrupt:</b></p> <table><tr><td>TIMER_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>TIMER_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Timer Width:</b></p> <table><tr><td>T0_8BIT</td><td>8-bit mode</td></tr><tr><td>T0_16BIT</td><td>16-bit mode</td></tr></table> <p><b>Clock Source:</b></p> <table><tr><td>T0_SOURCE_EXT</td><td>External clock source (I/O pin)</td></tr><tr><td>T0_SOURCE_INT</td><td>Internal clock source (TOSC)</td></tr></table> <p><b>External Clock Trigger (for T0_SOURCE_EXT):</b></p> <table><tr><td>T0_EDGE_FALL</td><td>External clock on falling edge</td></tr><tr><td>T0_EDGE_RISE</td><td>External clock on rising edge</td></tr></table> <p><b>Prescale Value:</b></p> <table><tr><td>T0_PS_1_1</td><td>1:1 prescale</td></tr><tr><td>T0_PS_1_2</td><td>1:2 prescale</td></tr><tr><td>T0_PS_1_4</td><td>1:4 prescale</td></tr><tr><td>T0_PS_1_8</td><td>1:8 prescale</td></tr><tr><td>T0_PS_1_16</td><td>1:16 prescale</td></tr><tr><td>T0_PS_1_32</td><td>1:32 prescale</td></tr><tr><td>T0_PS_1_64</td><td>1:64 prescale</td></tr><tr><td>T0_PS_1_128</td><td>1:128 prescale</td></tr><tr><td>T0_PS_1_256</td><td>1:256 prescale</td></tr></table>	TIMER_INT_ON	Interrupt enabled	TIMER_INT_OFF	Interrupt disabled	T0_8BIT	8-bit mode	T0_16BIT	16-bit mode	T0_SOURCE_EXT	External clock source (I/O pin)	T0_SOURCE_INT	Internal clock source (TOSC)	T0_EDGE_FALL	External clock on falling edge	T0_EDGE_RISE	External clock on rising edge	T0_PS_1_1	1:1 prescale	T0_PS_1_2	1:2 prescale	T0_PS_1_4	1:4 prescale	T0_PS_1_8	1:8 prescale	T0_PS_1_16	1:16 prescale	T0_PS_1_32	1:32 prescale	T0_PS_1_64	1:64 prescale	T0_PS_1_128	1:128 prescale	T0_PS_1_256	1:256 prescale
TIMER_INT_ON	Interrupt enabled																																		
TIMER_INT_OFF	Interrupt disabled																																		
T0_8BIT	8-bit mode																																		
T0_16BIT	16-bit mode																																		
T0_SOURCE_EXT	External clock source (I/O pin)																																		
T0_SOURCE_INT	Internal clock source (TOSC)																																		
T0_EDGE_FALL	External clock on falling edge																																		
T0_EDGE_RISE	External clock on rising edge																																		
T0_PS_1_1	1:1 prescale																																		
T0_PS_1_2	1:2 prescale																																		
T0_PS_1_4	1:4 prescale																																		
T0_PS_1_8	1:8 prescale																																		
T0_PS_1_16	1:16 prescale																																		
T0_PS_1_32	1:32 prescale																																		
T0_PS_1_64	1:64 prescale																																		
T0_PS_1_128	1:128 prescale																																		
T0_PS_1_256	1:256 prescale																																		
<b>Remarks:</b>	This function configures timer0 according to the options specified and then enables it.																																		
<b>File Name:</b>	t0open.c																																		
<b>Code Example:</b>	<pre>OpenTimer0( TIMER_INT_OFF &amp;             T0_8BIT &amp;             T0_SOURCE_INT &amp;             T0_PS_1_32 );</pre>																																		

## OpenTimer1

<b>Function:</b>	Configure and enable timer1.																																										
<b>Include:</b>	timers.h																																										
<b>Prototype:</b>	void OpenTimer1( unsigned char <i>config</i> );																																										
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file <code>timers.h</code>.</p> <p><b>Enable Timer1 Interrupt:</b></p> <table><tr><td>TIMER_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>TIMER_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Timer Width:</b></p> <table><tr><td>T1_8BIT_RW</td><td>8-bit mode</td></tr><tr><td>T1_16BIT_RW</td><td>16-bit mode</td></tr></table> <p><b>Clock Source:</b></p> <table><tr><td>T1_SOURCE_EXT</td><td>External clock source (I/O pin)</td></tr><tr><td>T1_SOURCE_INT</td><td>Internal clock source (TOSC)</td></tr></table> <p><b>Prescaler:</b></p> <table><tr><td>T1_PS_1_1</td><td>1:1 prescale</td></tr><tr><td>T1_PS_1_2</td><td>1:2 prescale</td></tr><tr><td>T1_PS_1_4</td><td>1:4 prescale</td></tr><tr><td>T1_PS_1_8</td><td>1:8 prescale</td></tr></table> <p><b>Oscillator Use:</b></p> <table><tr><td>T1_OSC1EN_ON</td><td>Enable Timer1 oscillator</td></tr><tr><td>T1_OSC1EN_OFF</td><td>Disable Timer1 oscillator</td></tr></table> <p><b>Synchronize Clock Input:</b></p> <table><tr><td>T1_SYNC_EXT_ON</td><td>Sync external clock input</td></tr><tr><td>T1_SYNC_EXT_OFF</td><td>Don't sync external clock input</td></tr></table> <p><b>Use With CCP:</b></p> <p><u>For devices with 1 or 2 CCPs</u></p> <table><tr><td>T3_SOURCE_CCP</td><td>Timer3 source for both CCP's</td></tr><tr><td>T1_CCP1_T3_CCP2</td><td>Timer1 source for CCP1 and Timer3 source for CCP2</td></tr><tr><td>T1_SOURCE_CCP</td><td>Timer1 source for both CCP's</td></tr></table> <p><u>For devices with more than 2 CCPs</u></p> <table><tr><td>T34_SOURCE_CCP</td><td>Timer3 and Timer4 are sources for all CCP's</td></tr><tr><td>T12_CCP12_T34_CCP345</td><td>Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5</td></tr><tr><td>T12_CCP1_T34_CCP2345</td><td>Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5</td></tr><tr><td>T12_SOURCE_CCP</td><td>Timer1 and Timer2 are sources for all CCP's</td></tr></table>	TIMER_INT_ON	Interrupt enabled	TIMER_INT_OFF	Interrupt disabled	T1_8BIT_RW	8-bit mode	T1_16BIT_RW	16-bit mode	T1_SOURCE_EXT	External clock source (I/O pin)	T1_SOURCE_INT	Internal clock source (TOSC)	T1_PS_1_1	1:1 prescale	T1_PS_1_2	1:2 prescale	T1_PS_1_4	1:4 prescale	T1_PS_1_8	1:8 prescale	T1_OSC1EN_ON	Enable Timer1 oscillator	T1_OSC1EN_OFF	Disable Timer1 oscillator	T1_SYNC_EXT_ON	Sync external clock input	T1_SYNC_EXT_OFF	Don't sync external clock input	T3_SOURCE_CCP	Timer3 source for both CCP's	T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2	T1_SOURCE_CCP	Timer1 source for both CCP's	T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's	T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5	T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5	T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's
TIMER_INT_ON	Interrupt enabled																																										
TIMER_INT_OFF	Interrupt disabled																																										
T1_8BIT_RW	8-bit mode																																										
T1_16BIT_RW	16-bit mode																																										
T1_SOURCE_EXT	External clock source (I/O pin)																																										
T1_SOURCE_INT	Internal clock source (TOSC)																																										
T1_PS_1_1	1:1 prescale																																										
T1_PS_1_2	1:2 prescale																																										
T1_PS_1_4	1:4 prescale																																										
T1_PS_1_8	1:8 prescale																																										
T1_OSC1EN_ON	Enable Timer1 oscillator																																										
T1_OSC1EN_OFF	Disable Timer1 oscillator																																										
T1_SYNC_EXT_ON	Sync external clock input																																										
T1_SYNC_EXT_OFF	Don't sync external clock input																																										
T3_SOURCE_CCP	Timer3 source for both CCP's																																										
T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2																																										
T1_SOURCE_CCP	Timer1 source for both CCP's																																										
T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's																																										
T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5																																										
T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5																																										
T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's																																										
<b>Remarks:</b>	This function configures timer1 according to the options specified and then enables it.																																										
<b>File Name:</b>	t1open.c																																										
<b>Code Example:</b>	<pre>OpenTimer1( TIMER_INT_ON    &amp;              T1_8BIT_RW      &amp;              T1_SOURCE_EXT    &amp;              T1_PS_1_1        &amp;              T1_OSC1EN_OFF    &amp;              T1_SYNC_EXT_OFF );</pre>																																										

---

## OpenTimer2

---

<b>Function:</b>	Configure and enable timer2.																																		
<b>Include:</b>	timers.h																																		
<b>Prototype:</b>	void OpenTimer2( unsigned char <i>config</i> );																																		
<b>Arguments:</b>	<p><i>config</i> A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file <code>timers.h</code>.</p> <p><b>Enable Timer2 Interrupt:</b></p> <table><tr><td>TIMER_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>TIMER_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Prescale Value:</b></p> <table><tr><td>T2_PS_1_1</td><td>1:1 prescale</td></tr><tr><td>T2_PS_1_4</td><td>1:4 prescale</td></tr><tr><td>T2_PS_1_16</td><td>1:16 prescale</td></tr></table> <p><b>Postscale Value:</b></p> <table><tr><td>T2_POST_1_1</td><td>1:1 postscale</td></tr><tr><td>T2_POST_1_2</td><td>1:2 postscale</td></tr><tr><td>:</td><td>:</td></tr><tr><td>T2_POST_1_15</td><td>1:15 postscale</td></tr><tr><td>T2_POST_1_16</td><td>1:16 postscale</td></tr></table> <p><b>Use With CCP:</b></p> <p><u>For devices with 1 or 2 CCPs</u></p> <table><tr><td>T3_SOURCE_CCP</td><td>Timer3 source for both CCP's</td></tr><tr><td>T1_CCP1_T3_CCP2</td><td>Timer1 source for CCP1 and Timer3 source for CCP2</td></tr><tr><td>T1_SOURCE_CCP</td><td>Timer1 source for both CCP's</td></tr></table> <p><u>For devices with more than 2 CCPs</u></p> <table><tr><td>T34_SOURCE_CCP</td><td>Timer3 and Timer4 are sources for all CCP's</td></tr><tr><td>T12_CCP12_T34_CCP345</td><td>Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5</td></tr><tr><td>T12_CCP1_T34_CCP2345</td><td>Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5</td></tr><tr><td>T12_SOURCE_CCP</td><td>Timer1 and Timer2 are sources for all CCP's</td></tr></table>	TIMER_INT_ON	Interrupt enabled	TIMER_INT_OFF	Interrupt disabled	T2_PS_1_1	1:1 prescale	T2_PS_1_4	1:4 prescale	T2_PS_1_16	1:16 prescale	T2_POST_1_1	1:1 postscale	T2_POST_1_2	1:2 postscale	:	:	T2_POST_1_15	1:15 postscale	T2_POST_1_16	1:16 postscale	T3_SOURCE_CCP	Timer3 source for both CCP's	T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2	T1_SOURCE_CCP	Timer1 source for both CCP's	T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's	T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5	T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5	T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's
TIMER_INT_ON	Interrupt enabled																																		
TIMER_INT_OFF	Interrupt disabled																																		
T2_PS_1_1	1:1 prescale																																		
T2_PS_1_4	1:4 prescale																																		
T2_PS_1_16	1:16 prescale																																		
T2_POST_1_1	1:1 postscale																																		
T2_POST_1_2	1:2 postscale																																		
:	:																																		
T2_POST_1_15	1:15 postscale																																		
T2_POST_1_16	1:16 postscale																																		
T3_SOURCE_CCP	Timer3 source for both CCP's																																		
T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2																																		
T1_SOURCE_CCP	Timer1 source for both CCP's																																		
T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's																																		
T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5																																		
T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5																																		
T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's																																		
<b>Remarks:</b>	This function configures timer2 according to the options specified and then enables it.																																		
<b>File Name:</b>	t2open.c																																		
<b>Code Example:</b>	<pre>OpenTimer2( TIMER_INT_OFF &amp;             T2_PS_1_1      &amp;             T2_POST_1_8    );</pre>																																		



## OpenTimer3

<b>Function:</b>	Configure and enable timer3.																																						
<b>Include:</b>	timers.h																																						
<b>Prototype:</b>	void OpenTimer3( unsigned char <i>config</i> );																																						
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file <code>timers.h</code>.</p> <p><b>Enable Timer3 Interrupt:</b></p> <table><tr><td>TIMER_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>TIMER_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Timer Width:</b></p> <table><tr><td>T3_8BIT_RW</td><td>8-bit mode</td></tr><tr><td>T3_16BIT_RW</td><td>16-bit mode</td></tr></table> <p><b>Clock Source:</b></p> <table><tr><td>T3_SOURCE_EXT</td><td>External clock source (I/O pin)</td></tr><tr><td>T3_SOURCE_INT</td><td>Internal clock source (TOSC)</td></tr></table> <p><b>Prescale Value:</b></p> <table><tr><td>T3_PS_1_1</td><td>1:1 prescale</td></tr><tr><td>T3_PS_1_2</td><td>1:2 prescale</td></tr><tr><td>T3_PS_1_4</td><td>1:4 prescale</td></tr><tr><td>T3_PS_1_8</td><td>1:8 prescale</td></tr></table> <p><b>Synchronize Clock Input:</b></p> <table><tr><td>T3_SYNC_EXT_ON</td><td>Sync external clock input</td></tr><tr><td>T3_SYNC_EXT_OFF</td><td>Don't sync external clock input</td></tr></table> <p><b>Use With CCP:</b></p> <p><u>For devices with 1 or 2 CCPs</u></p> <table><tr><td>T3_SOURCE_CCP</td><td>Timer3 source for both CCP's</td></tr><tr><td>T1_CCP1_T3_CCP2</td><td>Timer1 source for CCP1 and Timer3 source for CCP2</td></tr><tr><td>T1_SOURCE_CCP</td><td>Timer1 source for both CCP's</td></tr></table> <p><u>For devices with more than 2 CCPs</u></p> <table><tr><td>T34_SOURCE_CCP</td><td>Timer3 and Timer4 are sources for all CCP's</td></tr><tr><td>T12_CCP12_T34_CCP345</td><td>Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5</td></tr><tr><td>T12_CCP1_T34_CCP2345</td><td>Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5</td></tr><tr><td>T12_SOURCE_CCP</td><td>Timer1 and Timer2 are sources for all CCP's</td></tr></table>	TIMER_INT_ON	Interrupt enabled	TIMER_INT_OFF	Interrupt disabled	T3_8BIT_RW	8-bit mode	T3_16BIT_RW	16-bit mode	T3_SOURCE_EXT	External clock source (I/O pin)	T3_SOURCE_INT	Internal clock source (TOSC)	T3_PS_1_1	1:1 prescale	T3_PS_1_2	1:2 prescale	T3_PS_1_4	1:4 prescale	T3_PS_1_8	1:8 prescale	T3_SYNC_EXT_ON	Sync external clock input	T3_SYNC_EXT_OFF	Don't sync external clock input	T3_SOURCE_CCP	Timer3 source for both CCP's	T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2	T1_SOURCE_CCP	Timer1 source for both CCP's	T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's	T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5	T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5	T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's
TIMER_INT_ON	Interrupt enabled																																						
TIMER_INT_OFF	Interrupt disabled																																						
T3_8BIT_RW	8-bit mode																																						
T3_16BIT_RW	16-bit mode																																						
T3_SOURCE_EXT	External clock source (I/O pin)																																						
T3_SOURCE_INT	Internal clock source (TOSC)																																						
T3_PS_1_1	1:1 prescale																																						
T3_PS_1_2	1:2 prescale																																						
T3_PS_1_4	1:4 prescale																																						
T3_PS_1_8	1:8 prescale																																						
T3_SYNC_EXT_ON	Sync external clock input																																						
T3_SYNC_EXT_OFF	Don't sync external clock input																																						
T3_SOURCE_CCP	Timer3 source for both CCP's																																						
T1_CCP1_T3_CCP2	Timer1 source for CCP1 and Timer3 source for CCP2																																						
T1_SOURCE_CCP	Timer1 source for both CCP's																																						
T34_SOURCE_CCP	Timer3 and Timer4 are sources for all CCP's																																						
T12_CCP12_T34_CCP345	Timer1 and Timer2 are sources for CCP1 and CCP2 and Timer3 and Timer4 are sources for CCP3 through CCP5																																						
T12_CCP1_T34_CCP2345	Timer1 and Timer2 are sources for CCP1 and Timer3 and Timer4 are sources for CCP2 through CCP5																																						
T12_SOURCE_CCP	Timer1 and Timer2 are sources for all CCP's																																						
<b>Remarks:</b>	This function configures timer3 according to the options specified and then enables it.																																						
<b>File Name:</b>	t3open.c																																						
<b>Code Example:</b>	<pre>OpenTimer3( TIMER_INT_ON    &amp;              T3_8BIT_RW      &amp;              T3_SOURCE_EXT    &amp;              T3_PS_1_1        &amp;              T3_OSC1EN_OFF    &amp;              T3_SYNC_EXT_OFF );</pre>																																						

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## OpenTimer4

---

<b>Function:</b>	Configure and enable timer4.																				
<b>Include:</b>	timers.h																				
<b>Prototype:</b>	void OpenTimer4( unsigned char <i>config</i> );																				
<b>Arguments:</b>	<p><i>config</i></p> <p>A bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file <code>timers.h</code>.</p> <p><b>Enable Timer4 Interrupt:</b></p> <table><tr><td>TIMER_INT_ON</td><td>Interrupt enabled</td></tr><tr><td>TIMER_INT_OFF</td><td>Interrupt disabled</td></tr></table> <p><b>Prescale Value:</b></p> <table><tr><td>T4_PS_1_1</td><td>1:1 prescale</td></tr><tr><td>T4_PS_1_4</td><td>1:4 prescale</td></tr><tr><td>T4_PS_1_16</td><td>1:16 prescale</td></tr></table> <p><b>Postscale Value:</b></p> <table><tr><td>T4_POST_1_1</td><td>1:1 postscale</td></tr><tr><td>T4_POST_1_2</td><td>1:2 postscale</td></tr><tr><td>:</td><td>:</td></tr><tr><td>T4_POST_1_15</td><td>1:15 postscale</td></tr><tr><td>T4_POST_1_16</td><td>1:16 postscale</td></tr></table>	TIMER_INT_ON	Interrupt enabled	TIMER_INT_OFF	Interrupt disabled	T4_PS_1_1	1:1 prescale	T4_PS_1_4	1:4 prescale	T4_PS_1_16	1:16 prescale	T4_POST_1_1	1:1 postscale	T4_POST_1_2	1:2 postscale	:	:	T4_POST_1_15	1:15 postscale	T4_POST_1_16	1:16 postscale
TIMER_INT_ON	Interrupt enabled																				
TIMER_INT_OFF	Interrupt disabled																				
T4_PS_1_1	1:1 prescale																				
T4_PS_1_4	1:4 prescale																				
T4_PS_1_16	1:16 prescale																				
T4_POST_1_1	1:1 postscale																				
T4_POST_1_2	1:2 postscale																				
:	:																				
T4_POST_1_15	1:15 postscale																				
T4_POST_1_16	1:16 postscale																				
<b>Remarks:</b>	This function configures timer4 according to the options specified and then enables it.																				
<b>File Name:</b>	t4open.c																				
<b>Code Example:</b>	<pre>OpenTimer4( TIMER_INT_OFF &amp;             T4_PS_1_1      &amp;             T4_POST_1_8     );</pre>																				

---

**ReadTimer0**  
**ReadTimer1**  
**ReadTimer2**  
**ReadTimer3**  
**ReadTimer4**

---

**Function:** Read the value of the specified timer.

**Include:** `timers.h`

**Prototype:** `unsigned int ReadTimer0( void );`  
`unsigned int ReadTimer1( void );`  
`unsigned char ReadTimer2( void );`  
`unsigned int ReadTimer3( void );`  
`unsigned char ReadTimer4( void );`

**Remarks:** These functions read the value of the respective timer register(s).

Timer0: TMR0L, TMR0H

Timer1: TMR1L, TMR1H

Timer2: TMR2

Timer3: TMR3L, TMR3H

Timer4: TMR4

**Note:** When using a timer in 8-bit mode that may be configured in 16-bit mode (e.g., timer0), the upper byte is not ensured to be zero. The user may wish to cast the result to a char for correct results. For example:

```
// Example of reading a 16-bit result
// from a 16-bit timer operating in
// 8-bit mode:
unsigned int result;
result = (unsigned char) ReadTimer0();
```

**Return Value:** The current value of the timer.

**File Name:** `t0read.c`  
`t1read.c`  
`t2read.c`  
`t3read.c`  
`t4read.c`

---

## WriteTimer0 WriteTimer1 WriteTimer2 WriteTimer3 WriteTimer4

---

**Function:** Write a value into the specified timer.

**Include:** `timers.h`

**Prototype:**

```
void WriteTimer0( unsigned int  timer );  
void WriteTimer1( unsigned int  timer );  
void WriteTimer2( unsigned char timer );  
void WriteTimer3( unsigned int  timer );  
void WriteTimer4( unsigned char timer );
```

**Arguments:** *timer*  
The value that will be loaded into the specified timer.

**Remarks:** These functions write a value to the respective timer register(s):

Timer0:	TMR0L, TMR0H
Timer1:	TMR1L, TMR1H
Timer2:	TMR2
Timer3:	TMR3L, TMR3H
Timer4:	TMR4

**File Name:** `t0write.c`  
`t1write.c`  
`t2write.c`  
`t3write.c`  
`t4write.c`

**Code Example:** `WriteTimer0( 10000 );`

## 2.9.2 Example of Use

```
#include <p18C452.h>
#include <timers.h>
#include <usart.h>
#include <stdlib.h>

void main( void )
{
    int result;
    char str[7];

    // configure timer0
    OpenTimer0( TIMER_INT_OFF &
               T0_SOURCE_INT  &
               T0_PS_1_32 );

    // configure USART
    OpenUSART( USART_TX_INT_OFF &
              USART_RX_INT_OFF &
              USART_ASYNC_MODE &
              USART_EIGHT_BIT  &
              USART_CONT_RX,
              25                );

    while( 1 )
    {
        while( ! PORTBbits.RB3 ); // wait for RB3 high
        result = ReadTimer0();    // read timer

        if( result > 0xc000 )     // exit loop if value
            break;                // is out of range

        WriteTimer0( 0 );        // restart timer

        ultoa( result, str );    // convert timer to string
        putsUSART( str );        // print string
    }

    CloseTimer0();               // close modules
    CloseUSART();
}
```

## 2.10 USART FUNCTIONS

The following routines are provided for devices with a single USART peripheral:

**TABLE 2-13: SINGLE USART PERIPHERAL FUNCTIONS**

Function	Description
BusyUSART	Is the USART transmitting?
CloseUSART	Disable the USART.
DataRdyUSART	Is data available in the USART read buffer?
getcUSART	Read a byte from the USART.
getsUSART	Read a string from the USART.
OpenUSART	Configure the USART.
putcUSART	Write a byte to the USART.
putsUSART	Write a string from data memory to the USART.
putrsUSART	Write a string from program memory to the USART.
ReadUSART	Read a byte from the USART.
WriteUSART	Write a byte to the USART.
baudUSART	Set the baud rate configuration bits for enhanced USART.

The following routines are provided for devices with multiple USART peripherals:

**TABLE 2-14: MULTIPLE USART PERIPHERAL FUNCTIONS**

Function	Description
Busy $x$ USART	Is USART $x$ transmitting?
Close $x$ USART	Disable USART $x$ .
DataRdy $x$ USART	Is data available in the read buffer of USART $x$ ?
getc $x$ USART	Read a byte from USART $x$ .
gets $x$ USART	Read a string from USART $x$ .
Open $x$ USART	Configure USART $x$ .
putc $x$ USART	Write a byte to USART $x$ .
puts $x$ USART	Write a string from data memory to USART $x$ .
putrs $x$ USART	Write a string from program memory to USART $x$ .
Read $x$ USART	Read a byte from USART $x$ .
Write $x$ USART	Write a byte to USART $x$ .
baud $x$ USART	Set the baud rate configuration bits for enhanced USART $x$ .

## 2.10.1 Function Descriptions

---

### BusyUSART Busy1USART Busy2USART

---

<b>Function:</b>	Is the USART transmitting?
<b>Include:</b>	usart.h
<b>Prototype:</b>	<pre>char BusyUSART( void ); char Busy1USART( void ); char Busy2USART( void );</pre>
<b>Remarks:</b>	Returns a value indicating if the USART transmitter is currently busy. This function should be used prior to commencing a new transmission. BusyUSART should be used on parts with a single USART peripheral. Busy1USART and Busy2USART should be used on parts with multiple USART peripherals.
<b>Return Value:</b>	0 if the USART transmitter is idle 1 if the USART transmitter is in use
<b>File Name:</b>	ubusy.c u1busy.c u2busy.c
<b>Code Example:</b>	<pre>while (BusyUSART());</pre>

---

### CloseUSART Close1USART Close2USART

---

<b>Function:</b>	Disable the specified USART.
<b>Include:</b>	usart.h
<b>Prototype:</b>	<pre>void CloseUSART( void ); void Close1USART( void ); void Close2USART( void );</pre>
<b>Remarks:</b>	This function disables the interrupts, transmitter and receiver for the specified USART. CloseUSART should be used on parts with a single USART peripheral. Close1USART and Close2USART should be used on parts with multiple USART peripherals.
<b>File Name:</b>	uclose.c u1close.c u2close.c

---

## DataRdyUSART DataRdy1USART DataRdy2USART

---

<b>Function:</b>	Is data available in the read buffer?
<b>Include:</b>	usart.h
<b>Prototype:</b>	<pre>char DataRdyUSART( void ); char DataRdy1USART( void ); char DataRdy2USART( void );</pre>
<b>Remarks:</b>	This function returns the status of the RCIF flag bit in the PIR register. DataRdyUSART should be used on parts with a single USART peripheral. DataRdy1USART and DataRdy2USART should be used on parts with multiple USART peripherals.
<b>Return Value:</b>	1 if data is available 0 if data is not available
<b>File Name:</b>	udrdy.c u1drdy.c u2drdy.c
<b>Code Example:</b>	<pre>while (!DataRdyUSART());</pre>

---

---

## getcUSART getc1USART getc2USART

---

getcUSART is defined as ReadUSART. See [ReadUSART](#)

---

---

## getsUSART gets1USART gets2USART

---

<b>Function:</b>	Read a fixed-length string of characters from the specified USART.
<b>Include:</b>	usart.h
<b>Prototype:</b>	<pre>void getsUSART ( char * <i>buffer</i>,                 unsigned char <i>len</i> ); void gets1USART ( char * <i>buffer</i>,                 unsigned char <i>len</i> ); void gets2USART ( char * <i>buffer</i>,                 unsigned char <i>len</i> );</pre>
<b>Arguments:</b>	<i>buffer</i> A pointer to the location where incoming characters are to be stored. <i>len</i> The number of characters to read from the USART.
<b>Remarks:</b>	This function only works in 8-bit transmit/receive mode. This function waits for and reads <i>len</i> number of characters out of the specified USART. There is no time out when waiting for characters to arrive. getsUSART should be used on parts with a single USART peripheral. gets1USART and gets2USART should be used on parts with multiple USART peripherals.
<b>File Name:</b>	ugets.c u1gets.c u2gets.c
<b>Code Example:</b>	<pre>char inputstr[10]; getsUSART( inputstr, 5 );</pre>

---



## OpenUSART Open1USART Open2USART

**Function:** Configure the specified USART module.

**Include:** usart.h

**Prototype:**

```
void OpenUSART( unsigned char config,
                unsigned int spbrg);
void Open1USART( unsigned char config,
                 unsigned int spbrg);
void Open2USART( unsigned char config,
                 unsigned int spbrg);
```

**Arguments:** *config*  
A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file usart.h.

**Interrupt on Transmission:**

USART_TX_INT_ON	Transmit interrupt ON
USART_TX_INT_OFF	Transmit interrupt OFF

**Interrupt on Receipt:**

USART_RX_INT_ON	Receive interrupt ON
USART_RX_INT_OFF	Receive interrupt OFF

**USART Mode:**

USART_ASYNCH_MODE	Asynchronous Mode
USART_SYNC_MODE	Synchronous Mode

**Transmission Width:**

USART_EIGHT_BIT	8-bit transmit/receive
USART_NINE_BIT	9-bit transmit/receive

**Slave/Master Select\*:**

USART_SYNC_SLAVE	Synchronous Slave mode
USART_SYNC_MASTER	Synchronous Master mode

**Reception mode:**

USART_SINGLE_RX	Single reception
USART_CONT_RX	Continuous reception

**Baud rate:**

USART_BRGH_HIGH	High baud rate
USART_BRGH_LOW	Low baud rate

\* Applies to Synchronous mode only

***spbrg***

This is the value that is written to the baud rate generator register which determines the baud rate at which the USART operates. The formulas for baud rate are:

Asynchronous mode, high speed:

$$\text{FOSC} / (16 * (\textit{spbrg} + 1))$$

Asynchronous mode, low speed:

$$\text{FOSC} / (64 * (\textit{spbrg} + 1))$$

Synchronous mode:

$$\text{FOSC} / (4 * (\textit{spbrg} + 1))$$

Where FOSC is the oscillator frequency.

