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1  #include "switch.h"
2
3  /// extended state -----
4  // "basic" state
5  typedef enum {SW_IDLE, SW_IN, SW_OUT} swm_state_t;
6  static swm_state_t g_swm_state;
7
8  // externally reachable objects
9  bool gb_swm_long_msg; // set (externally) to start a measurement
10 bool gb_swm_msg; // set when a measurement is completed
11
12 // parameter to rf done msg
13 bool volatile gb_swm_can_sleep; // this FSM can sleep
14
15 // hardware resources
16 static InterruptIn *g_swm;
17
18 static Timeout tout_4ms; // timeout // pulsacion de un segundo
19 static Timer swm_tmr;
20 static Timeout tout_20ms;
21
22
23 // internal objects
24 static bool volatile gb_swm_initd; // true after call to rf init()
25
26 static bool volatile swm_fall_evnt;
27 static bool volatile swm_rise_evnt;
28
29 static bool volatile tout_4ms_evnt; // rebotes
30 static bool volatile tout_20ms_evnt;
31
32 // end of extended state -----
33
34 // ISRs -----
35 // switch SWM ISR
36 static void swm_fall_isr(void) {
37     swm_fall_evnt = true;
38     gb_swm_can_sleep = false;
39 }
40
41 static void swm_rise_isr(void){
42     swm_rise_evnt = true;
43     gb_swm_can_sleep = false;
44 }
45
46
47 //timeout ISR
48 static void tout_4ms_isr (void) {
49     tout_4ms_evnt = true;
50     gb_swm_can_sleep = false;
51 }
52
53 static void tout_20ms_isr (void) {
54     tout_20ms_evnt = true;
55     gb_swm_can_sleep = false;
56 }
57
58 // end of ISRs -----
59
60 // FSM -----
61 void swm_fsm (void) {
62     if (gb_swm_initd) { // protect against calling rf_fsm() w/o a previous call to rf init()
63         switch (g_swm_state) {
64
65             case SW_IDLE :
66
67                 if(swm_fall_evnt){
68                     swm_fall_evnt = false;
69                     tout_4ms.attach_us(tout_4ms_isr,4000);
70                 }
71                 if(tout_4ms_evnt){
72                     tout_4ms_evnt = false;
73                     tout_20ms.attach_us(tout_20ms_isr,20000);
74                     g_swm_state = SW_IN;
75                 }
76                 break;
77
78             case SW_IN :
79                 swm_fall_evnt = false;
80
81                 if(tout_20ms_evnt){
82                     tout_20ms_evnt = false;
83
84                     if(0U == *g_swm){

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85         swm_tmr.reset();
86         swm_tmr.start();
87         g_swm_state = SW_OUT;
88
89     }else{
90         g_swm_state = SW_IDLE;
91     }
92 }
93 break;
94
95 case SW_OUT :
96     swm_fall_evnt = false;
97
98     if(swm_rise_evnt){
99         swm_rise_evnt = false;
100         tout_4ms.attach_us(tout_4ms_isr, 4000);
101     }
102
103     if(tout_4ms_evnt){
104         tout_4ms_evnt = false;
105
106         if(swm_tmr.read_us() >= 1000000){
107             swm_tmr.stop();
108             gb_swm_long_msg = true;
109             g_swm_state = SW_IDLE;
110         }
111
112         if(swm_tmr.read_us() < 1000000){
113             swm_tmr.stop();
114             gb_swm_msg = true;
115             g_swm_state = SW_IDLE;
116         }
117     }
118
119     break;
120
121 // -----
122 } // switch (swm_state)
123
124
125 __disable_irq();
126 if(!swm_fall_evnt && !tout_4ms_evnt && !tout_20ms_evnt && !swm_rise_evnt &&
!tout_4ms_evnt ) {
127     gb_swm_can_sleep = true;
128 }
129 __enable_irq();
130 } // if (gb_rf_initd)
131 }
132 // end of FSM -----
133
134 // initialize FSM machinery -----
135 void swm_init(InterruptIn *swm){
136     if (!gb_swm_initd) {
137         gb_swm_initd = true;    // protect against multiple calls to rf_init
138
139         // initialize state
140         g_swm_state = SW_IDLE;
141
142         // initial actions
143         g_swm = swm;
144         swm_tmr.stop();
145         swm_tmr.reset();
146
147         g_swm->fall(swm_fall_isr);
148         g_swm->rise(swm_rise_isr);
149     }
150 }
151 // end of FSM initialization -----
152

```