**Remarks:** This function configures the USART module according to the specified configuration options.

OpenUSART should be used on parts with a single USART peripheral. Open1USART and Open2USART should be used on parts with multiple USART peripherals.

**File Name:** uopen.c  
u1open.c  
u2open.c

---

## OpenUSART Open1USART Open2USART (Continued)

---

**Code Example:**     OpenUSART1 ( USART\_TX\_INT\_OFF &  
                                  USART\_RX\_INT\_OFF &  
                                  USART\_ASYNC\_MODE &  
                                  USART\_EIGHT\_BIT &  
                                  USART\_CONT\_RX &  
                                  USART\_BRGH\_HIGH,  
                                  25                    ) ;

---

---

## putcUSART putc1USART putc2USART

---

putcxUSART is defined as WritexUSART. See **WriteUSART**

---

---

## putsUSART puts1USART puts2USART putrsUSART putrs1USART putrs2USART

---

**Function:**           Writes a string of characters to the USART including the null character.

**Include:**            usart.h

**Prototype:**          void putsUSART( char \***data** );  
                        void puts1USART( char \***data** );  
                        void puts2USART( char \***data** );  
                        void putrsUSART( const rom char \***data** );  
                        void putrs1USART( const rom char \***data** );  
                        void putrs2USART( const rom char \***data** );

**Arguments:**         **data**  
                        Pointer to a null-terminated string of data.

**Remarks:**           This function only works in 8-bit transmit/receive mode. This function writes a string of data to the USART including the null character. Strings located in data memory should be used with the “puts” versions of these functions. Strings located in program memory, including string literals, should be used with the “putrs” versions of these functions. putsUSART and putrsUSART should be used on parts with a single USART peripheral. The other functions should be used on parts with multiple USART peripherals.

**File Name:**          uputs.c  
                        u1puts.c  
                        u2puts.c  
                        uputrs.c  
                        u1putrs.c  
                        u2putrs.c

**Code Example:**      putrsUSART( "Hello World!" );

---

**ReadUSART**  
**Read1USART**  
**Read2USART**  
**getcUSART**  
**getc1USART**  
**getc2USART**

---

**Function:** Read a byte (one character) out of the USART receive buffer, including the 9th bit if enabled.

**Include:** usart.h

**Prototype:**

```
char ReadUSART( void );
char Read1USART( void );
char Read2USART( void );
char getcUSART( void );
char getc1USART( void );
char getc2USART( void );
```

**Remarks:** This function reads a byte out of the USART receive buffer. The Status bits and the 9th data bits are saved in a union with the following declaration:

```
union USART
{
    unsigned char val;
    struct
    {
        unsigned RX_NINE:1;
        unsigned TX_NINE:1;
        unsigned FRAME_ERROR:1;
        unsigned OVERRUN_ERROR:1;
        unsigned fill:4;
    };
};
```

The 9th bit is read-only if 9-bit mode is enabled. The Status bits are always read.

On a part with a single USART peripheral, the `getcUSART` and `ReadUSART` functions should be used and the status information is read into a variable named `USART_Status` which is of the type `USART` described above.

On a part with multiple USART peripherals, the `getcUSART` and `ReadUSART` functions should be used and the status information is read into a variable named `USARTx_Status` which is of the type `USART` described above.

**Return Value:** This function returns the next character in the USART receive buffer.

**File Name:**

```
uread.c
ulread.c
u2read.c
#define in usart.h
#define in usart.h
#define in usart.h
```

**Code Example:**

```
int result;
result = ReadUSART();
result |= (unsigned int)
    USART_Status.RX_NINE << 8;
```

---

**WriteUSART**  
**Write1USART**  
**Write2USART**  
**putcUSART**  
**putc1USART**  
**putc2USART**

---

**Function:** Write a byte (one character) to the USART transmit buffer, including the 9th bit if enabled.

**Include:** usart.h

**Prototype:**

```
void WriteUSART( char data );  
void Write1USART( char data );  
void Write2USART( char data );  
void putcUSART( char data );  
void putc1USART( char data );  
void putc2USART( char data );
```

**Arguments:** **data**  
The value to be written to the USART.

**Remarks:** This function writes a byte to the USART transmit buffer. If 9-bit mode is enabled, the 9th bit is written from the field TX\_NINE, found in a variable of type USART:

```
union USART  
{  
    unsigned char val;  
    struct  
    {  
        unsigned RX_NINE:1;  
        unsigned TX_NINE:1;  
        unsigned FRAME_ERROR:1;  
        unsigned OVERRUN_ERROR:1;  
        unsigned fill:4;  
    };  
};
```

On a part with a single USART peripheral, the putcUSART and WriteUSART functions should be used and the Status register is named USART\_Status which is of the type USART described above. On a part with multiple USART peripherals, the putcxUSART and WritexUSART functions should be used and the status register is named USARTx\_Status which is of the type USART described above.

**File Name:**

```
uwrite.c  
ulwrite.c  
u2write.c  
#define in usart.h  
#define in usart.h  
#define in usart.h
```

**Code Example:**

```
unsigned int outval;  
USART1_Status.TX_NINE = (outval & 0x0100)  
                        >> 8;  
Write1USART( (char) outval );
```

---

## baudUSART baud1USART baud2USART

---

<b>Function:</b>	Set the baud rate configuration bits for enhanced USART operation.																
<b>Include:</b>	usart.h																
<b>Prototype:</b>	<pre>void baudUSART( unsigned char <i>baudconfig</i> ); void baud1USART( unsigned char <i>baudconfig</i> ); void baud2USART( unsigned char <i>baudconfig</i> );</pre>																
<b>Arguments:</b>	<p><b><i>baudconfig</i></b> A bitmask that is created by performing a bitwise AND ('&amp;') operation with a value from each of the categories listed below. These values are defined in the file <code>usart.h</code>:</p> <p><b>Clock Idle State:</b></p> <table><tr><td>BAUD_IDLE_CLK_HIGH</td><td>Clock idle state is a high level</td></tr><tr><td>BAUD_IDLE_CLK_LOW</td><td>Clock idle state is a low level</td></tr></table> <p><b>Baud Rate Generation:</b></p> <table><tr><td>BAUD_16_BIT_RATE</td><td>16-bit baud generation rate</td></tr><tr><td>BAUD_8_BIT_RATE</td><td>8-bit baud generation rate</td></tr></table> <p><b>RX Pin Monitoring:</b></p> <table><tr><td>BAUD_WAKEUP_ON</td><td>RX pin monitored</td></tr><tr><td>BAUD_WAKEUP_OFF</td><td>RX pin not monitored</td></tr></table> <p><b>Baud Rate Measurement:</b></p> <table><tr><td>BAUD_AUTO_ON</td><td>Auto baud rate measurement enabled</td></tr><tr><td>BAUD_AUTO_OFF</td><td>Auto baud rate measurement disabled</td></tr></table>	BAUD_IDLE_CLK_HIGH	Clock idle state is a high level	BAUD_IDLE_CLK_LOW	Clock idle state is a low level	BAUD_16_BIT_RATE	16-bit baud generation rate	BAUD_8_BIT_RATE	8-bit baud generation rate	BAUD_WAKEUP_ON	RX pin monitored	BAUD_WAKEUP_OFF	RX pin not monitored	BAUD_AUTO_ON	Auto baud rate measurement enabled	BAUD_AUTO_OFF	Auto baud rate measurement disabled
BAUD_IDLE_CLK_HIGH	Clock idle state is a high level																
BAUD_IDLE_CLK_LOW	Clock idle state is a low level																
BAUD_16_BIT_RATE	16-bit baud generation rate																
BAUD_8_BIT_RATE	8-bit baud generation rate																
BAUD_WAKEUP_ON	RX pin monitored																
BAUD_WAKEUP_OFF	RX pin not monitored																
BAUD_AUTO_ON	Auto baud rate measurement enabled																
BAUD_AUTO_OFF	Auto baud rate measurement disabled																
<b>Remarks:</b>	These functions are only available for processors with enhanced USART capability.																
<b>File Name:</b>	ubaud.c u1baud.c u2baud.c																
<b>Code Example:</b>	<pre>baudUSART (BAUD_IDLE_CLK_HIGH &amp;            BAUD_16_BIT_RATE &amp;            BAUD_WAKEUP_ON &amp;            BAUD_AUTO_ON) ;</pre>																

## 2.10.2 Example of Use

```
#include <p18C452.h>
#include <usart.h>

void main(void)
{
    // configure USART
    OpenUSART( USART_TX_INT_OFF    &
               USART_RX_INT_OFF    &
               USART_ASYNC_MODE    &
               USART_EIGHT_BIT     &
               USART_CONT_RX        &
               USART_BRGH_HIGH,
               25 );

    while(1)
    {
        while( ! PORTAbits.RA0 ); //wait for RA0 high

        WriteUSART( PORTD );      //write value of PORTD

        if(PORTD == 0x80)         // check for termination
            break;                // value
    }

    CloseUSART();
}
```

## Chapter 3. Software Peripheral Library

### 3.1 INTRODUCTION

This chapter documents software peripheral library functions. The source code for all of these functions is included with MPLAB C18 in the `src\traditional\pmc` and `src\extended\pmc` subdirectories of the compiler installation.

See the *MPASM™ Assembler*, *MPLINK™ Object Linker*, *MPLIB™ Object Librarian* User's Guide (DS33014) for more information about building libraries.

The following peripherals are supported by MPLAB C18 library routines

- External LCD Functions (**Section 3.2 “External LCD Functions”**)
- External CAN2510 Functions (**Section 3.3 “External CAN2510 Functions”**)
- Software I<sup>2</sup>C™ Functions (**Section 3.4 “Software I<sup>2</sup>C Functions”**)
- Software SPI™ Functions (**Section 3.5 “Software SPI™ Functions”**)
- Software UART Functions (**Section 3.6 “Software UART Functions”**)

### 3.2 EXTERNAL LCD FUNCTIONS

These functions are designed to allow the control of a Hitachi HD44780 LCD controller using I/O pins from a PIC18 microcontroller. The following functions are provided:

**TABLE 3-1: EXTERNAL LCD FUNCTIONS**

Function	Description
BusyXLCD	Is the LCD controller busy?
OpenXLCD	Configure the I/O lines used for controlling the LCD and initialize the LCD.
putcXLCD	Write a byte to the LCD controller.
putsXLCD	Write a string from data memory to the LCD.
putrsXLCD	Write a string from program memory to the LCD.
ReadAddrXLCD	Read the address byte from the LCD controller.
ReadDataXLCD	Read a byte from the LCD controller.
SetCGRamAddr	Set the character generator address.
SetDDRamAddr	Set the display data address.
WriteCmdXLCD	Write a command to the LCD controller.
WriteDataXLCD	Write a byte to the LCD controller.

The precompiled versions of these functions use default pin assignments that can be changed by redefining the following macro assignments in the file `xlcd.h`, found in the `h` subdirectory of the compiler installation:

**TABLE 3-2: MACROS FOR SELECTING LCD PIN ASSIGNMENTS**

LCD Controller Line	Macros	Default Value	Use
E Pin	E_PIN	PORTBbits.RB4	Pin used for the E line.
	TRIS_E	DDRBbits.RB4	Bit that controls the direction of the pin associated with the E line.
RS Pin	RS_PIN	PORTBbits.RB5	Pin used for the RS line.
	TRIS_RS	DDRBbits.RB5	Bit that controls the direction of the pin associated with the RS line.
RW Pin	RW_PIN	PORTBbits.RB6	Pin used for the RW line.
	TRIS_RW	DDRBbits.RB6	Bit that controls the direction of the pin associated with the RW line.
Data Lines	DATA_PORT	PORTB	Pins used for DATA lines. These routines assume all pins are on a single port.
	TRIS_DATA_PORT	DDRB	Data Direction register associated with the DATA lines.

The libraries that are provided can operate in either a 4-bit mode or 8-bit mode. When operating in 8-bit mode, all the lines of a single port are used. When operating in 4-bit mode, either the upper 4 bits or lower 4 bits of a single port are used. The table below lists the macros used for selecting between 4- or 8-bit mode and for selecting which bits of a port are used when operating in 4-bit mode.

**TABLE 3-3: MACROS FOR SELECTING 4- OR 8-BIT MODE**

Macro	Default Value	Use
BIT8	not defined	If this value is defined when the library functions are built, they will operate in 8-bit Transfer mode. Otherwise, they will operate in 4-bit Transfer mode.
UPPER	not defined	When BIT8 is not defined, this value determines which nibble of the DATA_PORT is used for data transfer.  If UPPER is defined, the upper 4 bits (4:7) of DATA_PORT are used. If UPPER is not defined, the lower 4 bits (0:3) of DATA_PORT are used.

After these definitions have been made, the user must recompile the XLCD routines and then include the updated files in the project. This can be accomplished by adding the XLCD source files into the project or by recompiling the library files using the provided batch files.



The XLCD libraries also require that the following functions be defined by the user to provide the appropriate delays:

**TABLE 3-4: XLCD DELAY FUNCTIONS**

Function	Behavior
DelayFor18TCY	Delay for 18 cycles.
DelayPORXLCD	Delay for 15 ms.
DelayXLCD	Delay for 5 ms.

## 3.2.1 Function Descriptions

### BusyXLCD

<b>Function:</b>	Is the LCD controller busy?
<b>Include:</b>	xlcd.h
<b>Prototype:</b>	unsigned char BusyXLCD( void );
<b>Remarks:</b>	This function returns the status of the busy flag of the Hitachi HD44780 LCD controller.
<b>Return Value:</b>	1 if the controller is busy 0 otherwise.
<b>File Name:</b>	busyxlcd.c
<b>Code Example:</b>	while( BusyXLCD() );

### OpenXLCD

<b>Function:</b>	Configure the PIC® I/O pins and initialize the LCD controller.
<b>Include:</b>	xlcd.h
<b>Prototype:</b>	void OpenXLCD( unsigned char <i>lcdtype</i> );
<b>Arguments:</b>	<b>lcdtype</b> A bitmask that is created by performing a bitwise AND operation ('&') with a value from each of the categories listed below. These values are defined in the file xlcd.h. <b>Data Interface:</b> FOUR_BIT            4-bit Data Interface mode EIGHT_BIT          8-bit Data Interface mode <b>LCD Configuration:</b> LINE_5X7           5x7 characters, single line display LINE_5X10          5x10 characters display LINES_5X7          5x7 characters, multiple line display
<b>Remarks:</b>	This function configures the PIC18 I/O pins used to control the Hitachi HD44780 LCD controller. It also initializes this controller.
<b>File Name:</b>	openxlcd.c
<b>Code Example:</b>	OpenXLCD( EIGHT_BIT & LINES_5X7 );

### putcXLCD

See **WriteDataXLCD**.

---

## putsXLCD putsXLCD

---

<b>Function:</b>	Write a string to the Hitachi HD44780 LCD controller.
<b>Include:</b>	xlcd.h
<b>Prototype:</b>	<pre>void putsXLCD( char *<i>buffer</i> ); void putsXLCD( const rom char *<i>buffer</i> );</pre>
<b>Arguments:</b>	<p><i>buffer</i> Pointer to characters to be written to the LCD controller.</p>
<b>Remarks:</b>	<p>This function writes a string of characters located in <i>buffer</i> to the Hitachi HD44780 LCD controller. It stops transmission when a null character is encountered. The null character is not transmitted. Strings located in data memory should be used with the “puts” versions of these functions.</p> <p>Strings located in program memory, including string literals, should be used with the “puts” versions of these functions.</p>
<b>File Name:</b>	<pre>putsxlcd.c putrxlcd.c</pre>
<b>Code Example:</b>	<pre>char mybuff [20]; putsXLCD( "Hello World" ); putsXLCD( mybuff );</pre>

---

## ReadAddrXLCD

---

<b>Function:</b>	Read the address byte from the Hitachi HD44780 LCD controller.
<b>Include:</b>	xlcd.h
<b>Prototype:</b>	<pre>unsigned char ReadAddrXLCD( void );</pre>
<b>Remarks:</b>	<p>This function reads the address byte from the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the <i>BusyXLCD</i> function.</p> <p>The address read from the controller is for the character generator RAM or the display data RAM depending on the previous <i>Set??RamAddr</i> function that was called.</p>
<b>Return Value:</b>	This function returns an 8-bit quantity. The address is contained in the lower order 7 bits and the BUSY status flag in the Most Significant bit.
<b>File Name:</b>	<pre>readaddr.c</pre>
<b>Code Example:</b>	<pre>char addr; while ( BusyXLCD() ); addr = ReadAddrXLCD();</pre>

---

## ReadDataXLCD

---

**Function:** Read a data byte from the Hitachi HD44780 LCD controller.

**Include:** `xlcd.h`

**Prototype:** `char ReadDataXLCD( void );`

**Remarks:** This function reads a data byte from the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the `BusyXLCD` function. The data read from the controller is for the character generator RAM or the display data RAM depending on the previous `Set??RamAddr` function that was called.

**Return Value:** This function returns the 8-bit data value.

**File Name:** `readdata.c`

**Code Example:**

```
char data;
while ( BusyXLCD() );
data = ReadAddrXLCD();
```

---

## SetCGRamAddr

---

**Function:** Set the character generator address.

**Include:** `xlcd.h`

**Prototype:** `void SetCGRamAddr( unsigned char addr );`

**Arguments:** **addr**  
Character generator address.

**Remarks:** This function sets the character generator address of the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the `BusyXLCD` function.

**File Name:** `setcgram.c`

**Code Example:**

```
char cgaddr = 0x1F;
while( BusyXLCD() );
SetCGRamAddr( cgaddr );
```

---

## SetDDRamAddr

---

**Function:** Set the display data address.

**Include:** `xlcd.h`

**Prototype:** `void SetDDRamAddr( unsigned char addr );`

**Arguments:** **addr**  
Display data address.

**Remarks:** This function sets the display data address of the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the `BusyXLCD` function.

**File Name:** `setddram.c`

**Code Example:**

```
char ddaddr = 0x10;
while( BusyXLCD() );
SetDDRamAddr( ddaddr );
```

---

## WriteCmdXLCD

---

<b>Function:</b>	Write a command to the Hitachi HD44780 LCD controller.																										
<b>Include:</b>	xlcd.h																										
<b>Prototype:</b>	void WriteCmdXLCD( unsigned char <i>cmd</i> );																										
<b>Arguments:</b>	<p><i>cmd</i> Specifies the command to be performed. The command may be one of the following values defined in xlcd.h:</p> <table><tr><td>DOFF</td><td>Turn display off</td></tr><tr><td>CURSOR_OFF</td><td>Enable display with no cursor</td></tr><tr><td>BLINK_ON</td><td>Enable display with blinking cursor</td></tr><tr><td>BLINK_OFF</td><td>Enable display with unblinking cursor</td></tr><tr><td>SHIFT_CUR_LEFT</td><td>Cursor shifts to the left</td></tr><tr><td>SHIFT_CUR_RIGHT</td><td>Cursor shifts to the right</td></tr><tr><td>SHIFT_DISP_LEFT</td><td>Display shifts to the left</td></tr><tr><td>SHIFT_DISP_RIGHT</td><td>Display shifts to the right</td></tr></table> <p>Alternatively, the command may be a bitmask that is created by performing a bitwise AND operation ('&amp;') with a value from each of the categories listed below. These values are defined in the file xlcd.h.</p> <p><b>Data Transfer Mode:</b></p> <table><tr><td>FOUR_BIT</td><td>4-bit Data Interface mode</td></tr><tr><td>EIGHT_BIT</td><td>8-bit Data Interface mode</td></tr></table> <p><b>Display Type:</b></p> <table><tr><td>LINE_5X7</td><td>5x7 characters, single line</td></tr><tr><td>LINE_5X10</td><td>5x10 characters display</td></tr><tr><td>LINES_5X7</td><td>5x7 characters, multiple lines</td></tr></table>	DOFF	Turn display off	CURSOR_OFF	Enable display with no cursor	BLINK_ON	Enable display with blinking cursor	BLINK_OFF	Enable display with unblinking cursor	SHIFT_CUR_LEFT	Cursor shifts to the left	SHIFT_CUR_RIGHT	Cursor shifts to the right	SHIFT_DISP_LEFT	Display shifts to the left	SHIFT_DISP_RIGHT	Display shifts to the right	FOUR_BIT	4-bit Data Interface mode	EIGHT_BIT	8-bit Data Interface mode	LINE_5X7	5x7 characters, single line	LINE_5X10	5x10 characters display	LINES_5X7	5x7 characters, multiple lines
DOFF	Turn display off																										
CURSOR_OFF	Enable display with no cursor																										
BLINK_ON	Enable display with blinking cursor																										
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SHIFT_CUR_RIGHT	Cursor shifts to the right																										
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EIGHT_BIT	8-bit Data Interface mode																										
LINE_5X7	5x7 characters, single line																										
LINE_5X10	5x10 characters display																										
LINES_5X7	5x7 characters, multiple lines																										
<b>Remarks:</b>	This function writes the command byte to the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the BusyXLCD function.																										
<b>File Name:</b>	wcmdxlcd.c																										
<b>Code Example:</b>	<pre>while( BusyXLCD() ); WriteCmdXLCD( EIGHT_BIT &amp; LINES_5X7 ); WriteCmdXLCD( BLINK_ON ); WriteCmdXLCD( SHIFT_DISP_LEFT );</pre>																										

---

## putcXLCD WriteDataXLCD

---

<b>Function:</b>	Writes a byte to the Hitachi HD44780 LCD controller.
<b>Include:</b>	xlcd.h
<b>Prototype:</b>	void WriteDataXLCD( char <i>data</i> );
<b>Arguments:</b>	<p><i>data</i> The value of <i>data</i> can be any 8-bit value, but should correspond to the character RAM table of the HD44780 LCD controller.</p>
<b>Remarks:</b>	<p>This function writes a data byte to the Hitachi HD44780 LCD controller. The LCD controller should not be busy when this operation is performed – this can be verified using the BusyXLCD function.</p> <p>The data read from the controller is for the character generator RAM or the display data RAM depending on the previous Set??RamAddr function that was called.</p>
<b>File Name:</b>	writdata.c

## 3.2.2 Example of Use

```
#include <p18C452.h>
#include <xlcd.h>
#include <delays.h>
#include <usart.h>

void DelayFor18TCY( void )
{
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
    Nop();
}

void DelayPORXLCD (void)
{
    Delay1KTCYx(60); // Delay of 15ms
                    // Cycles = (TimeDelay * Fosc) / 4
                    // Cycles = (15ms * 16MHz) / 4
                    // Cycles = 60,000

    return;
}

void DelayXLCD (void)
{
    Delay1KTCYx(20); // Delay of 5ms
                    // Cycles = (TimeDelay * Fosc) / 4
                    // Cycles = (5ms * 16MHz) / 4
                    // Cycles = 20,000

    return;
}

void main( void )
{
    char data;

    // configure external LCD
    OpenXLCD( EIGHT_BIT & LINES_5X7 );

    // configure USART
    OpenUSART( USART_TX_INT_OFF & USART_RX_INT_OFF &
               USART_ASYNC_MODE & USART_EIGHT_BIT &
               USART_CONT_RX,
               25 );

    while(1)
    {
        while(!DataRdyUSART()); //wait for data
        data = ReadUSART();      //read data
        WriteDataXLCD(data);     //write to LCD
        if(data=='Q')
            break;
    }

    CloseUSART();
}
```

## 3.3 EXTERNAL CAN2510 FUNCTIONS

This section documents the MCP2510 external peripheral library functions. The following functions are provided:

**TABLE 3-5: EXTERNAL CAN2510 FUNCTIONS**

Function	Description
CAN2510BitModify	Modifies the specified bits in a register to the new values.
CAN2510ByteRead	Reads the MCP2510 register specified by the address.
CAN2510ByteWrite	Writes a value to the MCP2510 register specified by the address.
CAN2510DataRead	Reads a message from the specified receive buffer.
CAN2510DataReady	Determines if data is waiting in the specified receive buffer.
CAN2510Disable	Drives the selected PIC18CXXX I/O pin high to disable the Chip Select of the MCP2510. <sup>(1)</sup>
CAN2510Enable	Drives the selected PIC18CXXX I/O pin low to Chip Select the MCP2510. <sup>(1)</sup>
CAN2510ErrorState	Reads the current Error State of the CAN bus.
CAN2510Init	Initialize the PIC18CXXX SPI port for communications to the MCP2510 and then configures the MCP2510 registers to interface with the CAN bus.
CAN2510InterruptEnable	Modifies the CAN2510 interrupt enable bits (CANINTE register) to the new values.
CAN2510InterruptStatus	Indicates the source of the CAN2510 interrupt.
CAN2510LoadBufferStd	Loads a Standard data frame into the specified transfer buffer.
CAN2510LoadBufferXtd	Loads an Extended data frame into the specified transfer buffer.
CAN2510LoadRTRStd	Loads a Standard remote frame into the specified transfer buffer.
CAN2510LoadRTRXtd	Loads an Extended remote frame into the specified transfer buffer.
CAN2510ReadMode	Reads the MCP2510 current mode of operation.
CAN2510ReadStatus	Reads the status of the MCP2510 Transmit and Receive Buffers.
CAN2510Reset	Resets the MCP2510.
CAN2510SendBuffer	Requests message transmission for the specified transmit buffer(s).
CAN2510SequentialRead	Reads the number of specified bytes in the MCP2510, starting at the specified address. These values will be stored in DataArray.
CAN2510SequentialWrite	Writes the number of specified bytes in the MCP2510, starting at the specified address. These values will be written from DataArray.
CAN2510SetBufferPriority	Loads the specified priority for the specified transmit buffer.
CAN2510SetMode	Configures the MCP2510 mode of operation.
CAN2510SetMsgFilterStd	Configures ALL of the filter and mask values of the specific receive buffer for a standard message.

**TABLE 3-5: EXTERNAL CAN2510 FUNCTIONS (CONTINUED)**

Function	Description
CAN2510SetMsgFilterXtd	Configures ALL of the filter and mask values of the specific receive buffer for a extended message.
CAN2510SetSingleFilterStd	Configures the specified Receive filter with a filter value for a Standard (Std) message.
CAN2510SetSingleFilterXtd	Configures the specified Receive filter with a filter value for a Extended (Xtd) message.
CAN2510SetSingleMaskStd	Configures the specified Receive buffer mask with a mask value for a Standard (Std) format message.
CAN2510SetSingleMaskXtd	Configures the specified Receive buffer mask with a mask value for an Extended (Xtd) message.
CAN2510WriteBuffer	Initiates CAN message transmission of selected buffer.
CAN2510WriteStd	Writes a Standard format message out to the CAN bus using the first available transmit buffer.
CAN2510WriteXtd	Writes an Extended format message out to the CAN bus using the first available transmit buffer.

**Note 1:** The functions CAN2510Enable and CAN2510Disable will need to be recompiled if:

- the PICmicro® MCU assignment of the  $\overline{CS}$  pin is modified from RC2
- the device header file needs to be changed

## 3.3.1 Function Descriptions

### CAN2510BitModify

<b>Function:</b>	Modifies the specified bits in a register to the new values.
<b>Required CAN Mode(s):</b>	All
<b>Include:</b>	can2510.h
<b>Prototype:</b>	<pre>void CAN2510BitModify(     unsigned char <b>addr</b>     unsigned char <b>mask</b>     unsigned char <b>data</b> );</pre>
<b>Arguments:</b>	<p><b>addr</b> The value of <b>addr</b> specifies the address of the MCP2510 register to modify.</p> <p><b>mask</b> The value of <b>mask</b> specifies the bits that will be modified.</p> <p><b>data</b> The value of <b>data</b> specifies the new state of the bits.</p>
<b>Remarks:</b>	This function modifies the contents of the register specified by address, the mask specifies which bits are to be modified and the data specifies the new value to load into those bits. Only specific registers can be modified with the Bit Modify command.
<b>File Name:</b>	canbmod.c

---

## CAN2510ByteRead

---

**Function:** Reads the MCP2510 register specified by the address.

**Required CAN Mode(s):** All

**Include:** can2510.h

**Prototype:**  
unsigned char CAN2510ByteRead(  
    unsigned char *address* );

**Arguments:** *address*  
The address of the MCP2510 that is to be read.

**Remarks:** This function reads a single byte from the MCP2510 at the specified address.

**Return Value:** The contents of the specified address.

**File Name:** readbyte.c

---

---

## CAN2510ByteWrite

---

**Function:** Writes a value to the MCP2510 register specified by the address.

**Required CAN Mode(s):** All

**Include:** can2510.h

**Prototype:**  
void CAN2510ByteWrite(  
    unsigned char *address*,  
    unsigned char *value* );

**Arguments:** *address*  
The address of the MCP2510 that is to be written.

*value*  
The value that is to be written.

**Remarks:** This function writes a single byte from the MCP2510 at the specified address.

**File Name:** wrtbyte.c

---

---

## CAN2510DataRead

---

**Function:** Reads a message from the specified receive buffer.

**Required CAN Mode(s):** All (except Configuration mode)

**Include:** can2510.h

**Prototype:**  
unsigned char CAN2510DataRead(  
    unsigned char *bufferNum*,  
    unsigned long \**msgId*,  
    unsigned char \**numBytes*,  
    unsigned char \**data* );

**Arguments:** *bufferNum*  
Receive buffer from which to read the message. One of the following values:  
    CAN2510\_RXB0   Read receive buffer 0  
    CAN2510\_RXB1   Read receive buffer 1

*msgId*  
Points to a location that will be modified by the function to contain the CAN standard message identifier.

---



---

## CAN2510DataRead (Continued)

---

***numBytes***

Points to a location that will be modified by the function to contain the number of bytes in this message.

***data***

Points to an array that will be modified by the function to contain the message data. This array should be at least 8 bytes long, since that is the maximum message data length.

**Remarks:** This function determines if the message is a standard or extended message, decodes the ID and message length, and fills in the user-supplied locations with the appropriate information. The CAN2510DataReady function should be used to determine if a specified buffer has data to read.

**Return Value:** Function returns one of the following values:

CAN2510_XTDMMSG	Extended format message
CAN2510_STDMMSG	Standard format message
CAN2510_XTDRTR	Remote transmit request (XTD message)
CAN2510_STDRTR	Remote transmit request (STD message)

**File Name:** canread.c

---

## CAN2510DataReady

---

**Function:** Determines if data is waiting in the specified receive buffer.

**Required CAN Mode(s):** All (except Configuration mode)

**Include:** can2510.h

**Prototype:** unsigned char CAN2510DataReady(  
    unsigned char **bufferNum** );

**Arguments:** **bufferNum**  
Receive buffer to check for waiting message. One of the following values:

CAN2510_RXB0	Check Receive Buffer 0
CAN2510_RXB1	Check Receive Buffer 1
CAN2510_RXBX	Check Receive Buffer 0 and Receive Buffer 1

**Remarks:** This function tests the appropriate **RXnIF** bit in the CANINTF register.

**Return Value:** Returns zero if no message detected or a non-zero value if a message was detected.  
1 = buffer0  
2 = buffer1  
3 = both

**File Name:** canready.c

---

## CAN2510Disable

---

**Function:** Drives the selected PIC18CXXX I/O pin high to disable the Chip Select of the MCP2510.

**Required CAN Mode(s):**

All

**Include:** `canenabl.h`

**Note:** This include file will need to be modified if the Chip Select signal is not associated with the RC2 pin of the PICmicro MCU.

**Prototype:** `void CAN2510Disable( void );`

**Arguments:** None

**Remarks:** This function requires that the user modifies the file to specify the PIC18CXXX I/O pin (and Port) that will be used to connect to the MCP2510  $\overline{CS}$  pin. The default pin is RC2.

**Note:** The source file that contains this function (and the `CAN2510Enable` function) must have the definitions modified to correctly specify the Port (A, B, C, ...) and Pin number (1, 2, 3, ...) that is used to control the MCP2510  $\overline{CS}$  pin. After the modification, the processor-specific library must be rebuilt. See **Section 1.5.3 “Rebuilding”** for information on rebuilding.

**File Name:** `canenabl.c`

---

## CAN2510Enable

---

**Function:** Drives the selected PIC18CXXX I/O pin low to Chip Select the MCP2510.

**Required CAN Mode(s):**

All

**Include:** `canenabl.h`

**Note:** This include file will need to be modified if the Chip Select signal is not associated with the RC2 pin of the PICmicro MCU.

**Prototype:** `void CAN2510Enable( void );`

**Remarks:** This function requires that the user modifies the file to specify the PIC18CXXX I/O pin (and Port) that will be used to connect to the MCP2510  $\overline{CS}$  pin. The default pin is RC2.

**Note:** The source file that contains this function (and the `CAN2510Disable` function) must have the definitions modified to correctly specify the Port (A, B, C, ...) and Pin number (1, 2, 3, ...) that is used to control the MCP2510  $\overline{CS}$  pin. After the modification, the processor-specific library must be rebuilt. See **Section 1.5.3 “Rebuilding”** for information on rebuilding.

**File Name:** `canenabl.c`

---

## CAN2510ErrorState

---

**Function:** Reads the current Error State of the CAN bus.

**Required CAN Mode(s):** Normal mode, Loopback mode, Listen Only mode (Error counters are reset in Configuration mode)

**Include:** can2510.h

**Prototype:** unsigned char CAN2510ErrorState( void );

**Remarks:** This function returns the Error State of the CAN bus. The Error State is dependent on the values in the TEC and REC registers.

**Return Value:** Function returns one of the following values:

CAN2510_BUS_OFF	TEC > 255
CAN2510_ERROR_PASSIVE_TX	TEC > 127
CAN2510_ERROR_PASSIVE_RX	REC > 127
CAN2510_ERROR_ACTIVE_WITH_TXWARN	TEC > 95
CAN2510_ERROR_ACTIVE_WITH_RXWARN	REC > 95
CAN2510_ERROR_ACTIVE	TEC ≤ 95 and REC ≤ 95

**File Name:** canerrst.c

---

## CAN2510Init

---

**Function:** Initialize the PIC18CXXX SPI port for communications to the MCP2510 and then configures the MCP2510 registers to interface with the CAN bus.

**Required CAN Mode(s):** Configuration mode

**Include:** can2510.h

**Prototype:** unsigned char CAN2510Init( unsigned short long **BufferConfig**, unsigned short long **BitTimeConfig**, unsigned char **interruptEnables**, unsigned char **SPI\_syncMode**, unsigned char **SPI\_busMode**, unsigned char **SPI\_smpPhase** );

**Arguments:** The values of the following parameters are defined in the include file can2510.h.

***BufferConfig***  
The value of BufferConfig is constructed through the bitwise AND ('&') operation of the following options. Only one option per group function may be selected. The option in the **bold font** is the default value.

***Reset MCP2510 Device***  
Specifies if the MCP2510 Reset command is to be sent. This does not correspond to a bit in the MCP2510 registers.

<b>CAN2510_NORESET</b>	<b>Don't reset the MCP2510</b>
CAN2510_RESET	Reset the MCP2510

***Buffer 0 Filtering***  
Controlled by the RXB0M1:RXB0M0 bits (RXB0CTRL register)

<b>CAN2510_RXB0_USEFILT</b>	<b>Receive all messages, Use filters</b>
CAN2510_RXB0_STDMSG	Receive only Standard messages
CAN2510_RXB0_XTMSG	Receive only Extended messages
CAN2510_RXB0_NOFILT	Receive all messages, NO filters

***Buffer 1 Filtering***  
Controlled by the RXB1M1:RXB1M0 bits (RXB1CTRL register)

<b>CAN2510_RXB1_USEFILT</b>	<b>Receive all messages, Use filters</b>
CAN2510_RXB1_STDMSG	Receive only Standard messages
CAN2510_RXB1_XTMSG	Receive only Extended messages
CAN2510_RXB1_NOFILT	Receive all messages, NO filters

## CAN2510Init (Continued)

### Receive Buffer 0 to Receive Buffer 1 Rollover

Controlled by the BUKT bit (RXB0CTRL register)

**CAN2510\_RXB0\_ROLL**      **If receive buffer 0 is full, message goes to receive buffer 1**  
**CAN2510\_RXB0\_NOROLL**      Rollover Disabled

### RX1BF Pin Setting

Controlled by the B1BFS:B1BFE:B1BFM bits (BFPCTRL register)

**CAN2510\_RX1BF\_OFF**      **RX1BF pin is high-impedance**  
**CAN2510\_RX1BF\_INT**      RX1BF pin is an output which indicates Receive Buffer 1 was loaded. Can be used as an interrupt signal.  
**CAN2510\_RX1BF\_GPOUTH**      RX1BF pin is a general purpose digital output, Output High  
**CAN2510\_RX1BF\_GPOUTL**      RX1BF pin is a general purpose digital output, Output Low

### RX0BF Pin Setting

Controlled by the B0BFS:B0BFE:B0BFM bits (BFPCTRL register)

**CAN2510\_RX0BF\_OFF**      **RX0BF pin is high-impedance**  
**CAN2510\_RX0BF\_INT**      RX0BF pin is an output which indicates Receive Buffer 0 was loaded. Can be used as an interrupt signal.  
**CAN2510\_RX0BF\_GPOUTH**      RX0BF pin is a general purpose digital output, Output High  
**CAN2510\_RX0BF\_GPOUTL**      RX0BF pin is a general purpose digital output, Output Low

### TX2 Pin Setting

Controlled by the B2RTSM bit (TXRTSCTRL register)

**CAN2510\_TX2\_GPIN**      **TX2RTS pin is a digital input**  
**CAN2510\_TX2\_RTS**      TX2RTS pin is an input used to initiate a Request To Send frame from TXBUF2

### TX1 Pin Setting

Controlled by the B1RTSM bit (TXRTSCTRL register)

**CAN2510\_TX1\_GPIN**      **TX1RTS pin is a digital input**  
**CAN2510\_TX1\_RTS**      TX1RTS pin is an input used to initiate a Request To Send frame from TXBUF1

### TX0 Pin Setting

Controlled by the B0RTSM bit (TXRTSCTRL register)

**CAN2510\_TX0\_GPIN**      **TX0RTS pin is a digital input**  
**CAN2510\_TX0\_RTS**      TX0RTS pin is an input used to initiate a Request To Send frame from TXBUF0

### Request Mode of Operation

Controlled by the REQOP2:REQOP0 bits (CANCTRL register)

**CAN2510\_REQ\_CONFIG**      **Configuration mode**  
**CAN2510\_REQ\_NORMAL**      Normal Operation mode  
**CAN2510\_REQ\_SLEEP**      Sleep mode  
**CAN2510\_REQ\_LOOPBACK**      Loop Back mode  
**CAN2510\_REQ\_LISTEN**      Listen Only mode

### CLKOUT Pin Setting

Controlled by the CLKEN:CLKPRE1:CLKPRE0 bits (CANCTRL register)

**CAN2510\_CLKOUT\_8**      **CLKOUT = Fosc / 8**  
**CAN2510\_CLKOUT\_4**      CLKOUT = Fosc / 4  
**CAN2510\_CLKOUT\_2**      CLKOUT = Fosc / 2  
**CAN2510\_CLKOUT\_1**      CLKOUT = Fosc  
**CAN2510\_CLKOUT\_OFF**      CLKOUT is Disabled

## CAN2510Init (Continued)

### BitTimeConfig

The value of BitTimeConfig is constructed through the bitwise AND ('&') operation of the following options. Only one option per group function may be selected. The option in the **bold font** is the default value.

### Baud Rate Prescaler (BRP)

Controlled by the BRP5 : BRP0 bits (CNF1 register)

CAN2510_BRG_1X	<b>Tq = 1 x (2Tosc)</b>
:	:
CAN2510_BRG_64X	Tq = 64 x (2Tosc)

### Synchronization Jump Width

Controlled by the SJW1 : SJW0 bits (CNF1 register)

CAN2510_SJW_1TQ	<b>SJW length = 1 Tq</b>
CAN2510_SJW_2TQ	SJW length = 2 Tq
CAN2510_SJW_3TQ	SJW length = 3 Tq
CAN2510_SJW_4TQ	SJW length = 4 Tq

### Phase 2 Segment Width

Controlled by the PH2SEG2 : PH2SEG0 bits (CNF3 register)

CAN2510_PH2SEG_2TQ	<b>Length = 2 Tq</b>
CAN2510_PH2SEG_3TQ	Length = 3 Tq
CAN2510_PH2SEG_4TQ	Length = 4 Tq
CAN2510_PH2SEG_5TQ	Length = 5 Tq
CAN2510_PH2SEG_6TQ	Length = 6 Tq
CAN2510_PH2SEG_7TQ	Length = 7 Tq
CAN2510_PH2SEG_8TQ	Length = 8 Tq

### Phase 1 Segment Width

Controlled by the PH1SEG2 : PH1SEG0 bits (CNF2 register)

CAN2510_PH1SEG_1TQ	<b>Length = 1 Tq</b>
CAN2510_PH1SEG_2TQ	Length = 2 Tq
CAN2510_PH1SEG_3TQ	Length = 3 Tq
CAN2510_PH1SEG_4TQ	Length = 4 Tq
CAN2510_PH1SEG_5TQ	Length = 5 Tq
CAN2510_PH1SEG_6TQ	Length = 6 Tq
CAN2510_PH1SEG_7TQ	Length = 7 Tq
CAN2510_PH1SEG_8TQ	Length = 8 Tq

### Propagation Segment Width

Controlled by the PRSEG2 : PRSEG0 bits (CNF2 register)

CAN2510_PROPSEG_1TQ	<b>Length = 1 Tq</b>
CAN2510_PROPSEG_2TQ	Length = 2 Tq
CAN2510_PROPSEG_3TQ	Length = 3 Tq
CAN2510_PROPSEG_4TQ	Length = 4 Tq
CAN2510_PROPSEG_5TQ	Length = 5 Tq
CAN2510_PROPSEG_6TQ	Length = 6 Tq
CAN2510_PROPSEG_7TQ	Length = 7 Tq
CAN2510_PROPSEG_8TQ	Length = 8 Tq

### Phase 2 Source

Controlled by the BTLMODE bit (CNF2 register). This determines if the Phase 2 length is determined by the PH2SEG2 : PH2SEG0 bits or the greater length of PH1SEG2 : PH1SEG0 bits and (2Tq).

CAN2510_PH2SOURCE_PH2	<b>Length = PH2SEG2 : PH2SEG0</b>
CAN2510_PH2SOURCE_PH1	Length = greater of PH1SEG2 : PH1SEG0 and 2Tq

### Bit Sample Point Frequency

Controlled by the SAM bit (CNF2 register). This determines if the bit is sampled 1 or 3 times at the sample point.

CAN2510_SAMPLE_1x	<b>Bit is sampled once</b>
CAN2510_SAMPLE_3x	Bit is sampled three times

## CAN2510Init (Continued)

### RX pin Noise Filter in Sleep Mode

Controlled by the WAKFIL bit (CNF3 register). This determines if the RX pin will use a filter to reject noise when the device is in Sleep mode.

<b>CAN2510_RX_FILTER</b>	<b>Filtering on RX pin when in Sleep mode</b>
CAN2510_RX_NOFILTER	No filtering on RX pin when in Sleep mode

### interruptEnables

The value of `interruptEnables` can be a combination of the following values, combined using a bitwise AND ('&') operation. The option in the **bold font** is the default value. Controlled by all bits in the CANINTE register.

<b>CAN2510_NONE_EN</b>	<b>No interrupts enabled</b>
CAN2510_MSGERR_EN	Interrupt on error during message reception or transmission
CAN2510_WAKEUP_EN	Interrupt on CAN bus activity
CAN2510_ERROR_EN	Interrupt on EFLG error condition change
CAN2510_TXB2_EN	Interrupt on transmission buffer 2 becoming empty
CAN2510_TXB1_EN	Interrupt on transmission buffer 1 becoming empty
CAN2510_TXB0_EN	Interrupt on transmission buffer 0 becoming empty
CAN2510_RXB1_EN	Interrupt when message received in receive buffer 1
CAN2510_RXB0_EN	Interrupt when message received in receive buffer 0

### SPI\_syncMode

Specifies the PIC18CXXX SPI synchronization frequency:

<b>CAN2510_SPI_FOSC4</b>	<b>Communicates at Fosc/4</b>
CAN2510_SPI_FOSC16	Communicates at Fosc/16
CAN2510_SPI_FOSC64	Communicates at Fosc/64
CAN2510_SPI_FOSCTMR2	Communicates at TMR2/2

### SPI\_busMode

Specifies the PIC18CXXX SPI bus mode:

<b>CAN2510_SPI_MODE00</b>	<b>Communicate using SPI mode 00</b>
CAN2510_SPI_MODE01	Communicate using SPI mode 01

### SPI\_smpPhase

Specifies the PIC18CXXX SPI sample point:

<b>CAN2510_SPI_SMPMID</b>	<b>Samples in middle of SPI bit</b>
CAN2510_SPI_SMPEND	Samples at end of SPI bit

### Remarks:

This function initializes the PIC18CXXX SPI module, resets the MCP2510 device (if requested) and then configures the MCP2510 registers.

**Note:** When this function is completed, the MCP2510 is left in the Configuration mode.

### Return Value:

Indicates if the MCP2510 could be initialized.  
0 if initialization completed  
-1 if initialization did not complete

### File Name:

caninit.c

---

## CAN2510InterruptEnable

---

**Function:** Modifies the CAN2510 interrupt enable bits (CANINTE register) to the new values.

**Required CAN Mode(s):** All

**Include:** can2510.h,  
spi\_can.h

**Prototype:** void CAN2510InterruptEnable(  
    unsigned char ***interruptEnables*** );

**Arguments:** ***interruptEnables***  
The value of ***interruptEnables*** can be a combination of the following values, combined using a bitwise AND ('&') operation. The option in the **bold font** is the default value. Controlled by all bits in the CANINTE register.

<b>CAN2510_NONE_EN</b>	<b>No interrupts enabled (00000000)</b>
CAN2510_MSGERR_EN	Interrupt on error during message reception or transmission (10000000)
CAN2510_WAKEUP_EN	Interrupt on CAN bus activity (01000000)
CAN2510_ERROR_EN	Interrupt on EFLG error condition change (00100000)
CAN2510_TXB2_EN	Interrupt on transmission buffer 2 becoming empty (00010000)
CAN2510_TXB1_EN	Interrupt on transmission buffer 1 becoming empty (00001000)
CAN2510_TXB0_EN	Interrupt on transmission buffer 0 becoming empty (00000100)
CAN2510_RXB1_EN	Interrupt when message received in receive buffer 1 (00000010)
CAN2510_RXB0_EN	Interrupt when message received in receive buffer 0 (00000001)

**Remarks:** This function updates the CANINTE register with the value that is determined by ANDing the desired interrupt sources.

**File Name:** caninte.c

---

## CAN2510InterruptStatus

---

<b>Function:</b>	Indicates the source of the CAN2510 interrupt.																
<b>Required CAN Mode(s):</b>	All																
<b>Include:</b>	can2510.h, spi_can.h																
<b>Prototype:</b>	unsigned char CAN2510InterruptStatus( void );																
<b>Remarks:</b>	This function reads the CANSTAT register and specifies a code depending on the state of the ICODE2 : ICODE0 bits.																
<b>Return Value:</b>	Function returns one of the following values: <table><tr><td>CAN2510_NO_INTS</td><td>No interrupts occurred</td></tr><tr><td>CAN2510_WAKEUP_INT</td><td>Interrupt on CAN bus activity</td></tr><tr><td>CAN2510_ERROR_INT</td><td>Interrupt on EFLG error condition change</td></tr><tr><td>CAN2510_TXB2_INT</td><td>Interrupt on transmission buffer 2 becoming empty</td></tr><tr><td>CAN2510_TXB1_INT</td><td>Interrupt on transmission buffer 1 becoming empty</td></tr><tr><td>CAN2510_TXB0_INT</td><td>Interrupt on transmission buffer 0 becoming empty</td></tr><tr><td>CAN2510_RXB1_INT</td><td>Interrupt when message received in receive buffer 1</td></tr><tr><td>CAN2510_RXB0_INT</td><td>Interrupt when message received in receive buffer 0</td></tr></table>	CAN2510_NO_INTS	No interrupts occurred	CAN2510_WAKEUP_INT	Interrupt on CAN bus activity	CAN2510_ERROR_INT	Interrupt on EFLG error condition change	CAN2510_TXB2_INT	Interrupt on transmission buffer 2 becoming empty	CAN2510_TXB1_INT	Interrupt on transmission buffer 1 becoming empty	CAN2510_TXB0_INT	Interrupt on transmission buffer 0 becoming empty	CAN2510_RXB1_INT	Interrupt when message received in receive buffer 1	CAN2510_RXB0_INT	Interrupt when message received in receive buffer 0
CAN2510_NO_INTS	No interrupts occurred																
CAN2510_WAKEUP_INT	Interrupt on CAN bus activity																
CAN2510_ERROR_INT	Interrupt on EFLG error condition change																
CAN2510_TXB2_INT	Interrupt on transmission buffer 2 becoming empty																
CAN2510_TXB1_INT	Interrupt on transmission buffer 1 becoming empty																
CAN2510_TXB0_INT	Interrupt on transmission buffer 0 becoming empty																
CAN2510_RXB1_INT	Interrupt when message received in receive buffer 1																
CAN2510_RXB0_INT	Interrupt when message received in receive buffer 0																
<b>File Name:</b>	canints.c																

---

## CAN2510LoadBufferStd

---

<b>Function:</b>	Loads a Standard data frame into the specified transfer buffer.														
<b>Required CAN Mode(s):</b>	All														
<b>Include:</b>	can2510.h														
<b>Prototype:</b>	void CAN2510LoadBufferStd( unsigned char <i>bufferNum</i> , unsigned int <i>msgId</i> , unsigned char <i>numBytes</i> , unsigned char <i>*data</i> );														
<b>Arguments:</b>	<table><tr><td><i>bufferNum</i></td><td>Specifies the buffer to load the message into. One of the following values: <table><tr><td>CAN2510_TXB0</td><td>Transmit buffer 0</td></tr><tr><td>CAN2510_TXB1</td><td>Transmit buffer 1</td></tr><tr><td>CAN2510_TXB2</td><td>Transmit buffer 2</td></tr></table></td></tr><tr><td><i>msgId</i></td><td>CAN message identifier, up to 11 bits for a standard message.</td></tr><tr><td><i>numBytes</i></td><td>Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.</td></tr><tr><td><i>data</i></td><td>Array of data values to be loaded. The array must be at least as large as the value specified in <i>numBytes</i>.</td></tr></table>	<i>bufferNum</i>	Specifies the buffer to load the message into. One of the following values: <table><tr><td>CAN2510_TXB0</td><td>Transmit buffer 0</td></tr><tr><td>CAN2510_TXB1</td><td>Transmit buffer 1</td></tr><tr><td>CAN2510_TXB2</td><td>Transmit buffer 2</td></tr></table>	CAN2510_TXB0	Transmit buffer 0	CAN2510_TXB1	Transmit buffer 1	CAN2510_TXB2	Transmit buffer 2	<i>msgId</i>	CAN message identifier, up to 11 bits for a standard message.	<i>numBytes</i>	Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.	<i>data</i>	Array of data values to be loaded. The array must be at least as large as the value specified in <i>numBytes</i> .
<i>bufferNum</i>	Specifies the buffer to load the message into. One of the following values: <table><tr><td>CAN2510_TXB0</td><td>Transmit buffer 0</td></tr><tr><td>CAN2510_TXB1</td><td>Transmit buffer 1</td></tr><tr><td>CAN2510_TXB2</td><td>Transmit buffer 2</td></tr></table>	CAN2510_TXB0	Transmit buffer 0	CAN2510_TXB1	Transmit buffer 1	CAN2510_TXB2	Transmit buffer 2								
CAN2510_TXB0	Transmit buffer 0														
CAN2510_TXB1	Transmit buffer 1														
CAN2510_TXB2	Transmit buffer 2														
<i>msgId</i>	CAN message identifier, up to 11 bits for a standard message.														
<i>numBytes</i>	Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.														
<i>data</i>	Array of data values to be loaded. The array must be at least as large as the value specified in <i>numBytes</i> .														



---

## CAN2510LoadBufferStd (Continued)

---

**Remarks:** This function loads the message information, but does not transmit the message. Use the `CAN2510WriteBuffer()` function to write the message onto the CAN bus.  
This function does not set the priority of the buffer. Use the `CAN2510SetBufferPriority()` function to set buffer priority.

**File Name:** `canloads.c`

---

---

## CAN2510LoadBufferXtd

---

**Function:** Loads an Extended data frame into the specified transfer buffer.

**Required CAN Mode(s):** All

**Include:** `can2510.h`

**Prototype:**  

```
void CAN2510LoadBufferXtd(  
    unsigned char bufferNum,  
    unsigned long msgId,  
    unsigned char numBytes,  
    unsigned char *data );
```

**Arguments:**

***bufferNum***  
Specifies the buffer to load the message into. One of the following values:  

<code>CAN2510_TXB0</code>	Transmit buffer 0
<code>CAN2510_TXB1</code>	Transmit buffer 1
<code>CAN2510_TXB2</code>	Transmit buffer 2

***msgId***  
CAN message identifier, up to 29 bits for a extended message.

***numBytes***  
Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.

***data***  
Array of data values to be loaded. The array must be at least as large as the value specified in ***numBytes***.

**Remarks:** This function loads the message information, but does not transmit the message. Use the `CAN2510WriteBuffer()` function to write the message onto the CAN bus.  
This function does not set the priority of the buffer. Use the `CAN2510SetBufferPriority()` function to set buffer priority.

**File Name:** `canloadx.c`

---

---

## CAN2510LoadRTRStd

---

**Function:** Loads a Standard remote frame into the specified transfer buffer.

**Required CAN Mode(s):** All

**Include:** can2510.h

**Prototype:**  

```
void CAN2510LoadBufferStd(  
    unsigned char bufferNum,  
    unsigned int  msgId,  
    unsigned char numBytes);
```

**Arguments:**

***bufferNum***  
Specifies the buffer to load the message into. One of the following values:  
CAN2510\_TXB0                      Transmit buffer 0  
CAN2510\_TXB1                      Transmit buffer 1  
CAN2510\_TXB2                      Transmit buffer 2

***msgId***  
CAN message identifier, up to 11 bits for a standard message.

***numBytes***  
Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.

**Remarks:** This function loads the message information, but does not transmit the message. Use the CAN2510WriteBuffer() function to write the message onto the CAN bus.  
This function does not set the priority of the buffer. Use the CAN2510SetBufferPriority() function to set buffer priority.

**File Name:** canlrtrs.c

---

---

## CAN2510LoadRTRXtd

---

**Function:** Loads an Extended remote frame into the specified transfer buffer.

**Required CAN Mode(s):** All

**Include:** can2510.h

**Prototype:**  

```
void CAN2510LoadBufferXtd(  
    unsigned char bufferNum,  
    unsigned long msgId,  
    unsigned char numBytes);
```

**Arguments:**

***bufferNum***  
Specifies the buffer to load the message into. One of the following values:  
CAN2510\_TXB0                      Transmit buffer 0  
CAN2510\_TXB1                      Transmit buffer 1  
CAN2510\_TXB2                      Transmit buffer 2

***msgId***  
CAN message identifier, up to 29 bits for a extended message.

***numBytes***  
Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be stored.

**Remarks:** This function loads the message information, but does not transmit the message. Use the CAN2510WriteBuffer() function to write the message onto the CAN bus.  
This function does not set the priority of the buffer. Use the CAN2510SetBufferPriority() function to set buffer priority.

**File Name:** canlrtrrx.c

---

---

## CAN2510ReadMode

---

**Function:** Reads the MCP2510 current mode of operation.

**Required CAN Mode(s):** All

**Include:** `can2510.h`

**Prototype:** `unsigned char CAN2510ReadMode( void );`

**Remarks:** This function reads the current Operating mode. The mode may have a pending request for a new mode.

**Return Value:** *mode*  
The value of *mode* can be one of the following values (defined in `can2510.h`). Specified by the `OPMODE2:OPMODE0` bits (CANSTAT register). One of the following values:

<code>CAN2510_MODE_CONFIG</code>	Configuration registers can be modified
<code>CAN2510_MODE_NORMAL</code>	Normal (send and receive messages)
<code>CAN2510_MODE_SLEEP</code>	Wait for interrupt
<code>CAN2510_MODE_LISTEN</code>	Listen only, don't send
<code>CAN2510_MODE_LOOPBACK</code>	Used for testing, messages stay internal

**File Name:** `canmoder.c`

---

## CAN2510ReadStatus

---

**Function:** Reads the status of the MCP2510 Transmit and Receive Buffers.

**Required CAN Mode(s):** All

**Include:** `can2510.h`

**Prototype:** `unsigned char CAN2510ReadStatus( void );`

**Remarks:** This function reads the current status of the transmit and receive buffers.

**Return Value:** *status*  
The value of *status* (an unsigned byte) has the following format:

bit 7	TXB2IF
bit 6	TXB2REQ
bit 5	TXB1IF
bit 4	TXB1REQ
bit 3	TXB0IF
bit 2	TXB0REQ
bit 1	RXB1IF
bit 0	RXB0IF

**File Name:** `canstats.c`

---

## CAN2510Reset

---

**Function:** Resets the MCP2510.

**Required CAN Mode(s):** All

**Include:** can2510.h  
spi\_can.h  
spi.h

**Prototype:** void CAN2510Reset( void );

**Remarks:** This function resets the MCP2510.

**File Name:** canreset.c

---

---

## CAN2510SendBuffer

---

**Function:** Requests message transmission for the specified transmit buffer(s).

**Required CAN Mode(s):** Normal mode

**Include:** can2510.h

**Prototype:** void CAN2510WriteBuffer  
( unsigned char *bufferNum* );

**Arguments:** *bufferNum*  
Specifies the buffer to request transmission of. One of the following values:  
CAN2510\_TXB0                      Transmit buffer 0  
CAN2510\_TXB1                      Transmit buffer 1  
CAN2510\_TXB2                      Transmit buffer 2  
CAN2510\_TXB0\_B1                  Transmit buffer 0 and buffer 1  
CAN2510\_TXB0\_B2                  Transmit buffer 0 and buffer 2  
CAN2510\_TXB1\_B2                  Transmit buffer 1 and buffer 2  
CAN2510\_TXB0\_B1\_B2              Transmit buffer 0, buffer 1 and buffer 2

**Remarks:** This function requests transmission of a previously loaded message stored in the specified buffer(s). To load a message, use the CAN2510LoadBufferStd() or CAN2510LoadBufferXtd() routines.

**File Name:** cansend.c

---

---

## CAN2510SequentialRead

---

**Function:** Reads the number of specified bytes in the MCP2510, starting at the specified address. These values will be stored in *DataArray*.

**Required CAN Mode(s):** All

**Include:** can2510.h

**Prototype:** void CAN2510SequentialRead(  
    unsigned char \**DataArray*  
    unsigned char *CAN2510addr*  
    unsigned char *numbytes* );

**Arguments:** *DataArray*  
The start address of the data array that stores the sequential read data.

*CAN2510addr*  
The address of the MCP2510 where the sequential reads start from.

*numbytes*  
The number of bytes to sequentially read.

---

---

## CAN2510SequentialRead (Continued)

---

**Remarks:** This function reads sequential bytes from the MCP2510 starting at the specified address. These values are loaded starting at the first address of the array that is specified.

**File Name:** readseq.c

---

---

## CAN2510SequentialWrite

---

**Function:** Writes the number of specified bytes in the MCP2510, starting at the specified address. These values will be written from *DataArray*.

**Required CAN**

**Mode(s):** All

**Include:** can2510.h

**Prototype:**

```
void CAN2510SequentialWrite(  
    unsigned char *DataArray  
    unsigned char CAN2510addr  
    unsigned char numbytes );
```

**Arguments:**

*DataArray*  
The start address of the data array that contains the sequential write data.

*CAN2510addr*  
The address of the MCP2510 where the sequential writes start from.

*numbytes*  
The number of bytes to sequentially write.

**Remarks:** This function writes sequential bytes to the MCP2510 starting at the specified address. These values are contained starting at the first address of the array that is specified.

**File Name:** wrtseq.c

---

---

## CAN2510SetBufferPriority

---

**Function:** Loads the specified priority for the specified transmit buffer.

**Required CAN**

**Mode(s):** All

**Include:** can2510.h

**Prototype:**

```
void CAN2510SetBufferPriority(  
    unsigned char bufferNum,  
    unsigned char bufferPriority );
```

**Arguments:**

*bufferNum*  
Specifies the buffer to configure the priority of. One of the following values:

CAN2510_TXB0	Transmit buffer 0
CAN2510_TXB1	Transmit buffer 1
CAN2510_TXB2	Transmit buffer 2

*bufferPriority*

Priority of buffer. One of the following values:

CAN2510_PRI_HIGHEST	Highest message priority
CAN2510_PRI_HIGH	High message priority
CAN2510_PRI_LOW	Low message priority
CAN2510_PRI_LOWEST	Lowest message priority

**Remarks:** This function loads the specified priority of an individual buffer.

**File Name:** cansetpr.c

---

---

## CAN2510SetMode

---

<b>Function:</b>	Configures the MCP2510 mode of operation.										
<b>Required CAN Mode(s):</b>	All										
<b>Include:</b>	can2510.h										
<b>Prototype:</b>	void CAN2510SetMode( unsigned char <i>mode</i> );										
<b>Arguments:</b>	<p><i>mode</i></p> <p>The value of <i>mode</i> can be one of the following values (defined in can2510.h). Controlled by the REQOP2:REQOP0 bits (CANCTRL register). One of the following values:</p> <table><tr><td>CAN2510_MODE_CONFIG</td><td>Configuration registers can be modified</td></tr><tr><td>CAN2510_MODE_NORMAL</td><td>Normal (send and receive messages)</td></tr><tr><td>CAN2510_MODE_SLEEP</td><td>Wait for interrupt</td></tr><tr><td>CAN2510_MODE_LISTEN</td><td>Listen only, don't send</td></tr><tr><td>CAN2510_MODE_LOOPBACK</td><td>Used for testing, messages stay internal</td></tr></table>	CAN2510_MODE_CONFIG	Configuration registers can be modified	CAN2510_MODE_NORMAL	Normal (send and receive messages)	CAN2510_MODE_SLEEP	Wait for interrupt	CAN2510_MODE_LISTEN	Listen only, don't send	CAN2510_MODE_LOOPBACK	Used for testing, messages stay internal
CAN2510_MODE_CONFIG	Configuration registers can be modified										
CAN2510_MODE_NORMAL	Normal (send and receive messages)										
CAN2510_MODE_SLEEP	Wait for interrupt										
CAN2510_MODE_LISTEN	Listen only, don't send										
CAN2510_MODE_LOOPBACK	Used for testing, messages stay internal										
<b>Remarks:</b>	This function configures the specified mode. The mode will not change until all pending message transmissions are complete.										
<b>File Name:</b>	canmodes.c										

---

## CAN2510SetMsgFilterStd

---

<b>Function:</b>	Configures ALL of the filter and mask values of the specific receive buffer for a standard message.								
<b>Required CAN Mode(s):</b>	All								
<b>Include:</b>	can2510.h								
<b>Prototype:</b>	unsigned char CAN2510SetMsgFilterStd( unsigned char <i>bufferNum</i> , unsigned int <i>mask</i> , unsigned int <i>*filters</i> );								
<b>Arguments:</b>	<p><i>bufferNum</i></p> <p>Specifies the receive buffer to configure the mask and filters for. One of the following values:</p> <table><tr><td>CAN2510_RXB0</td><td>Configure RXM0, RXF0 and RXF1</td></tr><tr><td>CAN2510_RXB1</td><td>Configure RXM1, RXF2, RXF3, RXF4 and RXF5</td></tr></table> <p><i>mask</i></p> <p>Value to store in the corresponding mask</p> <p><i>filters</i></p> <p>Array of filter values.</p> <table><tr><td>For Buffer 0</td><td>Standard-length messages: Array of 2 unsigned integers</td></tr><tr><td>For Buffer 1</td><td>Standard-length messages: Array of 4 unsigned integers</td></tr></table>	CAN2510_RXB0	Configure RXM0, RXF0 and RXF1	CAN2510_RXB1	Configure RXM1, RXF2, RXF3, RXF4 and RXF5	For Buffer 0	Standard-length messages: Array of 2 unsigned integers	For Buffer 1	Standard-length messages: Array of 4 unsigned integers
CAN2510_RXB0	Configure RXM0, RXF0 and RXF1								
CAN2510_RXB1	Configure RXM1, RXF2, RXF3, RXF4 and RXF5								
For Buffer 0	Standard-length messages: Array of 2 unsigned integers								
For Buffer 1	Standard-length messages: Array of 4 unsigned integers								
<b>Remarks:</b>	This function configures the MCP2510 into Configuration mode, then writes the mask and filter values out to the appropriate registers. Before returning, it configures the MCP2510 to the original mode.								
<b>Return Value:</b>	Indicates if the MCP2510 modes could be modified properly. 0 if initialization and restoration of Operating mode completed -1 if initialization and restoration of Operating mode did not complete								
<b>File Name:</b>	canfms.c								

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---

## CAN2510SetMsgFilterXtd

---

<b>Function:</b>	Configures ALL of the filter and mask values of the specific receive buffer for a extended message.				
<b>Required CAN Mode(s):</b>	All				
<b>Include:</b>	can2510.h				
<b>Prototype:</b>	<pre>unsigned char CAN2510SetMsgFilterXtd(     unsigned char <i>bufferNum</i>,     unsigned long <i>mask</i>,     unsigned long <i>*filters</i> );</pre>				
<b>Arguments:</b>	<p><b><i>bufferNum</i></b> Specifies the receive buffer to configure the mask and filters for one of the following values:</p> <table><tr><td>CAN2510_RXB0</td><td>Configure RXM0, RXF0 and RXF1</td></tr><tr><td>CAN2510_RXB1</td><td>Configure RXM1, RXF2, RXF3, RXF4 and RXF5</td></tr></table> <p><b><i>mask</i></b> Value to store in the corresponding mask</p> <p><b><i>filters</i></b> Array of filter values. For Buffer 0 Extended-length messages: Array of 2 unsigned long integers For Buffer 1 Extended-length messages: Array of 4 unsigned long integers</p>	CAN2510_RXB0	Configure RXM0, RXF0 and RXF1	CAN2510_RXB1	Configure RXM1, RXF2, RXF3, RXF4 and RXF5
CAN2510_RXB0	Configure RXM0, RXF0 and RXF1				
CAN2510_RXB1	Configure RXM1, RXF2, RXF3, RXF4 and RXF5				
<b>Remarks:</b>	This function configures the MCP2510 into Configuration mode, then writes the mask and filter values out to the appropriate registers. Before returning, it configures the MCP2510 to the original mode.				
<b>Return Value:</b>	Indicates if the MCP2510 modes could be modified properly: 0 if Initialization and restoration of Operating mode completed -1 if initialization and restoration of Operating mode did not complete				
<b>File Name:</b>	canfmx.c				

---

## CAN2510SetSingleFilterStd

---

**Function:** Configures the specified Receive filter with a filter value for a Standard (Std) message.

**Required CAN Mode(s):** Configuration mode

**Include:** can2510.h

**Prototype:**  

```
void CAN2510SetSingleFilterStd(  
    unsigned char filterNum,  
    unsigned int filter );
```

**Arguments:**

***filterNum***  
Specifies the acceptance filter to configure. One of the following values:

CAN2510_RXF0	Configure RXF0	(for RXB0)
CAN2510_RXF1	Configure RXF1	(for RXB0)
CAN2510_RXF2	Configure RXF2	(for RXB1)
CAN2510_RXF3	Configure RXF3	(for RXB1)
CAN2510_RXF4	Configure RXF4	(for RXB1)
CAN2510_RXF5	Configure RXF5	(for RXB1)

***filter***  
Value to store in the corresponding filter

**Remarks:** This function writes the filter value to the appropriate registers. The MCP2510 must be in Configuration mode before executing this function.

**File Name:** canfilts.c

---

---

## CAN2510SetSingleFilterXtd

---

**Function:** Configures the specified Receive filter with a filter value for a Extended (Xtd) message.

**Required CAN Mode(s):** Configuration mode

**Include:** can2510.h

**Prototype:**  

```
void CAN2510SetSingleFilterXtd(  
    unsigned char filterNum,  
    unsigned long filter );
```

**Arguments:**

***filterNum***  
Specifies the acceptance filter to configure. One of the following values:

CAN2510_RXF0	Configure RXF0	(for RXB0)
CAN2510_RXF1	Configure RXF1	(for RXB0)
CAN2510_RXF2	Configure RXF2	(for RXB1)
CAN2510_RXF3	Configure RXF3	(for RXB1)
CAN2510_RXF4	Configure RXF4	(for RXB1)
CAN2510_RXF5	Configure RXF5	(for RXB1)

***filter***  
Value to store in the corresponding filter

**Remarks:** This function writes the filter value to the appropriate registers. The MCP2510 must be in Configuration mode before executing this function.

**File Name:** canfiltx.c

---



---

## CAN2510SetSingleMaskStd

---

<b>Function:</b>	Configures the specified Receive buffer mask with a mask value for a Standard (Std) format message.								
<b>Required CAN Mode(s):</b>	Configuration mode								
<b>Include:</b>	can2510.h								
<b>Prototype:</b>	unsigned char CAN2510SetSingleMaskStd( unsigned char <i>maskNum</i> , unsigned int <i>mask</i> );								
<b>Arguments:</b>	<i>maskNum</i> Specifies the acceptance mask to configure. One of the following values: <table><tr><td>CAN2510_RXM0</td><td>Configure RXM0</td><td>(for RXB0)</td></tr><tr><td>CAN2510_RXM1</td><td>Configure RXM1</td><td>(for RXB1)</td></tr></table> <i>mask</i> Value to store in the corresponding mask			CAN2510_RXM0	Configure RXM0	(for RXB0)	CAN2510_RXM1	Configure RXM1	(for RXB1)
CAN2510_RXM0	Configure RXM0	(for RXB0)							
CAN2510_RXM1	Configure RXM1	(for RXB1)							
<b>Remarks:</b>	This function writes the mask value to the appropriate registers. The MCP2510 must be in Configuration mode before executing this function.								
<b>File Name:</b>	canmasks.c								

---

## CAN2510SetSingleMaskXtd

---

<b>Function:</b>	Configures the specified Receive buffer mask with a mask value for an Extended (Xtd) message.								
<b>Required CAN Mode(s):</b>	Configuration mode								
<b>Include:</b>	can2510.h								
<b>Prototype:</b>	unsigned char CAN2510SetSingleMaskXtd( unsigned char <i>maskNum</i> , unsigned long <i>mask</i> );								
<b>Arguments:</b>	<i>maskNum</i> Specifies the acceptance mask to configure. One of the following values: <table><tr><td>CAN2510_RXM0</td><td>Configure RXM0</td><td>(for RXB0)</td></tr><tr><td>CAN2510_RXM1</td><td>Configure RXM1</td><td>(for RXB1)</td></tr></table> <i>mask</i> Value to store in the corresponding mask			CAN2510_RXM0	Configure RXM0	(for RXB0)	CAN2510_RXM1	Configure RXM1	(for RXB1)
CAN2510_RXM0	Configure RXM0	(for RXB0)							
CAN2510_RXM1	Configure RXM1	(for RXB1)							
<b>Remarks:</b>	This function writes the mask value to the appropriate registers. The MCP2510 must be in Configuration mode before executing this function.								
<b>File Name:</b>	canmaskx.c								

---

## CAN2510WriteBuffer

---

<b>Function:</b>	Initiates CAN message transmission of selected buffer.						
<b>Required CAN Mode(s):</b>	All						
<b>Include:</b>	can2510.h						
<b>Prototype:</b>	unsigned char CAN2510WriteBuffer( unsigned char <b>bufferNum</b> )						
<b>Arguments:</b>	<p><b>bufferNum</b> Specifies the buffer to load the message into. One of the following values:</p> <table><tr><td>CAN2510_TXB0</td><td>Transmit buffer 0</td></tr><tr><td>CAN2510_TXB1</td><td>Transmit buffer 1</td></tr><tr><td>CAN2510_TXB2</td><td>Transmit buffer 2</td></tr></table>	CAN2510_TXB0	Transmit buffer 0	CAN2510_TXB1	Transmit buffer 1	CAN2510_TXB2	Transmit buffer 2
CAN2510_TXB0	Transmit buffer 0						
CAN2510_TXB1	Transmit buffer 1						
CAN2510_TXB2	Transmit buffer 2						
<b>Remarks:</b>	This function initiates transmission of the selected transmit buffer.						
<b>File Name:</b>	canwrbuf.c						

---

## CAN2510WriteStd

---

<b>Function:</b>	Writes a Standard format message out to the CAN bus using the first available transmit buffer.
<b>Required CAN Mode(s):</b>	Normal mode
<b>Include:</b>	can2510.h
<b>Prototype:</b>	<pre>unsigned char CAN2510WriteStd(     unsigned int  <i>msgId</i>,     unsigned char <i>msgPriority</i>,     unsigned char <i>numBytes</i>,     unsigned char *<i>data</i> );</pre>
<b>Arguments:</b>	<p><b><i>msgId</i></b> CAN message identifier, 11 bits for a standard message. This 11-bit identifier is stored in the lower 11 bits of msgId (an unsigned integer).</p> <p><b><i>msgPriority</i></b> Priority of buffer. One of the following values: CAN2510_PRI_HIGHEST      Highest message priority CAN2510_PRI_HIGH        High intermediate message priority CAN2510_PRI_LOW         Low intermediate message priority CAN2510_PRI_LOWEST      Lowest message priority</p> <p><b><i>numBytes</i></b> Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be sent.</p> <p><b><i>data</i></b> Array of data values to be written. Must be at least as large as the value specified in <i>numBytes</i>.</p>
<b>Remarks:</b>	This function will query each transmit buffer for a pending message, and will post the specified message into the first available buffer.
<b>Return Value:</b>	Value indicates which buffer was used to transmit the message (0, 1 or 2). -1 indicates that no message was sent.
<b>File Name:</b>	canwrits.c

---

## CAN2510WriteXtd

---

<b>Function:</b>	Writes an Extended format message out to the CAN bus using the first available transmit buffer.
<b>Required CAN Mode(s):</b>	Normal mode
<b>Include:</b>	can2510.h
<b>Prototype:</b>	<pre>unsigned char CAN2510WriteXtd(     unsigned long <i>msgId</i>,     unsigned char <i>msgPriority</i>,     unsigned char <i>numBytes</i>,     unsigned char *<i>data</i> );</pre>
<b>Arguments:</b>	<p><b><i>msgId</i></b> CAN message identifier, 29 bits for an extended message. This 29-bit identifier is stored in the lower 29 bits of <i>msgId</i> (an unsigned long).</p> <p><b><i>msgPriority</i></b> Priority of buffer. One of the following values: CAN2510_PRI_HIGHEST      Highest message priority CAN2510_PRI_HIGH        High intermediate message priority CAN2510_PRI_LOW         Low intermediate message priority CAN2510_PRI_LOWEST      Lowest message priority</p> <p><b><i>numBytes</i></b> Number of bytes of data to transmit, from 0 to 8. If value is greater than 8, only the first 8 bytes of data will be sent.</p> <p><b><i>data</i></b> Array of data values to be written. Must be at least as large as the value specified in <i>numBytes</i>.</p>
<b>Remarks:</b>	This function will query each transmit buffer for a pending message, and will post the specified message into the first available buffer.
<b>Return Value:</b>	Value indicates which buffer was used to transmit the message (0, 1 or 2). -1 indicates that no message was sent.
<b>File Name:</b>	canwritx.c

## 3.4 SOFTWARE I<sup>2</sup>C FUNCTIONS

These functions are designed to allow the implementation of an I<sup>2</sup>C bus using I/O pins from a PIC18 microcontroller. The following functions are provided:

**TABLE 3-6: I<sup>2</sup>C™ SOFTWARE FUNCTIONS**

Function	Description
Clock_test	Generate a delay for slave clock stretching.
SWAckI2C	Generate an I <sup>2</sup> C™ bus <i>Acknowledge</i> condition.
SWGetcI2C	Read a byte from the I <sup>2</sup> C bus.
SWGetsI2C	Read a data string.
SWNotAckI2C	Generate an I <sup>2</sup> C bus <i>Not Acknowledge</i> condition.
SWPutcI2C	Write a single byte to the I <sup>2</sup> C bus.
SWPutsI2C	Write a string to the I <sup>2</sup> C bus.
SWReadI2C	Read a byte from the I <sup>2</sup> C bus.
SWRestartI2C	Generate an I <sup>2</sup> C bus <i>Restart</i> condition.
SWStartI2C	Generate an I <sup>2</sup> C bus <i>Start</i> condition.
SWStopI2C	Generate an I <sup>2</sup> C bus <i>Stop</i> condition.
SWWriteI2C	Write a single byte to the I <sup>2</sup> C bus.

The precompiled versions of these functions use default pin assignments that can be changed by redefining the macro assignments in the file `sw_i2c.h`, found in the `h` subdirectory of the compiler installation:

**TABLE 3-7: MACROS FOR SELECTING I<sup>2</sup>C™ PIN ASSIGNMENTS**

I <sup>2</sup> C Line	Macros	Default Value	Use
DATA Pin	DATA_PIN	PORTBbits.RB4	Pin used for the DATA line.
	DATA_LAT	LATBbits.LATB4	Latch associated with DATA pin.
	DATA_LOW	TRISBbits.TRISB4 = 0;	Statement to configure the DATA pin as an output.
	DATA_HI	TRISBbits.TRISB4 = 1;	Statement to configure the DATA pin as an input.
CLOCK Pin	SCLK_PIN	PORTBbits.RB3	Pin used for the CLOCK line.
	SCLK_LAT	LATBbits.LATB3	Latch associated with the CLOCK pin.
	CLOCK_LOW	TRISBbits.TRISB3 = 0;	Statement to configure the CLOCK pin as an output.
	CLOCK_HI	TRISBbits.TRISB3 = 1;	Statement to configure the CLOCK pin as an input.

After these definitions have been made, the user must recompile the I<sup>2</sup>C routines and then use the updated files in the project. This can be accomplished by adding the library source files into the project or by recompiling the library files using the provided batch files.

## 3.4.1 Function Descriptions

---

### Clock\_test

---

**Function:** Generate a delay for slave clock stretching.

**Include:** `sw_i2c.h`

**Prototype:** `char Clock_test( void );`

**Remarks:** This function is called to allow for slave clock stretching. The delay time may need to be adjusted per application requirements. If at the end of the delay period the clock line is low, a value is returned indicating clock error.

**Return Value:** 0 is returned if no clock error occurred  
-2 is returned if a clock error occurred

**File Name:** `swckti2c.c`

---

### SWAckI2C SWNotAckI2C

---

**Function:** Generate an I<sup>2</sup>C bus *Acknowledge/Not Acknowledge* condition.

**Include:** `sw_i2c.h`

**Prototype:** `char SWAckI2C( void );`  
`char SWNotAckI2C( void );`

**Remarks:** This function is called to generate an I<sup>2</sup>C bus Acknowledge sequence.

**Return Value:** 0 if the slave Acknowledges  
-1 if the slave does not Acknowledge

**File Name:** `swacki2c.c`

---

### SWGetcI2C

---

See `SWReadI2C`.

---

### SWGetsI2C

---

**Function:** Read a string from the I<sup>2</sup>C bus.

**Include:** `sw_i2c.h`

**Prototype:** `char SWGetsI2C(`  
    `unsigned char *rdptr,`  
    `unsigned char length );`

**Arguments:** *rdptr*  
Location to store the data read from the I<sup>2</sup>C bus.  
*length*  
Number of bytes to read.

**Remarks:** This function reads in a string of predetermined length.

**Return Value:** -1 if the master generated a *NOT ACK* bus condition before all bytes have been received  
0 otherwise

**File Name:** `swgtsi2c.c`

**Code Example:** `char x[10];`  
`SWGetsI2C( x,5 );`

---

## SWNotAckI2C

---

See SWAckI2C.

---

## SWPutcI2C

---

See SWWritel2C.

---

## SWPutsI2C

---

**Function:** Write a string to the I<sup>2</sup>C bus.

**Include:** `sw_i2c.h`

**Prototype:** `char SWPutsI2C( unsigned char *wrdptr );`

**Arguments:** *wrdptr*  
Pointer to data to be written to the I<sup>2</sup>C bus.

**Remarks:** This function writes out a data string up to (but not including) a null character.

**Return Value:** -1 if there was an error writing to the I<sup>2</sup>C bus  
0 otherwise

**File Name:** `swptsI2C.c`

**Code Example:**

```
char mybuff [] = "Hello";
SWPutsI2C(mybuff);
```

---

## SWReadI2C SWGetcI2C

---

**Function:** Read a byte from the I<sup>2</sup>C bus.

**Include:** `sw_i2c.h`

**Prototype:** `char SWReadI2C( void );`

**Remarks:** This function reads in a single data byte by generating the appropriate signals on the predefined I<sup>2</sup>C clock line.

**Return Value:** This function returns the acquired I<sup>2</sup>C data byte.  
-1 if there was an error in this function.

**File Name:** `swgtci2c.c`

---

## SWRestartI2C

---

**Function:** Generate an I<sup>2</sup>C *Restart* bus condition.

**Include:** `sw_i2c.h`

**Prototype:** `void SWRestartI2C( void );`

**Remarks:** This function is called to generate an I<sup>2</sup>C bus restart condition.

**File Name:** `swrsti2c.c`

---

## SWStartI2C

---

**Function:** Generate an I<sup>2</sup>C bus *Start* condition.  
**Include:** `sw_i2c.h`  
**Prototype:** `void SWStartI2C( void );`  
**Remarks:** This function is called to generate an I<sup>2</sup>C bus Start condition.  
**File Name:** `swstri2c.c`

---

---

## SWStopI2C

---

**Function:** Generate an I<sup>2</sup>C bus *Stop* condition.  
**Include:** `sw_i2c.h`  
**Prototype:** `void SWStopI2C( void );`  
**Remarks:** This function is called to generate an I<sup>2</sup>C bus Stop condition.  
**File Name:** `swstpi2c.c`

---

---

## SWWriteI2C SWPutI2C

---

**Function:** Write a byte to the I<sup>2</sup>C bus.  
**Include:** `sw_i2c.h`  
**Prototype:** `char SWWriteI2C( unsigned char data_out );`  
**Arguments:** *data\_out*  
Single data byte to be written to the I<sup>2</sup>C bus.  
**Remarks:** This function writes out a single data byte to the predefined data pin.  
**Return Value:** 0 if write is successful  
-1 if there was an error condition  
**File Name:** `swptci2c.c`  
**Code Example**

```
if(SWWriteI2C(0x80))
{
    errorHandler();
}
```

---



## 3.4.2 Example of Use

The following is a simple code example illustrating a software I<sup>2</sup>C implementation communicating with a Microchip 24LC01B I<sup>2</sup>C EE memory device.

```
#include <p18cxxx.h>
#include <sw_i2c.h>
#include <delays.h>

// FUNCTION Prototype
void main(void);
void byte_write(void);
void page_write(void);
void current_address(void);
void random_read(void);
void sequential_read(void);
void ack_poll(void);
unsigned char warr[] = {8,7,6,5,4,3,2,1,0};
unsigned char rarr[15];
unsigned char far *rdpctr = rarr;
unsigned char far *wrpctr = warr;
unsigned char var;

#define W_CS PORTA.2

//*****
void main( void )
{
    byte_write();
    ack_poll();
    page_write();
    ack_poll();
    Nop();
    sequential_read();
    Nop();
    while (1); // Loop indefinitely
}

void byte_write( void )
{
    SWStartI2C();
    var = SWPutcI2C(0xA0); // control byte
    SWAckI2C();
    var = SWPutcI2C(0x10); // word address
    SWAckI2C();
    var = SWPutcI2C(0x66); // data
    SWAckI2C();
    SWStopI2C();
}

void page_write( void )
{
    SWStartI2C();
    var = SWPutcI2C(0xA0); // control byte
    SWAckI2C();
    var = SWPutcI2C(0x20); // word address
    SWAckI2C();
    var = SWPutsI2C(wrpctr); // data
    SWStopI2C();
}
```

```
void sequential_read( void )
{
    SWStartI2C();
    var = SWPutcI2C( 0xA0 ); // control byte
    SWAckI2C();
    var = SWPutcI2C( 0x00 ); // address to read from
    SWAckI2C();
    SWRestartI2C();
    var = SWPutcI2C( 0xA1 );
    SWAckI2C();
    var = SWGetsI2C( rdptr, 9 );
    SWStopI2C();
}

void current_address( void )
{
    SWStartI2C();
    SWPutcI2C( 0xA1 ); // control byte
    SWAckI2C();
    SWGetcI2C(); // word address
    SWNotAckI2C();
    SWStopI2C();
}

void ack_poll( void )
{
    SWStartI2C();
    var = SWPutcI2C( 0xA0 ); // control byte
    while( SWAckI2C() )
    {
        SWRestartI2C();
        var = SWPutcI2C(0xA0); // data
    }
    SWStopI2C();
}
```

## 3.5 SOFTWARE SPI™ FUNCTIONS

These functions are designed to allow the implementation of an SPI using I/O pins from a PIC18 microcontroller. The following functions are provided:

**TABLE 3-8: SOFTWARE SPI™ FUNCTIONS**

Function	Description
ClearCSSWSPI	Clear the Chip Select (CS) pin.
OpenSWSPI	Configure the I/O pins for use as an SPI™.
putcSWSPI	Write a byte of data to the software SPI.
SetCSSWSPI	Set the Chip Select (CS) pin.
WriteSWSPI	Write a byte of data to the software SPI bus.

The precompiled versions of these functions use default pin assignments that can be changed by redefining the macro assignments in the file `sw_spi.h`, found in the `h` subdirectory of the compiler installation:

**TABLE 3-9: MACROS FOR SELECTING SPI™ PIN ASSIGNMENTS**

LCD Controller Line	Macros	Default Value	Use
CS Pin	SW_CS_PIN	PORTBbits.RB2	Pin used for the Chip Select (CS) line.
	TRIS_SW_CS_PIN	TRISBbits.TRISB2	Bit that controls the direction of the pin associated with the CS line.
DIN Pin	SW_DIN_PIN	PORTBbits.RB3	Pin used for the DIN line.
	TRIS_SW_DIN_PIN	TRISBbits.TRISB3	Bit that controls the direction of the pin associated with the DIN line.
DOUT Pin	SW_DOUT_PIN	PORTBbits.RB7	Pin used for the DOUT line.
	TRIS_SW_DOUT_PIN	TRISBbits.TRISB7	Bit that controls the direction of the pin associated with the DOUT line.
SCK Pin	SW_SCK_PIN	PORTBbits.RB6	Pin used for the SCK line.
	TRIS_SW_SCK_PIN	TRISBbits.TRISB6	Bit that controls the direction of the pin associated with the SCK line.

The libraries that are provided can operate in one of four modes. The table below lists the macros used for selecting between these modes. Exactly one of these must be defined when rebuilding the software SPI libraries.

**TABLE 3-10: MACROS FOR SELECTING MODES**

Macro	Default Value	Meaning
MODE0	defined	CKP = 0 CKE = 0
MODE1	not defined	CKP = 1 CKE = 0
MODE2	not defined	CKP = 0 CKE = 1
MODE3	not defined	CKP = 1 CKE = 1

After these definitions have been made, the user must recompile the software SPI routines and then include the updated files in the project. This can be accomplished by adding the software SPI source files into the project or by recompiling the library files using the provided batch files.

## 3.5.1 Function Descriptions

---

### ClearCSSWSPI

---

**Function:** Clear the Chip Select ( $\overline{\text{CS}}$ ) pin that is specified in the `sw_spi.h` header file.

**Include:** `sw_spi.h`

**Prototype:** `void ClearCSSWSPI( void );`

**Remarks:** This function clears the I/O pin that is specified in `sw_spi.h` to be the Chip Select ( $\overline{\text{CS}}$ ) pin for the software SPI.

**File Name:** `clrcsspi.c`

---

### OpenSWSPI

---

**Function:** Configure the I/O pins for the software SPI.

**Include:** `sw_spi.h`

**Prototype:** `void OpenSWSPI( void );`

**Remarks:** This function configures the I/O pins used for the software SPI to the correct input or output state and logic level.

**File Name:** `opensspi.c`

---

### putcSWSPI

---

See **WriteSWSPI**.

---

## SetCSSWSPI

---

**Function:** Set the Chip Select ( $\overline{CS}$ ) pin that is specified in the `sw_spi.h` header file.

**Include:** `sw_spi.h`

**Prototype:** `void SetCSSWSPI( void );`

**Remarks:** This function sets the I/O pin that is specified in `sw_spi.h` to be the Chip Select ( $\overline{CS}$ ) pin for the software SPI.

**File Name:** `setcsspi.c`

---

## WriteSWSPI putcSWSPI

---

**Function:** Write a byte to the software SPI.

**Include:** `sw_spi.h`

**Prototype:** `char WriteSWSPI( char data );`

**Arguments:** *data*  
Data to be written to the software SPI.

**Remarks:** This function writes the specified byte of data out the software SPI and returns the byte of data that was read. This function does not provide any control of the Chip Select pin ( $\overline{CS}$ ).

**Return Value:** This function returns the byte of data that was read from the data in (DIN) pin of the software SPI.

**File Name:** `wrtsspi.c`

**Code Example:**

```
char addr = 0x10;
char result;
result = WriteSWSPI( addr );
```

### 3.5.2 Example of Use

```
#include <p18C452.h>
#include <sw_spi.h>
#include <delays.h>

void main( void )
{
    char address;

    // configure software SPI
    OpenSWSPI();

    for( address=0; address<0x10; address++ )
    {
        ClearCSSWSPI();           //clear CS pin
        WriteSWSPI( 0x02 );       //send write cmd
        WriteSWSPI( address );    //send address hi
        WriteSWSPI( address );    //send address low
        SetCSSWSPI();             //set CS pin
        Delay10KTCYx( 50 );       //wait 5000,000TCY
    }
}
```

## 3.6 SOFTWARE UART FUNCTIONS

These functions are designed to allow the implementation of a UART using I/O pins from a PIC18 microcontroller. The following functions are provided:

**TABLE 3-11: SOFTWARE UART FUNCTIONS**

Function	Description
getcUART	Read a byte from the software UART.
getsUART	Read a string from the software UART.
OpenUART	Configure I/O pins for use as a UART.
putcUART	Write a byte to the software UART.
putsUART	Write a string to the software UART.
ReadUART	Read a byte from the software UART.
WriteUART	Write a byte to the software UART.

The precompiled versions of these functions use default pin assignments that can be changed by redefining the equate (equ) statements in the files `writuart.asm`, `readuart.asm` and `openuart.asm`, found in the `src/traditional/pmc/sw_uart` or `src/extended/pmc/sw_uart` subdirectory of the compiler installation:

**TABLE 3-12: MACROS FOR SELECTING UART PIN ASSIGNMENTS**

LCD Controller Line	Definition	Default Value	Use
TX Pin	SWTXD	PORTB	Port used for the transmit line.
	SWTXDpin	4	Bit in the SWTXD port used for the TX line.
	TRIS_SWTXD	TRISB	Data Direction register associated with the port used for the TX line.
RX Pin	SWRXD	PORTB	Port used for the receive line.
	SWRXDpin	5	Bit in the SWRXD port used for the RX line.
	TRIS_SWRXD	TRISB	Data Direction register associated with the port used for the RX line.

If changes to these definitions are made, the user must recompile the software UART routines and then include the updated files in the project. This can be accomplished by adding the software UART source files into the project or by recompiling the library files using the batch files provided with the MPLAB C18 compiler installation.

The UART libraries also require that the following functions be defined by the user to provide the appropriate delays:

**TABLE 3-13: SOFTWARE UART DELAY FUNCTIONS**

Function	Behavior
DelayTXBitUART	Delay for: $((((2 \cdot F_{osc}) / (4 \cdot \text{baud})) + 1) / 2) - 12$ cycles
DelayRXHalfBitUART	Delay for: $((((2 \cdot F_{osc}) / (8 \cdot \text{baud})) + 1) / 2) - 9$ cycles
DelayRXBitUART	Delay for: $((((2 \cdot F_{osc}) / (4 \cdot \text{baud})) + 1) / 2) - 14$ cycles

## 3.6.1 Function Descriptions

---

### getcUART

---

See ReadUART.

---

### getsUART

---

**Function:** Read a string from the software UART.

**Include:** `sw_uart.h`

**Prototype:** `void getsUART( char * buffer,  
unsigned char len );`

**Arguments:** *buffer*  
Pointer to the string of characters read from the software UART.  
*len*  
Number of characters to be read from the software UART.

**Remarks:** This function reads *len* characters from the software UART and places them in *buffer*.

**File Name:** `getsuart.c`

**Code Example:** `char x[10];  
getsUART( x, 5 );`

---

### OpenUART

---

**Function:** Configure the I/O pins for the software UART.

**Include:** `sw_uart.h`

**Prototype:** `void OpenUART( void );`

**Remarks:** This function configures the I/O pins used for the software UART to the correct input or output state and logic level.

**File Name:** `openuart.asm`

**Code Example:** `OpenUART();`

---

### putcUART

---

See WriteUART.

---

### putsUART

---

**Function:** Write a string to the software UART.

**Include:** `sw_uart.h`

**Prototype:** `void putsUART( char * buffer );`

**Arguments:** *buffer*  
String to be written to the software UART.

**Remarks:** This function writes a string of characters to the software UART. The entire string including the null is sent to the UART.

**File Name:** `putsuart.c`

**Code Example:** `char mybuff [] = "Hello";  
putsUART( mybuff );`

---

## ReadUART getcUART

---

**Function:** Read a byte from the software UART.

**Include:** `sw_uart.h`

**Prototype:** `char ReadUART( void );`

**Remarks:** This function reads a byte of data out the software UART.

**Return Value:** Returns the byte of data that was read from the receive data (RXD) pin of the software UART.

**File Name:** `readuart.asm`

**Code Example:**

```
char x;  
x = ReadUART();
```

---

## WriteUART putcUART

---

**Function:** Write a byte to the software UART.

**Include:** `sw_uart.h`

**Prototype:** `void WriteUART( char data );`

**Arguments:** *data*  
Byte of data to be written to software UART.

**Remarks:** This function writes the specified byte of data out the software UART.

**File Name:** `writuart.asm`

**Code Example:**

```
char x = 'H';  
WriteUART( x );
```

### 3.6.2 Example of Use

```
#include <p18C452.h>  
#include <sw_uart.h>  
  
void main( void )  
{  
    char data;  
  
    // configure software UART  
    OpenUART();  
  
    while( 1 )  
    {  
        data = ReadUART();    //read a byte  
        WriteUART( data );    //bounce it back  
    }  
}
```



---

## Chapter 4. General Software Library

---

### 4.1 INTRODUCTION

This chapter documents general software library functions found in the precompiled standard C library file. The source code for all of these functions is included with MPLAB C18 in the following subdirectories of the compiler installation:

- src\traditional\stdlib
- src\extended\stdlib
- src\traditional\delays
- src\extended\delays

The following categories of routines are supported by the MPLAB C18 library:

- Character Classification Functions
- Data Conversion Functions
- Memory and String Manipulation Functions
- Delay Functions
- Reset Functions
- Character Output Functions

### 4.2 CHARACTER CLASSIFICATION FUNCTIONS

These functions are consistent with the ANSI 1989 standard C library functions of the same name. The following functions are provided:

**TABLE 4-1: CHARACTER CLASSIFICATION FUNCTIONS**

Function	Description
isalnum	Determine if a character is alphanumeric.
isalpha	Determine if a character is alphabetic.
isctrl	Determine if a character is a control character.
isdigit	Determine if a character is a decimal digit.
isgraph	Determine if a character is a graphical character.
islower	Determine if a character is a lowercase alphabetic character.
isprint	Determine if a character is a printable character.
ispunct	Determine if a character is a punctuation character.
isspace	Determine if a character is a white space character.
isupper	Determine if a character is an uppercase alphabetic character.
isxdigit	Determine if a character is a hexadecimal digit.

## 4.2.1 Function Descriptions

---

### isalnum

---

<b>Function:</b>	Determine if a character is alphanumeric.
<b>Include:</b>	<code>ctype.h</code>
<b>Prototype:</b>	<code>unsigned char isalnum( unsigned char <i>ch</i> );</code>
<b>Arguments:</b>	<b><i>ch</i></b> Character to be checked.
<b>Remarks:</b>	A character is considered to be alphanumeric if it is in the range of 'A' to 'Z', 'a' to 'z' or '0' to '9'.
<b>Return Value:</b>	Non-zero if the character is alphanumeric Zero otherwise
<b>File Name:</b>	<code>isalnum.c</code>

---

### isalpha

---

<b>Function:</b>	Determine if a character is alphabetic.
<b>Include:</b>	<code>ctype.h</code>
<b>Prototype:</b>	<code>unsigned char isalpha( unsigned char <i>ch</i> );</code>
<b>Arguments:</b>	<b><i>ch</i></b> Character to be checked.
<b>Remarks:</b>	A character is considered to be alphabetic if it is in the range of 'A' to 'Z' or 'a' to 'z'.
<b>Return Value:</b>	Non-zero if the character is alphabetic Zero otherwise
<b>File Name:</b>	<code>isalpha.c</code>

---

### isctrl

---

<b>Function:</b>	Determine if a character is a control character.
<b>Include:</b>	<code>ctype.h</code>
<b>Prototype:</b>	<code>unsigned char isctrl( unsigned char <i>ch</i> );</code>
<b>Arguments:</b>	<b><i>ch</i></b> Character to be checked.
<b>Remarks:</b>	A character is considered to be a control character if it is not a printable character as defined by <code>isprint()</code> .
<b>Return Value:</b>	Non-zero if the character is a control character Zero otherwise
<b>File Name:</b>	<code>isctrl.c</code>

---

## isdigit

---

**Function:** Determine if a character is a decimal digit.

**Include:** ctype.h

**Prototype:** unsigned char isdigit( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a digit character if it is in the range of '0' to '9'.

**Return Value:** Non-zero if the character is a digit character  
Zero otherwise

**File Name:** isdigit.c

---

---

## isgraph

---

**Function:** Determine if a character is a graphical character.

**Include:** ctype.h

**Prototype:** unsigned char isgraph( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a graphical case alphabetic character if it is any printable character except space.

**Return Value:** Non-zero if the character is a graphical character  
Zero otherwise

**File Name:** isgraph.c

---

---

## islower

---

**Function:** Determine if a character is a lowercase alphabetic character.

**Include:** ctype.h

**Prototype:** unsigned char islower( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a lowercase alphabetic character if it is in the range of 'a' to 'z'.

**Return Value:** Non-zero if the character is a lowercase alphabetic character  
Zero otherwise

**File Name:** islower.c

---

---

## isprint

---

**Function:** Determine if a character is a printable character.

**Include:** ctype.h

**Prototype:** unsigned char isprint( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a printable character if it is in the range 0x20 to 0x7e, inclusive.

**Return Value:** Non-zero if the character is a printable character  
Zero otherwise

**File Name:** isprint.c

---

---

## ispunct

---

**Function:** Determine if a character is a punctuation character.

**Include:** ctype.h

**Prototype:** unsigned char ispunct( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a punctuation character if it is a printable character which is neither a space nor an alphanumeric character.

**Return Value:** Non-zero if the character is a punctuation character  
Zero otherwise

**File Name:** ispunct.c

---

---

## isspace

---

**Function:** Determine if a character is a white space character.

**Include:** ctype.h

**Prototype:** unsigned char isspace (unsigned char *ch*);

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a white space character if it is one of the following: space (' '), tab('\t'), carriage return ('\r'), new line ('\n'), form feed ('\f') or vertical tab ('\v').

**Return Value:** Non-zero if the character is a white space character  
Zero otherwise

**File Name:** isspace.c

---

---

## isupper

---

**Function:** Determine if a character is an uppercase alphabetic character.

**Include:** ctype.h

**Prototype:** unsigned char isupper (unsigned char *ch*);

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be an uppercase alphabetic character if it is in the range of 'A' to 'Z'.

**Return Value:** Non-zero if the character is an uppercase alphabetic character  
Zero otherwise

**File Name:** isupper.c

---

---

## isxdigit

---

**Function:** Determine if a character is a hexadecimal digit.

**Include:** ctype.h

**Prototype:** unsigned char isxdigit( unsigned char *ch* );

**Arguments:** *ch*  
Character to be checked.

**Remarks:** A character is considered to be a hexadecimal digit character if it is in the range of '0' to '9', 'a' to 'f' or 'A' to 'F'.

**Return Value:** Non-zero if the character is a hexadecimal digit character  
Zero otherwise

**File Name:** isxdig.c

---

## 4.3 DATA CONVERSION FUNCTIONS

Except as noted in the function descriptions, these functions are consistent with the ANSI 1989 standard C library functions of the same name. The functions provided are:

**TABLE 4-2: DATA CONVERSION FUNCTIONS**

Function	Description
atob	Convert a string to an 8-bit signed byte.
atof	Convert a string into a floating point value.
atoi	Convert a string to a 16-bit signed integer.
atol	Convert a string into a long integer representation.
btoa	Convert an 8-bit signed byte to a string.
itoa	Convert a 16-bit signed integer to a string.
ltoa	Convert a signed long integer to a string.
rand	Generate a pseudo-random integer.
srand	Set the starting seed for the pseudo-random number generator.
tolower	Convert a character to a lowercase alphabetical ASCII character.
toupper	Convert a character to an uppercase alphabetical ASCII character.
ultoa	Convert an unsigned long integer to a string.

### 4.3.1 Function Descriptions

#### atob

<b>Function:</b>	Convert a string to an 8-bit signed byte.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	signed char atob( const char * <i>s</i> );
<b>Arguments:</b>	<i>s</i> Pointer to ASCII string to be converted.
<b>Remarks:</b>	This function converts the ASCII string <i>s</i> into an 8-bit signed byte (-128 to 127). The input string must be in base 10 (decimal radix) and can begin with a character indicating sign ('+' or '-'). Overflow results are undefined. This function is an MPLAB C18 extension to the ANSI standard libraries.
<b>Return Value:</b>	8-bit signed byte for all strings in the range (-128 to 127).
<b>File Name:</b>	atob.asm

#### atof

<b>Function:</b>	Convert a string into a floating point value.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	double atof ( const char * <i>s</i> );
<b>Arguments:</b>	<i>s</i> Pointer to ASCII string to be converted.
<b>Remarks:</b>	This function converts the ASCII string <i>s</i> into a floating point value. Examples of floating point strings that are recognized are: -3.1415 1.0E2 1.0E+2 1.0E-2
<b>Return Value:</b>	The function returns the converted value.
<b>File Name:</b>	atof.c

---

## atoi

---

<b>Function:</b>	Convert a string to a 16-bit signed integer.
<b>Include:</b>	<code>stdlib.h</code>
<b>Prototype:</b>	<code>int atoi( const char * <i>s</i> );</code>
<b>Arguments:</b>	<i>s</i> Pointer to ASCII string to be converted.
<b>Remarks:</b>	This function converts the ASCII string <i>s</i> into an 16-bit signed integer (-32768 to 32767). The input string must be in base 10 (decimal radix) and can begin with a character indicating sign ('+' or '-'). Overflow results are undefined. This function is an MPLAB C18 extension to the ANSI standard libraries.
<b>Return Value:</b>	16-bit signed integer for all strings in the range (-32768 to 32767).
<b>File Name:</b>	<code>atoi.asm</code>

---

## atol

---

<b>Function:</b>	Convert a string into a long integer representation.
<b>Include:</b>	<code>stdlib.h</code>
<b>Prototype:</b>	<code>long atol( const char * <i>s</i> );</code>
<b>Arguments:</b>	<i>s</i> Pointer to ASCII string to be converted.
<b>Remarks:</b>	This function converts the ASCII string <i>s</i> into a long value. The input string must be in base 10 (decimal radix) and can begin with a character indicating sign ('+' or '-'). Overflow results are undefined. This function is an MPLAB C18 extension to the ANSI standard libraries.
<b>Return Value:</b>	The function returns the converted value.
<b>File Name:</b>	<code>atol.asm</code>

---

## btoa

---

<b>Function:</b>	Convert an 8-bit signed byte to a string.
<b>Include:</b>	<code>stdlib.h</code>
<b>Prototype:</b>	<code>char * btoa( signed char <i>value</i>,                   char * <i>string</i> );</code>
<b>Arguments:</b>	<i>value</i> An 8-bit signed byte. <i>string</i> Pointer to ASCII string that will hold the result. <i>string</i> must be long enough to hold the ASCII representation, including the sign character for negative values and a trailing null character.
<b>Remarks:</b>	This function converts the 8-bit signed byte in the argument <i>value</i> to a ASCII string representation.  This function is an MPLAB C18 extension of the ANSI required libraries.
<b>Return Value:</b>	Pointer to the result <i>string</i> .
<b>File Name:</b>	<code>btoa.asm</code>

---

## itoa

---

<b>Function:</b>	Convert a 16-bit signed integer to a string.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	char * itoa( int <i>value</i> , char * <i>string</i> );
<b>Arguments:</b>	<i>value</i> A 16-bit signed integer. <i>string</i> Pointer to ASCII string that will hold the result. <i>string</i> must be long enough to hold the ASCII representation, including the sign character for negative values and a trailing null character.
<b>Remarks:</b>	This function converts the 16-bit signed integer in the argument <i>value</i> to a ASCII string representation.  This function is an MPLAB C18 extension of the ANSI required libraries.
<b>Return Value:</b>	Pointer to the result <i>string</i> .
<b>File Name:</b>	itoa.asm

---

## ltoa

---

<b>Function:</b>	Convert a signed long integer to a string.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	char * ltoa( long <i>value</i> , char * <i>string</i> );
<b>Arguments:</b>	<i>value</i> A signed long integer to be converted. <i>string</i> Pointer to ASCII string that will hold the result.
<b>Remarks:</b>	This function converts the signed long integer in the argument <i>value</i> to a ASCII string representation. <i>string</i> must be long enough to hold the ASCII representation, including the sign character for negative values and a trailing null character. This function is an MPLAB C18 extension to the ANSI required libraries.
<b>Return Value:</b>	Pointer to the result <i>string</i> .
<b>File Name:</b>	ltoa.asm

---

## rand

---

<b>Function:</b>	Generate a pseudo-random integer.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	int rand( void );
<b>Remarks:</b>	Calls to this function return pseudo-random integer values in the range [0,32767]. To use this function effectively, you must seed the random number generator using the <code>srand()</code> function. This function will always return the same sequence of integers when identical seed values are used.
<b>Return Value:</b>	A psuedo-random integer value.
<b>File Name:</b>	rand.asm

---



---

## srand

---

**Function:** Set the starting seed for the pseudo-random number sequence.

**Include:** `stdlib.h`

**Prototype:** `void srand( unsigned int seed );`

**Arguments:** *seed*  
The starting value for the pseudo-random number sequence.

**Remarks:** This function sets the starting seed for the pseudo-random number sequence generated by the `rand()` function. The `rand()` function will always return the same sequence of integers when identical seed values are used. If `rand()` is called without `srand()` having first been called, the sequence of numbers generated will be the same as if `srand()` had been called with a seed value of 1.

**File Name:** `rand.asm`

---

---

## tolower

---

**Function:** Convert a character to a lowercase alphabetical ASCII character.

**Include:** `ctype.h`

**Prototype:** `char tolower( char ch );`

**Arguments:** *ch*  
Character to be converted.

**Remarks:** This function converts *ch* to a lowercase alphabetical ASCII character provided that the argument is a valid uppercase alphabetical character.

**Return Value:** This function returns a lowercase character if the argument was uppercase to begin with; otherwise the original character is returned.

**File Name:** `tolower.c`

---

---

## toupper

---

**Function:** Convert a character to an uppercase alphabetical ASCII character.

**Include:** `ctype.h`

**Prototype:** `char toupper( char ch );`

**Arguments:** *ch*  
Character to be converted.

**Remarks:** This function converts *ch* to an uppercase alphabetical ASCII character provided that the argument is a valid lowercase alphabetical character.

**Return Value:** This function returns an uppercase character if the argument was lowercase to begin with; otherwise the original character is returned.

**File Name:** `toupper.c`

---

## ultoa

<b>Function:</b>	Convert an unsigned long integer to a string.
<b>Include:</b>	stdlib.h
<b>Prototype:</b>	char * ultoa( unsigned long <i>value</i> , char * <i>string</i> );
<b>Arguments:</b>	<i>value</i> An unsigned long integer to be converted. <i>string</i> Pointer to ASCII string that will hold the result.
<b>Remarks:</b>	This function converts the unsigned long integer in the argument <i>value</i> to a ASCII string representation. <i>string</i> must be long enough to hold the ASCII representation, including a trailing null character. This function is an MPLAB C18 extension to the ANSI required libraries.
<b>Return Value:</b>	Pointer to the result <i>string</i> .
<b>File Name:</b>	ultoa.asm

## 4.4 MEMORY AND STRING MANIPULATION FUNCTIONS

Except as noted in the function descriptions, these functions are consistent with the ANSI (1989) standard C library functions of the same name. The following functions are provided:

**TABLE 4-3: MEMORY AND STRING MANIPULATION FUNCTIONS**

Function	Description
memchr memchrpgm	Search for a value in a specified memory region.
memcmp memcmppgm memcmppgm2ram memcmppram2pgm	Compare the contents of two arrays.
memcpy memcpypgm memcpypgm2ram memcpyram2pgm	Copy a buffer.
memmove memmovepgm memmovepgm2ram memmoveram2pgm	Copy a buffer, where the source and destination may overlap.
memset memsetpgm	Initialize an array with a single repeated value.
strcat strcatpgm strcatpgm2ram strcatram2pgm	Append a copy of the source string to the end of the destination string.
strchr strchrpgm	Locate the first occurrence of a value in a string.
strcmp strcmppgm strcmppgm2ram strcmppram2pgm	Compare two strings.
strcpy strcpypgm strcpypgm2ram strcpyram2pgm	Copy a string from data or program memory into data memory.

**TABLE 4-3: MEMORY AND STRING MANIPULATION FUNCTIONS (CONTINUED)**

strcspn strcspnpgm strcspnpgmram strcspnrampgm	Calculate the number of consecutive characters at the beginning of a string that are not contained in a set of characters.
strlen strlenpgm	Determine the length of a string.
strlwr strlwrpgm	Convert all uppercase characters in a string to lowercase.
strncat strncatpgm strncatpgm2ram strncatram2pgm	Append a specified number of characters from the source string to the end of the destination string.
strncmp strncmppgm strncmppgm2ram strncmpram2pgm	Compare two strings, up to a specified number of characters.
strncpy strncpypgm strncpypgm2ram strncpyram2pgm	Copy characters from the source string into the destination string, up to the specified number of characters.
strpbrk strpbrkpgm strpbrkpgmram strpbrkrampgm	Search a string for the first occurrence of a character from a set of characters.
strrchr strrchrpgm	Locate the last occurrence of a specified character in a string.
strspn strspnpgm strspnpgmram strspnrampgm	Calculate the number of consecutive characters at the beginning of a string that are contained in a set of characters.
strstr strstrpgm strstrpgmram strsrrampgm	Locate the first occurrence of a string inside another string.
strtok strtokpgm strtokpgmram strtokrampgm	Break a string into substrings or tokens, by inserting null characters in place of specified delimiters.
strupr struprpgm	Convert all lowercase characters in a string to uppercase.

## 4.4.1 Function Descriptions

---

### memchr memchrpgm

---

<b>Function:</b>	Locate the first occurrence of a byte value in a specified memory region.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>void * memchr( const void *<i>mem</i>,                unsigned char <i>c</i>,                size_t <i>n</i> ); rom char * memchrpgm( const rom char *<i>mem</i>,                      const unsigned char <i>c</i>,                      sizerom_t <i>n</i> );</pre>
<b>Arguments:</b>	<p><i>mem</i> Pointer to a memory region.</p> <p><i>c</i> Byte value to find.</p> <p><i>n</i> Maximum number of bytes to search.</p>
<b>Remarks:</b>	<p>This function searches up to <i>n</i> bytes of the region <i>mem</i> to find the first occurrence of <i>c</i>.</p> <p>This function differs from the ANSI specified function in that <i>c</i> is defined as an unsigned char parameter rather than an int parameter.</p>
<b>Return Value:</b>	If <i>c</i> appears in the first <i>n</i> bytes of <i>mem</i> , this function returns a pointer to the character in <i>mem</i> . Otherwise, it returns a null pointer.
<b>File Names:</b>	memchr.asm mchrpgm.asm

---

### memcmp memcmppgm memcmppgm2ram memcmppram2pgm

---

<b>Function:</b>	Compare the contents of two arrays of bytes.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>signed char memcmp(     const void * <i>buf1</i>,     const void * <i>buf2</i>,     size_t <i>memsize</i> ); signed char memcmppgm(     const rom void * <i>buf1</i>,     const rom void * <i>buf2</i>,     sizerom_t <i>memsize</i> ); signed char memcmppgm2ram(     const void * <i>buf1</i>,     const rom void * <i>buf2</i>,     sizeram_t <i>memsize</i> ); signed char memcmppram2pgm(     const rom void * <i>buf1</i>,     const void * <i>buf2</i>,     sizeram_t <i>memsize</i> );</pre>

---

## memcmp memcppgm memcppgm2ram memcmpram2pgm (Continued)

---

Arguments:	<i>buf1</i> Pointer to first array. <i>buf2</i> Pointer to second array. <i>memsize</i> Number of elements to be compared in arrays.
Remarks:	This function compares the first <i>memsize</i> number of bytes in <i>buf1</i> to the first <i>memsize</i> number of bytes in <i>buf2</i> and returns a value indicating whether the buffers are less than, equal to or greater than each other.
Return Value:	Returns a value that is: <0 if <i>buf1</i> is less than <i>buf2</i> ==0 if <i>buf1</i> is the same as <i>buf2</i> >0 if <i>buf1</i> is greater than <i>buf2</i>
File Names:	memcmp.asm memcpp2p.asm memcpp2r.asm memcmpr2p.asm

---

## memcpy memcpypgm memcpypgm2ram memcpyram2pgm

---

**Function:** Copy the contents of the source buffer into the destination buffer.

**Include:** string.h

**Prototype:**

```
void * memcpy(  
    void * dest,  
    const void * src,  
    size_t memsize );  
rom void * memcpypgm(  
    rom void * dest,  
    const rom void * src,  
    sizero_m_t memsize );  
void * memcpypgm2ram(  
    void * dest,  
    const rom void * src,  
    sizera_m_t memsize );  
rom void * memcpyram2pgm(  
    rom void * dest,  
    const void * src,  
    sizera_m_t memsize );
```

**Arguments:**

*dest*  
Pointer to destination array.

*src*  
Pointer to source array.

*memsize*  
Number of bytes of *src* array to copy into *dest*.

**Remarks:** This function copies the first *memsize* number of bytes in *src* to the array *dest*. If *src* and *dest* overlap, the behavior is undefined.

---

## memcpy memcpypgm memcpypgm2ram memcpyram2pgm (Continued)

---

**Return Value:** This function returns the value of *dest*.

**File Names:** memcpy.asm  
memcpyp2p.asm  
memcpyp2r.asm  
memcpyr2p.asm

---

---

## memmove memmovepgm memmovepgm2ram memmoveram2pgm

---

**Function:** Copy the contents of the source buffer into the destination buffer, even if the regions overlap.

**Include:** string.h

**Prototype:**

```
void * memmove( void * dest,
                const void * src,
                size_t memsize );

rom void * memmovepgm(
    rom void * dest,
    const rom void * src,
    sizet_om_t memsize );

void * memmovepgm2ram(
    void * dest,
    const rom void * src,
    sizet_om_t memsize );

rom void * memmoveram2pgm(
    rom void * dest,
    const void * src,
    sizet_om_t memsize );
```

**Arguments:** *dest*  
Pointer to destination array.  
*src*  
Pointer to source array.  
*memsize*  
Number of bytes of *src* array to copy into *dest*.

**Remarks:** This function copies the first *memsize* number of bytes in *src* to the array *dest*. This function performs correctly even if *src* and *dest* overlap.

**Return Value:** This function returns the value of *dest*.

**File Names:** memmove.asm  
memmovep2p.asm  
memmovep2r.asm  
memmovev2p.asm

---

---

## memset memsetpgm

---

<b>Function:</b>	Copy the specified character into the destination array.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>void * memset( void * <i>dest</i>,                unsigned char <i>value</i>,                size_t <i>memsize</i> );  rom void * memsetpgm(     rom void * <i>dest</i>,     unsigned char <i>value</i>,     sizetom_t <i>memsize</i> );</pre>
<b>Arguments:</b>	<p><i>dest</i> Pointer to destination array.</p> <p><i>value</i> Character value to be copied.</p> <p><i>memsize</i> Number of bytes of <i>dest</i> into which <i>value</i> is copied.</p>
<b>Remarks:</b>	This function copies the character <i>value</i> into the first <i>memsize</i> bytes of the array <i>dest</i> . This functions differs from the ANSI specified function in that <i>value</i> is defined as an unsigned char rather than as an int parameter.
<b>Return Value:</b>	This function returns the value of <i>dest</i> .
<b>File Name:</b>	memset.asm memsetpgm.asm

---

---

## strcat strcatpgm strcatpgm2ram strcatram2pgm

---

<b>Function:</b>	Append a copy of the source string to the end of the destination string.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strcat( char * <i>dest</i>,                const char * <i>src</i> );  rom char * strcatpgm(     rom char * <i>dest</i>,     const rom char * <i>src</i> );  char * strcatpgm2ram(     char * <i>dest</i>,     const rom char * <i>src</i> );  rom char * strcatram2pgm(     rom char * <i>dest</i>,     const char * <i>src</i> );</pre>
<b>Arguments:</b>	<p><i>dest</i> Pointer to destination array.</p> <p><i>src</i> Pointer to source array.</p>
<b>Remarks:</b>	This function copies the string in <i>src</i> to the end of the string in <i>dest</i> . The <i>src</i> string starts at the null in <i>dest</i> . A null character is added to the end of the resulting string in <i>dest</i> . If <i>src</i> and <i>dest</i> overlap, the behavior is undefined.
<b>Return Value:</b>	This function returns the value of <i>dest</i> .

---

**strcat**  
**strcatpgm**  
**strcatpgm2ram**  
**strcatram2pgm (Continued)**

```
File Names:      strcat.asm
                 scatp2p.asm
                 scatp2r.asm
                 scatp2p.asm
```

**strchr**  
**strchrpgm**

<b>Function:</b>	Locate the first occurrence of a specified character in a string.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strchr( const char * <i>str</i>,                unsigned char <i>c</i> ); rom char * strchrpgm(                const rom char * <i>str</i>,                unsigned char <i>c</i> );</pre>
<b>Arguments:</b>	<p><i>str</i> Pointer to a string to be searched.</p> <p><i>c</i> Character to find.</p>
<b>Remarks:</b>	<p>This function searches the string <i>str</i> to find the first occurrence of character <i>c</i>.</p> <p>This function differs from the ANSI specified function in that <i>c</i> is defined as an <code>unsigned char</code> parameter rather than an <code>int</code> parameter.</p>
<b>Return Value:</b>	If <i>c</i> appears in <i>str</i> , this function returns a pointer to the character in <i>str</i> . Otherwise, it returns a null pointer.
<b>File Names:</b>	strchr.asm schrpgm.asm

**strcmp**  
**strcmpppgm**  
**strcmpppgm2ram**  
**strcmppram2pgm**

<b>Function:</b>	Compare two strings.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>signed char strcmp(     const char * <i>str1</i>,     const char * <i>str2</i> ); signed char strcmpppgm(     const rom char * <i>str1</i>,     const rom char * <i>str2</i> ); signed char strcmpppgm2ram(     const char * <i>str1</i>,     const rom char * <i>str2</i> ); signed char strcmppram2pgm(     const rom char * <i>str1</i>,     const char * <i>str2</i> );</pre>



---

**strcmp**  
**strcmpppgm**  
**strcmpppgm2ram**  
**strcmppram2pgm**

---

**Arguments:** *str1*  
Pointer to first string.  
*str2*  
Pointer to second string.

**Remarks:** This function compares the string in *str1* to the string in *str2* and returns a value indicating if *str1* is less than, equal to or greater than *str2*.

**Return Value:** Returns a value that is:  
<0 if *str1* is less than *str2*  
==0 if *str1* is the same as *str2*  
>0 if *str1* is greater than *str2*

**File Name:** strcmp.asm  
scmpp2p.asm  
scmpp2r.asm  
scmpr2p.asm

---

---

**strcpy**  
**strcpypgm**  
**strcpypgm2ram**  
**strcpyram2pgm**

---

**Function:** Copy the source string into the destination string.

**Include:** string.h

**Prototype:**  
char \* strcpy( char \* *dest*,  
                    const char \* *src* );  
rom char \* strcpypgm(  
                    rom char \* *dest*,  
                    const rom char \* *src* );char \*  
char \* strcpypgm2ram(  
                    char \* *dest*,  
                    const rom char \* *src* );  
rom char \* strcpyram2pgm(  
                    rom char \* *dest*,  
                    const char \* *src* );

**Arguments:** *dest*  
Pointer to destination string.  
*src*  
Pointer to source string.

**Remarks:** This function copies the string in *src* to *dest*. Characters in *src* are copied up to, and including, the terminating null character in *src*. If *src* and *dest* overlap, the behavior is undefined.

**Return Value:** This function returns the value of *dest*.

**File Name:** strcpy.asm  
scpy2p.asm  
scpy2r.asm  
scpyr2p.asm

---

---

## strcspn strcspnpgm strcspnpgmram strcspnrampgm

---

<b>Function:</b>	Calculate the number of consecutive characters at the beginning of a string that are not contained in a set of characters.												
<b>Include:</b>	string.h												
<b>Prototype:</b>	<pre>size_t strcspn( const char * <i>str1</i>,                 const char * <i>str2</i> ); sizerom_t strcspnpgm(     const rom char * <i>str1</i>,     const rom char * <i>str2</i> ); sizerom_t strcspnpgmram(     const rom char * <i>str1</i>,     const char * <i>str2</i> ); sizeram_t strcspnrampgm(     const char * <i>str1</i>,     const rom char * <i>str2</i> );</pre>												
<b>Arguments:</b>	<p><i>str1</i> Pointer to a string to be searched.</p> <p><i>str2</i> Pointer to a string that is treated as a set of characters.</p>												
<b>Remarks:</b>	<p>This function will determine the number of consecutive characters from the beginning of <i>str1</i> that are not contained in <i>str2</i>. For example:</p> <table><tr><th><i>str1</i></th><th><i>str2</i></th><th>result</th></tr><tr><td>"hello"</td><td>"aeiou"</td><td>1</td></tr><tr><td>"antelope"</td><td>"aeiou"</td><td>0</td></tr><tr><td>"antelope"</td><td>"xyz"</td><td>8</td></tr></table>	<i>str1</i>	<i>str2</i>	result	"hello"	"aeiou"	1	"antelope"	"aeiou"	0	"antelope"	"xyz"	8
<i>str1</i>	<i>str2</i>	result											
"hello"	"aeiou"	1											
"antelope"	"aeiou"	0											
"antelope"	"xyz"	8											
<b>Return Value:</b>	This function returns the number of consecutive characters from the beginning of <i>str1</i> that are not contained in <i>str2</i> , as shown in the examples above.												
<b>File Names:</b>	strcspn.asm scspnpp.asm scspnpr.asm scspnrp.asm												

---

## strlen strlenpgm

---

<b>Function:</b>	Return the length of the string.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>size_t strlen( const char * <i>str</i> ); sizerom_t strlenpgm( const rom char * <i>str</i> );</pre>
<b>Arguments:</b>	<p><i>str</i> Pointer to string.</p>
<b>Remarks:</b>	This function determines the length of the string, not including the terminating null character.
<b>Return Value:</b>	This function returns the length of the string.
<b>File Name:</b>	strlen.asm slenpgm.asm

---

## strlwr strlwrpgm

---

**Function:** Convert all uppercase characters in a string to lowercase.

**Include:** string.h

**Prototype:**  
char \* strlwr( char \* *str* );  
rom char \* strlwrpgm( rom char \* *str* );

**Arguments:** *str*  
Pointer to string.

**Remarks:** This function converts all uppercase characters in *str* to lowercase characters. All characters that are not uppercase (A to Z) are not affected.

**Return Value:** This function returns the value of *str*.

**File Name:** strlwr.asm  
slwrpgm.asm

---

---

## strncat strncatpgm strncatpgm2ram strncatram2pgm

---

**Function:** Append a specified number of characters from the source string to the destination string.

**Include:** string.h

**Prototype:**  
char \* strncat( char \* *dest*,  
                  const char \* *src*,  
                  size\_t *n* );  
rom char \* strncatpgm(  
                  rom char \* *dest*,  
                  const rom char \* *src*,  
                  sizerom\_t *n* );  
char \* strncatpgm2ram(  
                  char \* *dest*,  
                  const rom char \* *src*,  
                  sizeram\_t *n* );  
rom char \* strncatram2pgm(  
                  rom char \* *dest*,  
                  const char \* *src*,  
                  sizeram\_t *n* );

**Arguments:** *dest*  
Pointer to destination array.  
*src*  
Pointer to source array.  
*n*  
Number of characters to append.

**Remarks:** This function appends exactly *n* characters from the string in *src* to the end of the string in *dest*. If a null character is copied before *n* characters have been copied, null characters will be appended to *dest* until exactly *n* characters have been appended.  
If *src* and *dest* overlap, the behavior is undefined.  
If a null character is not encountered, then a null character is not appended.

**Return Value:** This function returns the value of *dest*.

---

---

## strncat strncatpgm strncatpgm2ram strncatram2pgm (Continued)

---

**File Names:**       strncat.asm  
                  sncatp2p.asm  
                  sncatp2r.asm  
                  sncatr2p.asm

---

---

## strncmp strncmppgm strncmppgm2ram strncmpram2pgm

---

**Function:**       Compare two strings, up to a specified number of characters.

**Include:**        string.h

**Prototype:**      signed char strncmp( const char \* *str1*,  
  const char \* *str2*,  
  size\_t *n* );  
  
                  signed char strncmppgm(  
  const rom char \* *str1*,  
  const rom char \* *str2*,  
  sizerom\_t *n* );  
  
                  signed char strncmppgm2ram(  
  const char \* *str1*,  
  const rom char \* *str2*,  
  sizeram\_t *n* );  
  
                  signed char strncmpram2pgm(  
  const rom char \* *str1*,  
  const char \* *str2*,  
  sizeram\_t *n* );

**Arguments:**      *str1*  
                    Pointer to first string.  
                    *str2*  
                    Pointer to second string.  
                    *n*  
                    Maximum number of characters to compare.

**Remarks:**       This function compares the string in *str1* to the string in *str2* and  
                    returns a value indicating if *str1* is less than, equal to or greater than  
                    *str2*. If *n* characters are compared and no differences are found, this  
                    function will return a value indicating that the strings are equivalent.

**Return Value:**   Returns a value based on the first character that differs between *str1*  
                    and *str2*. It returns:  
                    <0   if *str1* is less than *str2*  
                    ==0   if *str1* is the same as *str2*  
                    >0   if *str1* is greater than *str2*

**File Name:**      strncmp.asm  
                    sncmpp2p.asm  
                    sncmpp2r.asm  
                    sncmpr2p.asm

---

---

**strncpy**  
**strncpypgm**  
**strncpypgm2ram**  
**strncpyram2pgm**

---

**Function:** Copy characters from the source string into the destination string, up to the specified number of characters.

**Include:** string.h

**Prototype:**

```
char * strncpy( char * dest,
                const char * src,
                size_t n );
rom char * strncpypgm(
    rom char * dest,
    const rom char * src,
    sizeroam_t n );
char *strncpypgm2ram(
    char * dest,
    const rom char * src,
    sizeram_t n );
rom char * strncpyram2pgm(
    rom char * dest,
    const char * src,
    sizeram_t n );
```

**Arguments:**

*dest*  
Pointer to destination string.

*src*  
Pointer to source string.

*n*  
Maximum number of characters to copy.

**Remarks:** This function copies the string in *src* to *dest*. Characters in *src* are copied into *dest* until the terminating null character or *n* characters have been copied. If *n* characters were copied and no null character was found then *dest* will not be null-terminated.

If copying takes place between objects that overlap, the behavior is undefined.

**Return Value:** This function returns the value of *dest*.

**File Name:**

strncpy.asm  
sncpy2p.asm  
sncpy2r.asm  
sncpyr2p.asm

---

## strpbrk strpbrkpgm strpbrkpgmram strpbrkrampgm

---

<b>Function:</b>	Search a string for the first occurrence of a character from a specified set of characters.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strpbrk( const char * <i>str1</i>,                 const char * <i>str2</i> ); rom char * strpbrkpgm(                 const rom char * <i>str1</i>,                 const rom char * <i>str2</i> ); rom char * strpbrkpgmram(                 const rom char * <i>str1</i>,                 const char * <i>str2</i> ); char * strpbrkrampgm(                 const char * <i>str1</i>,                 const rom char * <i>str2</i> );</pre>
<b>Arguments:</b>	<p><i>str1</i> Pointer to a string to be searched.</p> <p><i>str2</i> Pointer to a string that is treated as a set of characters.</p>
<b>Remarks:</b>	This function will search <i>str1</i> for the first occurrence of a character contained in <i>str2</i> .
<b>Return Value:</b>	If a character in <i>str2</i> is found, a pointer to that character in <i>str1</i> is returned. If no character from <i>str2</i> is found in <i>str1</i> , a null pointer is returned.
<b>File Names:</b>	strpbrk.asm spbrkpp.asm spbrkpr.asm spbrkrp.asm

---

## strrchr

---

<b>Function:</b>	Locate the last occurrence of a specified character in a string.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strrchr( const char * <i>str</i>,                 const char <i>c</i> );</pre>
<b>Arguments:</b>	<p><i>str</i> Pointer to a string to be searched.</p> <p><i>c</i> Character to find.</p>
<b>Remarks:</b>	<p>This function searches the string <i>str</i>, including the terminating null character, to find the last occurrence of character <i>c</i>.</p> <p>This function differs from the ANSI specified function in that <i>c</i> is defined as an unsigned char parameter rather than an int parameter.</p>
<b>Return Value:</b>	If <i>c</i> appears in <i>str</i> , this function returns a pointer to the character in <i>str</i> . Otherwise, it returns a null pointer.
<b>File Names:</b>	strrchr.asm

---

**strspn**  
**strspnpgm**  
**strspnpgmram**  
**strspnrampgm**

---

**Function:** Calculate the number of consecutive characters at the beginning of a string that are contained in a set of characters.

**Include:** string.h

**Prototype:**

```
size_t strspn( const char * str1,
               const char * str2 );
sizerom_t strspnpgm(
    const rom char * str1,
    const rom char * str2 );
sizerom_t strspnpgmram(
    const rom char * str1,
    const char * str2 );
sizeram_t strspnrampgm(
    const char * str1,
    const rom char * str2 );
```

**Arguments:**

*str1*  
Pointer to a string to be searched.

*str2*  
Pointer to a string that is treated as a set of characters.

**Remarks:** This function will determine the number of consecutive characters from the beginning of *str1* that are contained in *str2*. For example:

<i>str1</i>	<i>str2</i>	result
"banana"	"ab"	2
"banana"	"abn"	6
"banana"	"an"	0

**Return Value:** This function returns the number of consecutive characters from the beginning of *str1* that are contained in *str2*, as shown in the examples above.

**File Names:**

strspn.asm  
sspnp.asm  
sspnp.ram  
sspnp.ram

---

## strstr strstrpgm strstrpgmram strstrrampgm

---

<b>Function:</b>	Locate the first occurrence of a string inside another string.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strstr( const char * <i>str</i>,                const char * <i>substr</i> );  rom char * strstrpgm(                const rom char * <i>str</i>,                const rom char * <i>substr</i> );  rom char * strstrpgmram(                const rom char * <i>str</i>,                const char * <i>substr</i> );  char * strstrrampgm(                const char * <i>str</i>,                const rom char * <i>substr</i> );</pre>
<b>Arguments:</b>	<p><i>str</i> Pointer to a string to be searched.</p> <p><i>substr</i> Pointer to a string pattern for which to search.</p>
<b>Remarks:</b>	This function will find the first occurrence of the string <i>substr</i> (excluding the null terminator) within string <i>str</i> .
<b>Return Value:</b>	If the string is located, a pointer to that string in <i>str</i> will be returned. Otherwise a null pointer is returned.
<b>File Names:</b>	strstr.asm sstrpp.asm sstrpr.asm sstrrp.asm

---

## strtok strtokpgm strtokpgmram strtokrampgm

---

<b>Function:</b>	Break a string into substrings or tokens, by inserting null characters in place of specified delimiters.
<b>Include:</b>	string.h
<b>Prototype:</b>	<pre>char * strtok( char * <i>str</i>,                const char * <i>delim</i> );  rom char * strtokpgm(                rom char * <i>str</i>,                const rom char * <i>delim</i> );  char * strtokpgmram(                char * <i>str</i>,                const rom char * <i>delim</i> );  rom char * strtokrampgm(                rom char * <i>str</i>,                const char * <i>delim</i> );</pre>
<b>Arguments:</b>	<p><i>str</i> Pointer to a string to be searched.</p> <p><i>delim</i> Pointer to a set of characters that indicate the end of a token.</p>

---



---

## strtok strtokpgm strtokpgmram strtokrampgm (Continued)

---

Remarks:	<p>This function can be used to split up a string into substrings by replacing specified characters with null characters. The first time this function is invoked on a particular string, that string should be passed in <i>str</i>. After the first time, this function can continue parsing the string from the last delimiter by invoking it with a null value passed in <i>str</i>. When <i>strtok</i> is invoked with a non-null parameter for <i>str</i>, it starts searching <i>str</i> from the beginning. It skips all leading characters that appear in the string <i>delim</i>, then skips all characters not appearing in <i>delim</i>, then sets the next character to null.</p> <p>When <i>strtok</i> is invoked with a null parameter for <i>str</i>, it searches the string that was most recently examined, beginning with the character after the one that was set to null during the previous call. It skips all characters not appearing in <i>delim</i>, then sets the next character to null. If <i>strtok</i> finds the end of the string before it finds a delimiter, it does not modify the string.</p> <p>The set of characters that is passed in <i>delim</i> need not be the same for each call to <i>strtok</i>.</p>
Return Value:	<p>If a delimiter was found, this function returns a pointer into <i>str</i> to the first character that was searched that did not appear in the set of characters <i>delim</i>. This character represents the first character of a token that was created by the call.</p> <p>If no delimiter was found prior to the terminating null character, a null pointer is returned from the function.</p>
File Names:	<p>strtok.asm stokpgm.asm stokpr.asm stokrp.asm</p>

---

## strupr struprgpm

---

Function:	Convert all lowercase characters in a string to uppercase.
Include:	string.h
Prototype:	<pre>char *strupr( char * str ); rom char *struprgpm( rom char * str );</pre>
Arguments:	<p><i>str</i> Pointer to string.</p>
Remarks:	<p>This function converts all lowercase characters in <i>str</i> to uppercase characters. All characters that are not lowercase (a to z) are not affected.</p>
Return Value:	This function returns the value of <i>str</i> .
File Name:	<p>strupr.asm suprgpm.asm</p>

## 4.5 DELAY FUNCTIONS

The delay functions execute code for a specific number of processor instruction cycles. For time based delays, the processor operating frequency must be taken into account. The following routines are provided:

**TABLE 4-4: DELAY FUNCTIONS**

Function	Description
Delay1TCY	Delay one instruction cycle.
Delay10TCYx	Delay in multiples of 10 instruction cycles.
Delay100TCYx	Delay in multiples of 100 instruction cycles.
Delay1KTCYx	Delay in multiples of 1,000 instruction cycles.
Delay10KTCYx	Delay in multiples of 10,000 instruction cycles.

### 4.5.1 Function Descriptions

#### Delay1TCY

**Function:** Delay 1 instruction cycle (TCY).  
**Include:** `delays.h`  
**Prototype:** `void Delay1TCY( void );`  
**Remarks:** This function is actually a `#define` for the NOP instruction. When encountered in the source code, the compiler simply inserts a NOP.  
**File Name:** `#define` in `delays.h`

#### Delay10TCYx

**Function:** Delay in multiples of 10 instruction cycles (TCY).  
**Include:** `delays.h`  
**Prototype:** `void Delay10TCYx( unsigned char unit );`  
**Arguments:** `unit`  
The value of `unit` can be any 8-bit value. A value in the range [1,255] will delay (`unit * 10`) cycles. A value of 0 causes a delay of 2,560 cycles.  
**Remarks:** This function creates a delay in multiples of 10 instruction cycles.  
**File Name:** `d10tcyx.asm`

#### Delay100TCYx

**Function:** Delay in multiples of 100 instruction cycles (TCY).  
**Include:** `delays.h`  
**Prototype:** `void Delay100TCYx( unsigned char unit );`  
**Arguments:** `unit`  
The value of `unit` can be any 8-bit value. A value in the range [1,255] will delay (`unit * 100`) cycles. A value of 0 causes a delay of 25,600 cycles.

---

## Delay100TCYx (Continued)

---

**Remarks:** This function creates a delay in multiples of 100 instruction cycles. This function uses the globally allocated variable, `DelayCounter1`. If this function is used in both interrupt and mainline code, the variable `DelayCounter1` should be saved and restored in the interrupt handler. Refer to the `save=` clause of the `#pragma interrupt` or `#pragma interruptlow` directives for more information. Note that other delay functions also use the globally allocated `DelayCounter1` variable.

**File Name:** `d100tcyx.asm`

---

## Delay1KTCYx

---

**Function:** Delay in multiples of 1,000 instruction cycles (TCY).

**Include:** `delays.h`

**Prototype:** `void Delay1KTCYx( unsigned char unit );`

**Arguments:** *unit*  
The value of *unit* can be any 8-bit value. A value in the range [1,255] will delay (*unit* \* 1000) cycles. A value of 0 causes a delay of 256,000 cycles.

**Remarks:** This function creates a delay in multiples of 1,000 instruction cycles. This function uses the globally allocated variables, `DelayCounter1` and `DelayCounter2`. If this function is used in both interrupt and mainline code, these variables, `DelayCounter1` and `DelayCounter2`, should be saved and restored in the interrupt handler. Refer to the `save=` clause of the `#pragma interrupt` and `#pragma interruptlow` directives for more information. Note that other delay functions also use the globally allocated `DelayCounter1` variable.

**File Name:** `d1ktcyx.asm`

---

## Delay10KTCYx

---

**Function:** Delay in multiples of 10,000 instruction cycles (TCY).

**Include:** `delays.h`

**Prototype:** `void Delay10KTCYx( unsigned char unit );`

**Arguments:** *unit*  
The value of *unit* can be any 8-bit value. A value in the range [1,255] will delay (*unit* \* 10000) cycles. A value of 0 causes a delay of 2,560,000 cycles.

**Remarks:** This function creates a delay in multiples of 10,000 instruction cycles. This function uses the globally allocated variable, `DelayCounter1`. If this function is used in both interrupt and mainline code, the variable `DelayCounter1` should be saved and restored in the interrupt handler. Refer to the `save=` clause of the `#pragma interrupt` or `#pragma interruptlow` directives for more information. Note that other delay functions also use the globally allocated `DelayCounter1` variable.

**File Name:** `d10ktcyx.asm`

## 4.6 RESET FUNCTIONS

The Reset functions may be used to help determine the source of a Reset or wake-up event and for reconfiguring the processor status following a Reset. The following routines are provided:

**TABLE 4-5: RESET FUNCTIONS**

Function	Description
isBOR	Determine if the cause of a Reset was the Brown-out Reset circuit.
isLVD	Determine if the cause of a Reset was a low voltage detect condition.
isMCLR	Determine if the cause of a Reset was the $\overline{\text{MCLR}}$ pin.
isPOR	Detect a Power-on Reset condition.
isWDTTO	Determine if the cause of a Reset was a Watchdog timer time-out.
isWDTWU	Determine if the cause of a wake-up was the Watchdog timer.
isWU	Detects if the microcontroller was just waken up from Sleep from the $\overline{\text{MCLR}}$ pin or an interrupt.
StatusReset	Set the $\overline{\text{POR}}$ and $\overline{\text{BOR}}$ bits.

**Note:** If you are using Brown-out Reset (BOR) or the Watchdog Timer (WDT), then you must define the enable macros (`#define BOR_ENABLED` and `#define WDT_ENABLED`, respectively) in the header file `reset.h` and recompile the source code.  
If the device is configured to reset on stack overflow/underflow, then you must define the enable macro (`#define STVR_ENABLED`) in the header file `reset.h` and recompile the source code.

### 4.6.1 Function Descriptions

#### isBOR

<b>Function:</b>	Determine if the cause of a Reset was the Brown-out Reset circuit.
<b>Include:</b>	<code>reset.h</code>
<b>Prototype:</b>	<code>char isBOR( void );</code>
<b>Remarks:</b>	This function detects if the microcontroller was reset due to the Brown-out Reset circuit. This condition is indicated by the following Status bits: <code>POR = 1</code> <code>BOR = 0</code>
<b>Return Value:</b>	1 if the Reset was due to the Brown-out Reset circuit 0 otherwise
<b>File Name:</b>	<code>isbor.c</code>

#### isLVD

<b>Function:</b>	Determine if the cause of a Reset was a low voltage detect condition.
<b>Include:</b>	<code>reset.h</code>
<b>Prototype:</b>	<code>char isLVD( void );</code>
<b>Remarks:</b>	This function detects if the voltage of the device has become lower than the value specified in the LVDCON register (LVDL3:LVDL0 bits.)
<b>Return Value:</b>	1 if a Reset was due to LVD during normal operation 0 otherwise
<b>File Name:</b>	<code>islvd.c</code>

---

## isMCLR

---

<b>Function:</b>	Determine if the cause of a Reset was the MCLR pin.
<b>Include:</b>	reset.h
<b>Prototype:</b>	char isMCLR( void );
<b>Remarks:</b>	<p>This function detects if the microcontroller was reset via the <math>\overline{\text{MCLR}}</math> pin while in normal operation. This situation is indicated by the following Status bits:</p> <p><math>\overline{\text{POR}} = 1</math> If Brown-out is enabled, <math>\overline{\text{BOR}} = 1</math> If WDT is enabled, <math>\overline{\text{TO}} = 1</math> <math>\overline{\text{PD}} = 1</math> If stack overflow/underflow reset is enabled, then the stack overflow and underflow flag bits will be cleared in the <i>STKPTR</i> register.</p>
<b>Return Value:</b>	1 if the Reset was due to $\overline{\text{MCLR}}$ during normal operation 0 otherwise
<b>File Name:</b>	ismclr.c

---

## isPOR

---

<b>Function:</b>	Detect a Power-on Reset condition.
<b>Include:</b>	reset.h
<b>Prototype:</b>	char isPOR( void );
<b>Remarks:</b>	<p>This function detects if the microcontroller just left a Power-on Reset. This condition is indicated by the following Status bits:</p> <p><math>\overline{\text{POR}} = 0</math> <math>\overline{\text{BOR}} = 0</math> <math>\overline{\text{TO}} = 1</math> <math>\overline{\text{PD}} = 1</math></p> <p>This condition also can occur for <math>\overline{\text{MCLR}}</math> during normal operation and when the <i>CLRWDT</i> instruction is executed. After <i>isPOR</i> is called, <i>StatusReset</i> should be called to set the <math>\overline{\text{POR}}</math> and <math>\overline{\text{BOR}}</math> bits.</p>
<b>Return Value:</b>	1 if the device just left a Power-on Reset 0 otherwise
<b>File Name:</b>	ispor.c

---

## isWDTTO

---

<b>Function:</b>	Determine if the cause of a Reset was a Watchdog Timer (WDT) time out.
<b>Include:</b>	reset.h
<b>Prototype:</b>	char isWDTTO( void );
<b>Remarks:</b>	<p>This function detects if the microcontroller was reset due to the WDT during normal operation. This condition is indicated by the following Status bits:</p> <p><math>\overline{\text{POR}} = 1</math> <math>\overline{\text{BOR}} = 1</math> <math>\overline{\text{TO}} = 0</math> <math>\overline{\text{PD}} = 1</math></p>
<b>Return Value:</b>	1 if the Reset was due to the WDT during normal operation 0 otherwise
<b>File Name:</b>	iswdtto.c

---

## isWDTWU

---

<b>Function:</b>	Determine if the cause of a wake-up was the Watchdog Timer (WDT).
<b>Include:</b>	reset.h
<b>Prototype:</b>	char isWDTWU( void );
<b>Remarks:</b>	This function detects if the microcontroller was brought out of Sleep by the WDT. This condition is indicated by the following Status bits: $\overline{POR} = 1$ $\overline{BOR} = 1$ $\overline{TO} = 0$ $\overline{PD} = 0$
<b>Return Value:</b>	1 if device was brought out of Sleep by the WDT 0 otherwise
<b>File Name:</b>	iswdtwu.c

---

## isWU

---

<b>Function:</b>	Detects if the microcontroller was just waken up from Sleep via the $\overline{MCLR}$ pin or interrupt.
<b>Include:</b>	reset.h
<b>Prototype:</b>	char isWU( void );
<b>Remarks:</b>	This function detects if the microcontroller was brought out of Sleep by the $\overline{MCLR}$ pin or an interrupt. This condition is indicated by the following Status bits: $\overline{POR} = 1$ $\overline{BOR} = 1$ $\overline{TO} = 1$ $\overline{PD} = 0$
<b>Return Value:</b>	1 if the device was brought out of Sleep by the $\overline{MCLR}$ pin or an interrupt 0 otherwise
<b>File Name:</b>	iswu.c

---

## StatusReset

---

<b>Function:</b>	Set the $\overline{POR}$ and $\overline{BOR}$ bits in the CPUSTA register.
<b>Include:</b>	reset.h
<b>Prototype:</b>	void StatusReset( void );
<b>Remarks:</b>	This function sets the POR and BOR bits in the CPUSTA register. These bits must be set in software after a Power-on Reset has occurred.
<b>File Name:</b>	statrst.c

## 4.7 CHARACTER OUTPUT FUNCTIONS

The character output functions provide a central family of functions for processing output to peripherals, memory buffers and other consumers of character data.

When processing a call to `fprintf`, `printf`, `sprintf`, `vfprintf`, `vprintf` or `vsprintf`, MPLAB C18 will always process the variable length portion of the argument list with integer promotions enabled (see the “Integer Promotions” section of the *MPLAB® C18 C Compiler User’s Guide* (DS51288) for more information). This allows the standard library to interface with the compiler cleanly and with consistent behavior for the formatting of the output as would normally be expected from those functions.

### 4.7.1 Output Streams

Output is based on the use of a destination stream. A stream can be a peripheral, memory buffer, or any other consumer of data and is denoted by a pointer to an object of `FILE` type. MPLAB C18 defines two streams in the standard library:

`_H_USER` output via the user-defined output function `_user_putc`.

`_H_USART` output via the library output function `_usart_putc`.

The current version of the library supports only these two output streams. Both streams are always considered to be open and do not require use of functions such as `fopen`, `fclose`, etc.

The global variables `stdout` and `stderr` are defined by the library and have default value of `_H_USART`. To change the destination to be `_H_USER`, assign that value to the variable. For example, to change standard output to use the user defined output function:

```
stdout = _H_USER;
```

**TABLE 4-6: CHARACTER OUTPUT FUNCTIONS**

Function	Description
<code>fprintf</code>	Formatted string output to a stream.
<code>fputs</code>	String output to a stream.
<code>printf</code>	Formatted string output to <code>stdout</code> .
<code>putc</code>	Character output to a stream
<code>puts</code>	String output to <code>stdout</code> .
<code>sprintf</code>	Formatted string output to a data memory buffer.
<code>vfprintf</code>	Formatted string output to a stream with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<code>vprintf</code>	Formatted string output to <code>stdout</code> with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<code>vsprintf</code>	Formatted string output to a data memory buffer with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<code>_usart_putc</code>	Single character output to the USART (USART1 for devices which have more than one USART).
<code>_user_putc</code>	Single character output in an application defined manner.

## 4.7.2 Function Descriptions

---

### fprintf

---

<b>Function:</b>	Formatted string output to a stream.
<b>Include:</b>	stdio.h
<b>Prototype:</b>	int fprintf (FILE *f, const rom char *fmt, ...);
<b>Remarks:</b>	<p>The <code>fprintf</code> function formats output, passing the characters to the specified stream via the <code>putc</code> function. The format string is processed one character at a time and the characters are output as they appear in the format string, except for format specifiers. A format specifier is indicated in the format string by a percent sign, %; following that, a well-formed format specifier has the following components.<sup>1</sup> Except for the conversion operation, all format specifiers are optional:</p> <ol style="list-style-type: none"><li>1. Flag characters (order does not matter), where a flag character is one of #, -, +, 0 or space.</li><li>2. A <i>field width</i>, which is a decimal integer constant value an asterisk, *.</li><li>3. A <i>field precision</i>, which is a period (.), optionally followed by a decimal integer or an asterisk, *.</li><li>4. A <i>size specification</i>, which is one of the specifiers h, H, hh, j, z, Z, t, T or l.</li><li>5. A <i>conversion operation</i>, which is one of c, b, B, d, i, n, o, p, P, s, S, u, x, X or %.</li></ol>

---

<sup>1</sup>Not all components are valid for all conversion operations. Details are provided in the descriptions of the conversion operators.



---

## fprintf (Continued)

---

### Flag Characters

- # The *alternate form* of the result will be presented. For the `o` conversion, the alternate form is as if the precision were increased such that the first digit of the result is forced to be a zero. For the `x` conversion, a non-zero result will have a `0x` prefix added to it. For the `X` conversion, a non-zero result will have a `0X` prefix added to it. For the `b` conversion, a non-zero result will have a `0b` prefix added to it. For the `B` conversion, a non-zero result will have a `0B` prefix added to it. For other conversions, the flag is ignored.
- The result will be left justified. If this flag is not specified, the result will be right justified.
- + For a signed conversion, the result will always begin with a `+` or a `-` sign. By default, a sign character is only added to the result if the result is negative. For other conversions, the flag is ignored.
- space For a signed conversion, if the result is non-negative or has no characters, a space will be prefixed to the result. If the space and `+` flags are both specified, the space flag will be ignored. For other conversions, the flag is ignored.
- 0 For the integer conversions (`d`, `i`, `o`, `u`, `b`, `B`, `x`, `X`), leading zeroes are prefixed to the result (after any sign and/or base indicators) such that the result fills the field width. No space padding is performed. If the `-` flag is also specified, the `0` flag will be ignored. If a precision is specified, the `0` flag will be ignored. For other conversions, the flag is ignored.

### Field Width

The field width specifies the minimum number of characters for the converted value. If the converted value is shorter than the field width, then the value is padded to have the number of characters be equal to the field width. By default, leading spaces are used for padding; the flag characters are used to alter the pad character and the justification of the value.

If the field width is an asterisk character, `*`, an `int` argument is read to specify the field width. If the value is negative, it is as if the `-` flag were specified, followed by a positive field width.

### Field Precision

The field precision specifies the minimum number of digits which will be present in the converted value for a `d`, `i`, `o`, `u`, `b`, `B`, `x` or `X` conversion, or the maximum number of characters in the converted value for an `s` conversion.

If the field width is an asterisk character, `*`, an `int` argument is read to specify the field width. If the value is negative, it is as if the precision were unspecified.

For the `d`, `i`, `o`, `u`, `b`, `B`, `x` or `X` conversion operators, the default precision is `1`. For all other conversion operators the behavior when the precision is unspecified is described below.

---

## fprintf (Continued)

---

### Size Specifications

The size specification character applies to the integer conversion specifiers, `d`, `i`, `o`, `u`, `b`, `B`, `x` or `X`, and the pointer conversion specifiers, `p` and `P`. If present for any other conversion operator, it is ignored.

- `hh` For integer conversion specifiers, the argument to be converted is a signed `char` or unsigned `char` argument.<sup>2</sup> For an `n` conversion specifier, the specifier denotes a pointer to a signed `char` argument.
- `h` For integer conversion specifiers, the argument to be converted is a short `int` or unsigned short `int`. For an `n` conversion specifier, the specifier denotes a pointer to a short `int` argument. As a plain `int` is the same size as a short `int` for MPLAB C18, this option has no actual effect and is present for compatibility purposes only. For pointer conversion specifiers, the argument to be converted is a 16-bit pointer.
- `H` For integer conversion specifiers, the argument to be converted is a short long `int` or unsigned short long `int`. For an `n` conversion specifier, the specifier denotes a pointer to a short long `int` argument. For pointer conversion specifiers, the argument to be converted is a 24-bit pointer.<sup>3</sup> For example, when outputting a `far rom char *`, the size specifier `H` should be used (`%HS`).
- `j` For integer conversion specifiers, the argument to be converted is an `intmax_t` or `uintmax_t` argument. For an `n` conversion specifier, the specifier denotes a pointer to an `intmax_t` argument. For MPLAB C18, this is equivalent to the `l` size specifier.
- `l` For integer conversion specifiers, the argument to be converted is a long `int` or unsigned long `int`. For an `n` conversion specifier, the specifier denotes a pointer to a long `int` argument. For pointer conversion specifiers, the size specifier is ignored.
- `t` For integer conversion specifiers, the argument to be converted is an `ptrdiff_t` argument. For an `n` conversion specifier, the specifier denotes a pointer to a signed integer type corresponding to `ptrdiff_t` argument. For MPLAB C18, this is equivalent to the `h` size specifier.
- `T` For integer conversion specifiers, the argument to be converted is an `ptrdifffrom_t` argument. For an `n` conversion specifier, the specifier denotes a pointer to a signed integer type corresponding to `ptrdifffrom_t` argument. For MPLAB C18, this is equivalent to the `H` size specifier.<sup>4</sup>
- `z` For integer conversion specifiers, the argument to be converted is an `size_t` argument. For an `n` conversion specifier, the specifier denotes a pointer to a signed integer type corresponding to `size_t` argument. For MPLAB C18, this is equivalent to the `h` size specifier.
- `Z` For integer conversion specifiers, the argument to be converted is an `sizerom_t` argument. For an `n` conversion specifier, the specifier denotes a pointer to a signed integer type corresponding to `sizerom_t` argument. For MPLAB C18, this is equivalent to the `H` size specifier.<sup>5</sup>

---

<sup>2</sup>Note that the integer promotions will still apply when the argument is passed. This specifier causes the argument to be cast back to 8 bits in size prior to the value being used.

<sup>3</sup>The `H` size specifier is an MPLAB C18 specific extension to ANSI C.

<sup>4</sup>The `T` size specifier is an MPLAB C18 specific extension to ANSI C.

<sup>5</sup>The `Z` size specifier is an MPLAB C18 specific extension to ANSI C.

---

## fprintf (Continued)

---

### Conversion Operators

- c The `int` argument is converted to an `unsigned char` value and the character represented by that value is written.
- d, i The `int` argument is formatted as signed decimal with the precision indicating the minimum number of digits to be written. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.
- o The `unsigned int` argument is converted to unsigned octal with the precision indicating the minimum number of digits to be written. If the converted value has fewer digits, it is prepended with leading zeros. If the converted value is zero and the precision is zero, no characters will be written.
- u The `unsigned int` argument is formatted as unsigned decimal with the precision indicating the minimum number of digits to be written. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.
- b The `unsigned int` argument is formatted as unsigned binary with the precision indicating the minimum number of digits to be written. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.<sup>6</sup>
- B The `unsigned int` argument is formatted as unsigned binary with the precision indicating the minimum number of digits to be written. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.<sup>7</sup>
- x The `unsigned int` argument is formatted as unsigned hexadecimal with the precision indicating the minimum number of digits to be written. The characters `abcdef` are used for the representation if the decimal numbers 10 through 15. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.
- X The `unsigned int` argument is formatted as unsigned hexadecimal with the precision indicating the minimum number of digits to be written. The characters `ABCDEF` are used for the representation of the decimal numbers 10 through 15. If the converted value has fewer digits, it is prepended with zeros. If the converted value is zero and the precision is zero, no characters will be written.
- s Characters from the data memory array of `char` argument are written until either a terminating `'\0'` character is seen (the `'\0'` character is not written) or the number of characters written is equal to the specified precision. If the precision is specified to be greater than the size of the array or is unspecified, the array must contain a terminating `'\0'` character.
- S Characters from the program memory array of `char` argument are written until either a terminating `'\0'` character is seen (the `'\0'` character is not written) or the number of characters written is equal to the specified precision. If the precision is specified to be greater than the size of the array or is unspecified, the array must contain a terminating `'\0'` character.<sup>8</sup> When outputting a `far rom char *`, make sure to use the `H` size specifier (i.e., `%HS`).

---

<sup>6</sup>The `b` conversion operator is an MPLAB C18 specific extension to ANSI C.

<sup>7</sup>The `B` conversion operator is an MPLAB C18 specific extension to ANSI C.

<sup>8</sup>The `S` conversion operator is an MPLAB C18 specific extension to ANSI C.

## fprintf (Continued)

---

- p The pointer to void (data or program memory) argument is converted to an equivalent size unsigned integer type and that value is processed as if the x conversion operator had been specified. If the H size specifier is present, the pointer is a 24-bit pointer, else it is a 16-bit pointer.
  - P The pointer to void (data or program memory) argument is converted to an equivalent size unsigned integer type and that value is processed as if the x conversion operator had been specified. If the H size specifier is present, the pointer is a 24-bit pointer, else it is a 16-bit pointer.<sup>9</sup>
  - n The number of characters written so far shall be stored in the location referenced by the argument, which is a pointer to an integer type in data memory. The size of the integer type is determined by the size specifier present for the conversion, or a plain 16-bit integer if no size specifier is present.
  - % A literal % character is written. The conversion specification shall be %% only, no flags or other specifiers may be present.
- If a conversion specifier is invalid (e.g., a flag character is present for the %% conversion specifier), the behavior is undefined.

**Return Value:** fprintf returns EOF if an error occurs, otherwise returns the number of characters output.

**Filename:** fprintf.c

**Code Example:**

```
#include <stdio.h>
void main (void)
{
    far rom char * S = "Hello, World!";
    int n = 0x1234;
    fprintf (_H_USART, "test output to USART\n");
    fprintf (_H_USER, "test output to application"
            "defined function\n" );
    fprintf (stdout, "hex output: %#x", n);
    fprintf (stderr, "%HS\n", S);
}
```

---

<sup>9</sup>The P conversion operator is an MPLAB C18 specific extension to ANSI C.

---

## fputs

---

**Function:** String output to a stream.

**Include:** stdio.h

**Prototype:** int fputs (const rom char \*s, FILE \*f);

**Remarks:** fputs outputs a null terminated string to the specified output stream, one character at a time via putc. A newline character is appended to the output. The terminating null is not output.

**Return Value:** fputs returns EOF if an error occurs, otherwise returns a non-negative value.

**Filename:** fputs.c

---

## printf

---

<b>Function:</b>	Formatted string output to <code>stdout</code> .
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<code>int printf (const rom char *fmt, ...);</code>
<b>Remarks:</b>	The <code>printf</code> function formats output, passing the characters to <code>stdout</code> via the <code>putc</code> function. The format string is processed as described for the <code>fprintf</code> function.
<b>Return Value:</b>	<code>printf</code> returns EOF if an error occurs, otherwise returns the number of characters output.
<b>Filename:</b>	<code>printf.c</code>
<b>Code Example:</b>	<pre>#include &lt;stdio.h&gt; void main (void) {     /* will output via stdout (_H_USART by default) */     printf ("Hello, World!\n"); }</pre>

---

## putc

---

<b>Function:</b>	Character output to a stream.
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<code>int putc (char c, FILE *f);</code>
<b>Remarks:</b>	<code>putc</code> outputs a single character to the specified output stream.
<b>Return Value:</b>	<code>putc</code> returns EOF if an error occurs, otherwise returns the character which was output.
<b>Filename:</b>	<code>putc.c</code>

---

## puts

---

<b>Function:</b>	String output to <code>stdout</code> .
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<code>int puts (const rom char *s);</code>
<b>Remarks:</b>	<code>puts</code> outputs a null terminated string to <code>stdout</code> one character at a time via <code>putc</code> . A newline character is appended to the output. The terminating null is not output.
<b>Return Value:</b>	<code>puts</code> returns EOF if an error occurs, otherwise returns a non-negative value.
<b>Filename:</b>	<code>puts.c</code>
<b>Code Example:</b>	<pre>#include &lt;stdio.h&gt; void main (void) {     puts ("test message"); }</pre>

---

## sprintf

---

<b>Function:</b>	Formatted string output to a data memory buffer.
<b>Include:</b>	stdio.h
<b>Prototype:</b>	int sprintf (char *buf, const rom char *fmt, ...);
<b>Remarks:</b>	The <code>sprintf</code> function formats output, storing the characters to the destination data memory buffer, <code>buf</code> . The format string, <code>fmt</code> , is processed as described for the <code>fprintf</code> function.
<b>Return Value:</b>	<code>sprintf</code> returns EOF if an error occurs, otherwise the number of characters output is returned.
<b>Filename:</b>	sprintf.c
<b>Code Example:</b>	<pre>#include &lt;stdio.h&gt; void main (void) {     int i = 0xA12;     char buf[20];     sprintf (buf, "%#010x", i);     /* buf will contain the string "0x00000a12" }</pre>

---

## fprintf

---

<b>Function:</b>	Formatted string output to a stream with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<b>Include:</b>	stdio.h
<b>Prototype:</b>	int fprintf (FILE *f, const rom char *fmt, va_list ap);
<b>Remarks:</b>	The <code>fprintf</code> function formats output, passing the characters to the specified output stream, <code>f</code> , via the <code>putc</code> function. The format string, <code>fmt</code> , is processed as described for the <code>fprintf</code> function except that the arguments consumed when processing the format string are retrieved via the <code>stdarg</code> variable length argument facility.
<b>Return Value:</b>	<code>fprintf</code> returns EOF if an error occurs, otherwise the number of characters output is returned.
<b>Filename:</b>	fprintf.c

---

## vprintf

---

<b>Function:</b>	Formatted string output to <code>stdout</code> with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<b>Include:</b>	stdio.h
<b>Prototype:</b>	int vprintf (const rom char *fmt, va_list ap);
<b>Remarks:</b>	The <code>vprintf</code> function formats output, passing the characters to <code>stdout</code> via the <code>putc</code> function. The format string, <code>fmt</code> , is processed as described for the <code>fprintf</code> function except that the arguments consumed when processing the format string are retrieved via the <code>stdarg</code> variable length argument facility.
<b>Return Value:</b>	<code>vprintf</code> returns EOF if an error occurs, otherwise the number of characters output is returned.
<b>Filename:</b>	vprintf.c

---

---

## vsprintf

---

<b>Function:</b>	Formatted string output to a data memory buffer with the arguments for processing the format string supplied via the <code>stdarg</code> facility.
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<pre>int vsprintf (char *buf, const rom char *fmt,               va_list ap);</pre>
<b>Remarks:</b>	The <code>vsprintf</code> function formats output, storing the characters to the destination data memory buffer, <code>buf</code> . The format string, <code>fmt</code> , is processed as described for the <code>fprintf</code> function except that the arguments consumed when processing the format string are retrieved via the <code>stdarg</code> variable-length-argument facility.
<b>Return Value:</b>	<code>vsprintf</code> returns EOF if an error occurs, otherwise the number of characters output is returned.
<b>Filename:</b>	<code>vsprintf.c</code>

---

## \_usart\_putc

---

<b>Function:</b>	Single character output to the USART (USART1 for devices which have more than one USART).
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<pre>int _usart_putc (char c);</pre>
<b>Remarks:</b>	<p><code>_usart_putc</code> is the library output function invoked by <code>putc</code> when <code>_H_USART</code> is the destination stream. The character to be output is assigned to the transmit register (TXREG) when the USART is ready for output (TRMT is set).</p> <p>If the USART is not enabled when <code>_usart_putc</code> is called (TXSTA bit TXEN is clear), the USART will be enabled (TXEN and SPEN will be set) and set to maximum baud rate output (SPBRG will be assigned a value of zero). This configuration allows the character output library functions to be used with the MPLAB IDE support for USART debug output without explicit peripheral configuration.</p>
<b>Return Value:</b>	<code>_usart_putc</code> returns the value of the character which was output.
<b>Filename:</b>	<code>_usart_putc.c</code>

---

## \_user\_putc

---

<b>Function:</b>	Single character output in an application defined manner.
<b>Include:</b>	<code>stdio.h</code>
<b>Prototype:</b>	<pre>int _user_putc (char c);</pre>
<b>Remarks:</b>	<code>_user_putc</code> is an application defined function. It will be called by the character output functions for each character to be output when the destination stream is <code>_H_USER</code> .
<b>Return Value:</b>	<code>_user_putc</code> returns the value of the character which was output.

NOTES:



---

## Chapter 5. Math Libraries

---

### 5.1 INTRODUCTION

This chapter documents math library functions. It includes two sections:

- 32-Bit Floating Point Math Library
- The C Standard Library Math Functions

### 5.2 32-BIT FLOATING POINT MATH LIBRARY

The basic floating point operations—add, subtract, multiply, divide and conversions between floats and integers—comply with the IEEE 754 standard for single precision floats with two exceptions. The exceptions will be discussed under Subnormals (**Section 5.2.1.2 “Subnormals”**) and Rounding (**Section 5.2.2 “Rounding”**). The extended mode and traditional mode use the same float representations and the results of float operations are the same.

The IEEE standard for binary floating-point arithmetic published in 1985 became known officially as ANSI/IEEE Std 754-1985 [IEEE85]. The standard has three important requirements:

- consistent representation of floating-point numbers by all machines adopting the standard;
- correctly rounded floating-point operations, using various rounding modes;
- consistent treatment of exceptional situations such as division by zero.

#### 5.2.1 Floating-Point Representation

The C18 floating point number representation follows the single precision IEEE 754 standard. A floating-point number consists of four parts:

1. A sign
2. A significand
3. A base
4. An exponent

These components are of the form

$$x = \pm d_0.d_1.d_2.d_3 \cdots d_{23} \times 2^E$$

where  $\pm$  is the sign,  $d_0.d_1.d_2.d_3 \cdots d_{23}$  is the significand, and  $E$  is the exponent to which the base 2 is raised. Each  $d_i$  is a digit (0 or 1). The exponent  $E$  is an integer in the range  $E_{min}$  to  $E_{max}$  where  $E_{min} = -126$  and  $E_{max} = 127$ .

Single-format numbers use a 32-bit word organized as a 1-bit sign, an 8-bit biased exponent  $e = E + 127$ , and a 23-bit fraction, which is the fractional part of the significand.

The most-significant bit of the significand ( $d_0$ ) is not stored. This is possible because its value can be inferred from the exponent value: if the biased exponent value is 0, then  $d_0 = 0$ , otherwise  $d_0 = 1$ . Using this convention allows 24 bits of precision to be stored in 23 physical bits.

Sign	8-bit biased exponent $E$	23-bit unsigned fraction $f$
$\pm$	$e_7e_6e_5e_4e_3e_2e_1e_0$	$d_0d_1d_2d_3 \dots d_{23}$

In the C18 implementation, the  $d_0 = 0$  numbers are not used (see **Section 5.2.1.2 “Subnormals”**).

## 5.2.1.1 NORMALS

All the lines in Table 5-1 except the first and last refer to normalized numbers. The exponent bit string  $e_7e_6e_5 \dots e_0$  uses a biased representation; the bit string is stored as the binary representation of  $E+127$ , where  $E$  is the unbiased exponent. The number 127, which is added to the exponent  $E$ , is called the *exponent bias*. For example, the number  $1=(1.000 \dots 0)_2 2^0$  is stored as

0	01111111	00000000000000000000000
---	----------	-------------------------

Here the exponent bit string is the binary representation for  $0+127$  and the fraction bit string is the binary representation for 0 (the fractional part of 1.0).

The range of exponent field bit strings for normalized numbers is 00000001 to 11111110 (the decimal numbers 1 through 254), representing actual exponents from  $E_{\min} = -126$  to  $E_{\max} = 127$ .

**TABLE 5-1: IEEE-754 SINGLE FORMAT**

Biased Exponent	Number Represented
$(00000000)_2 = (00)_{16} = (0)_{10}$	$\pm (0.d_1d_2d_3 \dots d_{23})_2 \times 2^{-126}$
$(00000001)_2 = (01)_{16} = (1)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{-126}$
$(00000010)_2 = (02)_{16} = (2)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{-125}$
$(00000011)_2 = (03)_{16} = (3)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{-124}$
↓	↓
$(01111110)_2 = (7E)_{16} = (126)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{-1}$
$(01111111)_2 = (7F)_{16} = (127)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^0$
$(10000000)_2 = (80)_{16} = (128)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^1$
↓	↓
$(11111100)_2 = (FC)_{16} = (252)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{125}$
$(11111101)_2 = (FD)_{16} = (253)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{126}$
$(11111110)_2 = (FE)_{16} = (254)_{10}$	$\pm (1.d_1d_2d_3 \dots d_{23})_2 \times 2^{127}$
$(11111111)_2 = (FF)_{16} = (255)_{10}$	$\pm \infty$ if $d_1 \dots d_{23} = 0$ NaN if $d_1 \dots d_{23} \neq 0$

The smallest positive, non-zero normalized number that can be stored is represented by

0	00000001	00000000000000000000000
---	----------	-------------------------

and this is denoted by

$$N_{\min} = (1.000 \dots 0)_2 \times 2^{-126} = 2^{-126} \sim 1.2 \times 10^{-38}$$

The constant  $N_{\min}$  is accessible to C programmers using the manifest constant `FLT_MIN` defined in `<float.h>`.

The largest normalized number (equivalently, the largest finite number) is represented by

0	11111110	11111111111111111111111
---	----------	-------------------------

and this is denoted by

$$N_{\max} = (1.111 \dots 1)_2 \times 2^{127} = (2 - 2^{-23}) \times 2^{127} \sim 2^{128} \sim 3.4 \times 10^{38}$$

The constant  $N_{\max}$  is accessible to C programmers using the manifest constant `FLT_MAX` defined in `<float.h>`.

### 5.2.1.2 SUBNORMALS

The smallest normalized number that can be represented is  $2^{-126}$ . The IEEE 754 standard uses the combination of a zero biased exponent  $e$  and a nonzero fraction  $f$  to represent smaller numbers called subnormal numbers. The structure of subnormal numbers is shown on line 1 of Table 5-1. In the C18 float implementation, subnormal numbers are always converted to signed zero.

IEEE 754 uses two different zero representations:  $+0$  and  $-0$ . The  $+0$  is represented by all zero bits. The  $-0$  is represented by all zero bits except for the sign bit.

If the result of a float operation is less than the smallest normalized number, the result is set to a signed zero before it is returned. Since, in the C18 implementation, no float operation can create a subnormal, a subnormal will appear only if it is constructed explicitly as a literal, or is generated in some way other than by standard float operations. If a subnormal value is used in a float operation, it is converted automatically to a signed zero before it is used in the operation.

### 5.2.1.3 NaNs

In addition to supporting signed infinities, signed zeroes and signed non-zero finite numbers, the IEEE floating-point format specifies an encoding for error patterns. These patterns are not numbers but a recording of the fact that an invalid operation has been attempted. Any such pattern is an error indicator, not a floating-point number and so is referred to as Not a Number, or NaN. Invalid operations are defined by the IEEE standard to include:

- Magnitude subtraction of infinities, such as  $(+\infty) + (-\infty)$
- Multiplication of a zero by an infinity, such as  $(0) \times (+\infty)$
- Division of a zero or infinity by zero or infinity, respectively, such as  $(+\infty)/(-\infty)$  or  $(+\infty)/(+\infty)$

NaNs have a biased exponent of 255, which is also the exponent used to encode infinities. The interpretation when the biased exponent is 255 is: if the fraction is zero, the encoding represents an infinity; if the fraction is not zero, the encoding represents NaN (not a number). Ignoring the sign bit, which the standard does not interpret for NaNs, there are therefore  $2^{23} - 1$  possible NaNs. The C18 implementation returns the NaN pattern  $7FFF\ FFFF_{16}$  in response to an invalid operation. That is, the sign bit is 0, the exponent is 255, and the fraction bits are all 1s.

## 5.2.2 Rounding

The IEEE-754 standard requires that operations be correctly rounded. The standard defines the correctly rounded value of  $x$ , which is denoted by  $\text{round}(x)$ , as follows: If  $x$  is a floating-point number, then  $\text{round}(x) = x$ . Otherwise, the correctly-rounded value depends on which of four rounding modes is in effect. The C18 float implementation uses the Round to Nearest mode with a slight modification to the IEEE 754 standard. The threshold for rounding up is about 0.502 instead of exactly 0.5. This gives a slight bias toward rounding toward zero. This modification results in a significant savings in code space and execution time with virtually no consequences for real-world calculations.

## 5.3 THE C STANDARD LIBRARY MATH FUNCTIONS

All the math functions of the standard C Library will return NaN if one or more of its arguments:

- is NaN.
- is outside the range of values for which the function has a defined real value, for example the square root of a negative number.

Table 5-2 lists the math functions.

**TABLE 5-2: MATH LIBRARY FUNCTIONS**

Function	Description
acos	Compute the inverse cosine (arccosine).
asin	Compute the inverse sine (arcsine).
atan	Compute the inverse tangent (arctangent).
atan2	Compute the inverse tangent (arctangent) of a ratio.
ceil	Compute the ceiling (least integer).
cos	Compute the cosine.
cosh	Compute the hyperbolic cosine.
exp	Compute the exponential $e^x$ .
fabs	Compute the absolute value.
floor	Compute the floor (greatest integer).
fmod	Compute the remainder.
frexp	Split into fraction and exponent.
ieeeetomchp	Convert an IEEE-754 format 32-bit floating point value into the Microchip 32-bit floating point format.
ldexp	Load exponent – compute $x * 2^n$ .
log	Compute the natural logarithm.
log10	Compute the common (base 10) logarithm.
mchpt IEEE	Convert a Microchip format 32-bit floating point value into the IEEE-754 32-bit floating point format.
modf	Compute the modulus.
pow	Compute the exponential $x^y$ .
sin	Compute the sine.
sinh	Compute the hyperbolic sine.
sqrt	Compute the square root.
tan	Compute the tangent.
tanh	Compute the hyperbolic tangent.

---

### 5.3.1 Function Descriptions

---

#### acos

---

<b>Function:</b>	Compute the inverse cosine (arccosine)
<b>Include:</b>	<code>math.h</code>
<b>Prototype:</b>	<code>float acos( float x );</code>
<b>Remarks:</b>	This function computes the inverse cosine (arccosine) of the argument $x$ , which must be between $-1$ and $+1$ . Arguments outside the permitted range produce domain errors and the result is NaN.
<b>Return Value:</b>	The returned value is the arccosine in radians, and is between $0$ and $\pi$ .
<b>File Name:</b>	<code>acos.c</code>

---

#### asin

---

<b>Function:</b>	Compute the inverse sine (arcsine).
<b>Include:</b>	<code>math.h</code>
<b>Prototype:</b>	<code>float asin( float x );</code>
<b>Remarks:</b>	This function computes the inverse sine (arcsine) of the argument $x$ , which must be between $-1$ and $+1$ . Arguments outside the permitted range produce domain errors and the result is NaN.
<b>Return Value:</b>	The returned value is the arcsine in radians, and is between $-\pi/2$ and $\pi/2$ .
<b>File Name:</b>	<code>asin.c</code>

---

#### atan

---

<b>Function:</b>	Compute the inverse tangent (arctangent).
<b>Include:</b>	<code>math.h</code>
<b>Prototype:</b>	<code>float atan( float x );</code>
<b>Remarks:</b>	This function computes the inverse tangent (arctangent) of the argument $x$ . If $x$ is a NaN, a domain error occurs and the value returned is NaN.
<b>Return Value:</b>	The returned value is in radians, and between $-\pi/2$ and $\pi/2$ .
<b>File Name:</b>	<code>atan.c</code>

---

#### atan2

---

<b>Function</b>	Compute the inverse tangent (arctangent) of a ratio.
<b>Include:</b>	<code>math.h</code>
<b>Prototype:</b>	<code>float atan2( float y, float x );</code>
<b>Remarks:</b>	This function computes the inverse tangent (arctangent) of $y/x$ . If $x$ or $y$ is NaN, a domain occurs and the value returned is NaN. If $x$ is a NaN, or if $x = y = 0$ , or if $x = y = \infty$ , a domain error occurs and the value returned is NaN.
<b>Return Value:</b>	The returned value is in radians, and between $-\pi$ and $\pi$ .
<b>File Name:</b>	<code>atan2.c</code>

---

---

## ceil

---

**Function:** Compute the ceiling (least integer).  
**Include:** `math.h`  
**Prototype:** `float ceil ( float x );`  
**Remarks:** None.  
**Return Value:** The smallest integer greater than or equal to  $x$ .  
**File Name:** `ceil.c`

---

---

## COS

---

**Function:** Compute the cosine.  
**Include:** `math.h`  
**Prototype:** `float cos ( float x );`  
**Remarks:** Computes the cosine of  $x$  (in radians). A domain error results from an argument that is infinite or NaN. Both cases return NaN.  
**Return Value:** The cosine of argument  $x$ .  
**File Name:** `cos.c`

---

---

## cosh

---

**Function:** Compute the hyperbolic cosine.  
**Include:** `math.h`  
**Prototype:** `float cosh ( float x );`  
**Remarks:** None.  
**Return Value:** The hyperbolic cosine of argument  $x$ .  
**File Name:** `cosh.c`

---

---

## exp

---

**Function:** Compute the exponential  $e^x$ .  
**Include:** `math.h`  
**Prototype:** `float exp ( float x );`  
**Remarks:** A range error occurs if the magnitude of  $x$  is too large. The range of this function is limited to values for the exponent of between approximately -103.2789 and 88.722283. The minimum value of the result is  $2^{-149}$  and the maximum is  $2^{127}$ .  
**Return Value:** The value of the exponential  $e^x$ .  
**File Name:** `exp.c`

---

---

## fabs

---

**Function:** Compute the absolute value.  
**Include:** `math.h`  
**Prototype:** `float fabs( float x );`  
**Remarks:** For floating point arguments that are zeroes and infinities, the return value is the argument with the sign bit cleared.  
**Return Value:** The absolute value of  $x$ .  
**File Name:** `fabs.c`

---

---

**floor**

---

**Function:** Compute the floor (greatest integer).  
**Include:** `math.h`  
**Prototype:** `float floor( float x );`  
**Remarks:** None.  
**Return Value:** The largest integer less than or equal to  $x$ .  
**File Name:** `floor.c`

---



---

**fmod**

---

**Function:** Compute the remainder.  
**Include:** `math.h`  
**Prototype:** `float fmod( float x, float y );`  
**Remarks:** None.  
**Return Value:** The remainder for  $x$  modulo  $y$ .  
**File Name:** `fmod.c`

---



---

**frexp**

---

**Function:** Split into fraction and exponent.  
**Include:** `math.h`  
**Prototype:** `float frexp( float x, int *pexp );`  
**Remarks:** Separates the argument  $x$  into two parts that fit this formula:  

$$x = \text{frexp}(x, *pexp) \times 2^{*pexp}$$
The integer value, which is stored at location `pexp`, is chosen so that the fractional portion of the result is between  $\frac{1}{2}$  and 1.  
**Return Value:** Fractional result that satisfies the conditions listed above.  
**File Name:** `frexp.c`

---



---

**ieeetomchp**

---

**Function:** Convert an IEEE-754 format 32-bit floating point value into the Microchip 32-bit floating point format.  
**Include:** `math.h`  
**Prototype:** `unsigned long ieeetomchp( float v );`  
**Remarks:** This function adjusts the sign bit of the floating point representation to be located as required by the Microchip format:

	eb	f0	f1	f2
IEEE-754 32-bit	seee eeee	exxx xxxx	xxxx xxxx	xxxx xxxx
Microchip 32-bit	eeee eeee	sxxx xxxx	xxxx xxxx	xxxx xxxx
	<i>s=sign bit</i>	<i>e=exponent</i>	<i>x=significand</i>	

**Return Value:** The converted 32-bit value.  
**File Name:** `ieeetomchp.c`

---

---

## ldexp

---

**Function:** Load exponent – compute  $x * 2^n$ .  
**Include:** `math.h`  
**Prototype:** `float ldexp( float x, int n );`  
**Remarks:** None.  
**Return Value:** Returns the value of  $x * 2^n$ .  
**File Name:** `ldexp.c`

---

## log

---

**Function:** Compute the natural logarithm.  
**Include:** `math.h`  
**Prototype:** `float log( float x );`  
**Remarks:** A domain error occurs if the argument is not in the interval  $[0, +\infty]$ .  
**Return Value:** Natural logarithm of  $x$ .  
**File Name:** `log.c`

---

## log10

---

**Function:** Compute the common (base 10) logarithm.  
**Include:** `math.h`  
**Prototype:** `float log10( float x );`  
**Remarks:** A domain error occurs if the argument is not in the interval  $[0, +\infty]$ .  
**Return Value:**  $\log_{10}x$ .  
**File Name:** `log10.c`

---

## mchpt IEEE

---

**Function:** Convert a Microchip format 32-bit floating point value into the IEEE-754 32-bit floating point format.  
**Include:** `math.h`  
**Prototype:** `float ieeeTomchp( unsigned long v );`  
**Remarks:** This function adjusts the sign bit of the floating point representation to be located as required by the IEEE format:

	eb	f0	f1	f2
IEEE-754 32-bit	seee eeee	exxx xxxx	xxxx xxxx	xxxx xxxx
Microchip 32-bit	eeee eeee	sxxx xxxx	xxxx xxxx	xxxx xxxx

*s=sign bit      e=exponent      x=significand*

**Return Value:** The converted floating point value.  
**File Name:** `mchpt IEEE.c`

---



---

## modf

---

<b>Function:</b>	Compute the modulus.
<b>Include:</b>	math.h
<b>Prototype:</b>	float modf( float x, float *ipart );
<b>Remarks:</b>	This function separates the argument x into integer and fractional parts. The fractional part is returned, and the integer part is stored at location ipart. If the argument is NaN, the results for both the fractional and integer part will be NaN as well.
<b>Return Value:</b>	Fractional portion of x.
<b>File Name:</b>	modf.c

---

## pow

---

<b>Function:</b>	Compute the exponential $x^y$ .
<b>Include:</b>	math.h
<b>Prototype:</b>	float pow( float x, float y );
<b>Remarks:</b>	Domain errors occur if x is finite and negative, and y is finite and not an integer; also if x is zero and y is less than or equal to zero. A range error occurs if $x^y$ is too large or too small to be represented. In such a case, a correctly signed infinity or zero is returned and a range error is signaled.
<b>Return Value:</b>	xy.
<b>File Name:</b>	pow.c

---

## sin

---

<b>Function:</b>	Compute the sine.
<b>Include:</b>	math.h
<b>Prototype:</b>	float sin( float x );
<b>Remarks:</b>	Computes the sine of x (in radians). A domain error results from an argument that is infinite or NaN. Both cases return NaN.
<b>Return Value:</b>	The sine of x.
<b>File Name:</b>	sin.c

---

## sinh

---

<b>Function:</b>	Compute the hyperbolic sine.
<b>Include:</b>	math.h
<b>Prototype:</b>	float sinh( float x );
<b>Remarks:</b>	None.
<b>Return Value:</b>	The hyperbolic sine of argument x.
<b>File Name:</b>	sinh.c

---

---

## sqrt

---

**Function:** Compute the square root.

**Include:** `math.h`

**Prototype:** `float sqrt( float x );`

**Remarks:** A domain error occurs if the argument `x` is strictly negative. The principal square root exists and is computable for every non-negative floating point number `x`.

**Return Value:** The square root of `x`.

**File Name:** `sqrt.c`

---

## tan

---

**Function:** Compute the tangent.

**Include:** `math.h`

**Prototype:** `float tan( float x );`

**Remarks:** Computes the tangent of `x` (in radians). A domain error occurs if the argument is infinite or NaN. Both cases return NaN.

**Return Value:** The tangent of `x`.

**File Name:** `tan.c`

---

## tanh

---

**Function:** Compute the hyperbolic tangent.

**Include:** `math.h`

**Prototype:** `float tanh( float x );`

**Remarks:** If the argument is NaN, the return value is NaN.

**Return Value:** The hyperbolic tangent of `x`.

**File Name:** `tanh.c`

---

---

## Glossary

---

### A

**Absolute Section**

A section with a fixed address that cannot be changed by the linker.

**Access Memory**

Special General Purpose Registers (GPR) on the PIC18 PICmicro microcontrollers that allow access regardless of the setting of the Bank Select Register (BSR).

**Address**

The code that identifies where a piece of information is stored in memory.

**Anonymous Structure**

An unnamed object.

**ANSI**

American National Standards Institute

**Assembler**

A language tool that translates assembly source code into machine code.

**Assembly**

A symbolic language that describes the binary machine code in a readable form.

**Assigned Section**

A section that has been assigned to a target memory block in the linker command file.

**Asynchronously**

Multiple events that do not occur at the same time. This is generally used to refer to interrupts that may occur at any time during processor execution.

### B

**Binary**

The base two numbering system that uses the digits 0-1. The right-most digit counts ones, the next counts multiples of 2, then  $2^2 = 4$ , etc.

### C

**Central Processing Unit**

The part of a device that is responsible for fetching the correct instruction for execution, decoding that instruction, and then executing that instruction. When necessary, it works in conjunction with the arithmetic logic unit (ALU) to complete the execution of the instruction. It controls the program memory address bus, the data memory address bus, and accesses to the stack.

**Compiler**

A program that translates a source file written in a high-level language into machine code.

## **Conditional Compilation**

The act of compiling a program fragment only if a certain constant expression, specified by a preprocessor directive, is true.

## **CPU**

Central Processing Unit

## **E**

### **Endianness**

The ordering of bytes in a multi-byte object.

### **Error File**

A file containing the diagnostics generated by the MPLAB C18 compiler.

### **Extended Mode**

In Extended mode, the compiler will utilize the extended instructions (i.e., ADDFSR, ADDULNK, CALLW, MOVSE, MOVSS, PUSHL, SUBFSR and SUBULNK) and the indexed with literal offset addressing.

## **F**

### **Fatal Error**

An error that will halt compilation immediately. No further messages will be produced.

### **Frame Pointer**

A pointer that references the location on the stack that separates the stack-based arguments from the stack-based local variables.

### **Free-standing**

An implementation that accepts any strictly conforming program that does not use complex types and in which the use of the features specified in the library clause (ANSI '89 standard clause 7) is confined to the contents of the standard headers `<float.h>`, `<iso646.h>`, `<limits.h>`, `<stdarg.h>`, `<stdbool.h>`, `<stddef.h>` and `<stdint.h>`.

## **H**

### **Hexadecimal**

The base 16 numbering system that uses the digits 0-9 plus the letters A-F (or a-f). The digits A-F represent decimal values of 10 to 15. The right-most digit counts ones, the next counts multiples of 16, then  $16^2 = 256$ , etc.

### **High-level Language**

A language for writing programs that is further removed from the processor than assembly.

## **I**

### **ICD**

In-Circuit Debugger

### **ICE**

In-Circuit Emulator

### **IDE**

Integrated Development Environment

## **IEEE**

Institute of Electrical and Electronics Engineers

## **Interrupt**

A signal to the CPU that suspends the execution of a running application and transfers control to an ISR so that the event may be processed. Upon completion of the ISR, normal execution of the application resumes.

## **Interrupt Service Routine**

A function that handles an interrupt.

## **ISO**

International Organization for Standardization

## **ISR**

Interrupt Service Routine

## **L**

### **Latency**

The time between when an event occurs and the response to it.

### **Librarian**

A program that creates and manipulates libraries.

### **Library**

A collection of relocatable object modules.

### **Linker**

A program that combines object files and libraries to create executable code.

### **Little Endian**

Within a given object, the Least Significant Byte is stored at lower addresses.

## **M**

### **Memory Model**

A description that specifies the size of pointers that point to program memory.

### **Microcontroller**

A highly integrated chip that contains a CPU, RAM, some form of ROM, I/O ports and timers.

### **MPASM Assembler**

Microchip Technology's relocatable macro assembler for PICmicro microcontroller families.

### **MPLIB Object Librarian**

Microchip Technology's librarian for PICmicro microcontroller families.

### **MPLINK Object Linker**

Microchip Technology's linker for PICmicro microcontroller families.

## **N**

### **Non-extended Mode**

In Non-extended mode, the compiler will not utilize the extended instructions nor the indexed with literal offset addressing.

## O

### Object File

A file containing object code. It may be immediately executable or it may require linking with other object code files (e.g., libraries) to produce a complete executable program.

### Object Code

The machine code generated by an assembler or compiler.

### Octal

The base 8 number system that only uses the digits 0-7. The right-most digit counts ones, the next digit counts multiples of 8, then  $8^2 = 64$ , etc.

## P

### Pragma

A directive that has meaning to a specific compiler.

## R

### RAM

Random Access Memory

### Random Access Memory

A memory device in which information can be accessed in any order.

### Read Only Memory

Memory hardware that allows fast access to permanently stored data but prevents addition to or modification of the data.

### ROM

Read Only Memory

### Recursive

Self-referential (e.g., a function that calls itself).

### Reentrant

A function that may have multiple, simultaneously active instances. This may happen due to either direct or indirect recursion or through execution during interrupt processing.

### Relocatable

An object whose address has not been assigned to a fixed memory location.

### Runtime Model

Set of assumptions under which the compiler operates.

## S

### Section

A portion of an application located at a specific address of memory.

### Section Attribute

A characteristic ascribed to a section (e.g., an access section).

### Special Function Register

Registers that control I/O processor functions, I/O status, timers or other modes or peripherals.

**Storage Class**

Determines the lifetime of the memory associated with the identified object.

**Storage Qualifier**

Indicates special properties of the objects being declared (e.g., `const`).

**V****Vector**

The memory locations that an application will jump to when either a Reset or interrupt occurs.

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