

## **RPi.GPIO Module Usage**

## Import the module:

import RPI.GPIO (as "whatever" if desired - as IO is assumed in the following)

**Pin numbering:** a choice is <u>required</u> to specify channel

designations:

IO.setmode(IO.BOARD)

...Or... (see reverse side for diagram)

IO.setmode(IO.BCM)

**Setup:** every channel that is to be used:

IO.setup(channel, IO.IN) IO.setup(channel, IO.OÚT)

You can specify an initial state for the pin:

IO.setup(channel, IO.OUT, initial=IO.HIGH)

Or setup a bunch at a time:

**chan\_list = [11,12]** add multiple channels

can use tuples instead i.e.: chanlist = (11,12)

IO.setup(chan\_list, IO.OUT)

Read or write (set) pins: (NOTE: a "pin" is the

same as a "channel")

**IO.input(channel)** (o=False=IO.Low,1=True=IO.High)

**IO.output(channel, state)** (states same as above)

Can output to several channels with one command:

chanlist = [11,12] <- this also works with tuples

IO.output(chanlist, IO.LOW) <- this sets all to ÎO.LOW

IO.output(chanlist, (IO.HIGH, IO.LOW)) <- this sets first

HIGH and the second LOW

**Environmental information:** 

**GPIO.RPI INFO** about your RPi

**GPIO.RPI\_INFO['P1\_REVISION']** Raspberry Pi board revision **GPIO.VERSION** RPi.GPIO version number

Find the function of a channel:

func = IO.gpio\_function(pin)

will return a value from:

IO.IN, IO.OUT, IO.SPI, IO.I2C, IO.HARD PWM, IO.SERIAL,

IO.UNKNOWN

**Pull UP / Pull DOWN:** 

Unconnected pins float.

Default values (High or Low) can be set in **software** or with

hardware

**Hardware:** 

Pull Up:

Input channel -> 10K resistor -> 3.3V

Pull Down:

Input channel -> 10K resistor -> oV

Software:

IO.setup (channel, IO.IN, pull\_up\_down = IO.PUD\_UP) or

IO.PUD\_DOWN) or

IO.PUD OFF)

**Edge detection:** change of state event -3 ways to handle

**1. wait for edge()** function - stops everything until an edge is detected.

IO.wait\_for\_edge (channel, IO.RISING) can detect edges of type IO.RISING, IO.FALLING or IO.BOTH

2. event detected() function - use in a loop with other activity — event triggers priority response. Example:

IO.add\_event\_detect(channel, IO.RISING) activity detection on a channel

[your loop activity here]

if IO.event\_detected(channel):

print('Button pressed')

3. threaded callbacks - RPi,GPIO runs a second thread for callback functions. This means that callback functions can be run at the same time as your main program, in immediate response to an For example:

def my\_callback(channel):

print('Edge detected on channel %s'%channel') print('This is run in a different thread to your main program')

IO.add\_event\_detect(channel, IO.RISING, callback=my\_callback) add rising edge detection on a channel

...the rest of your program...

If you want more than one callback function:

def my callback one (channel):

print ('Callback one')

def my\_callback\_two (channel):

print ('Callback two')

IO.add event detect(channel, IO.RISING) 10.add event callback(channel. my callback one)

IO.add event caliback(channel, my callback two)

Note that in this case, the callback functions are run sequentially, not concurrently. This is because there is only one thread used for callbacks, in which every callback is run in the order in which they have been defined.

Switch debounce: solutions to a button event causing multiple callbacks

**Hardware:** add a 0.1uF capacitor across your switch.

**Software:** add the bouncetime= parameter to a function where you specify a callback function. bouncetime= should be specified in milliseconds.

IO.add event detect(channel. IO.RISING. callback=my callback, bouncetime=200)

IO.add\_event\_callback(channel, my\_callback, bouncetime=200)

**Remove Event Detection:** 

IO.remove event detect(channel)



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## **TOOLBOX**

Cleanup: resets all channels and clears pin num -bering system at the end of a program - just do it.

IO.cleanup()

Or cleanup just select pins:

IO.cleanup(channel)

IO.cleanup((channel1, channel2)) IO.cleanup([channel1, channel2])

<-tuple <-or list

Raspberry Pi Model B+ **3V** 1 Power GPI02 **5V** 2 3 Common breadboard numbering SDA1 12C Power GPI03 3 Ground 6 SCL<sub>1</sub>12C GPIO14 8 GPIO4 4 UARTO-TXD **GP1015** 5 Ground 10 9 UARTO-RXD GPI018 GPIO17 11 12 PCM-CLK 7 **GPI027** Ground 13 16 GPIO23 8 GPIO22 15 **3V** 18 9 GPIO24 **GPI010** Ground 10 19 20 GPI09 GPIO25 11 21 22 GPI08 GPI011 12 23 24 SPIo-SCLK SPIo-CEo-N GPI07 13 Ground 26 SPIO-CE1-N ID SC ID SD 14 27 28 12C ID EEPROM 12C ID EEPROM GPI05 29 30 Ground GPI06 GPIO12 16 31 32 GPI013 Ground 17 33 GPIO11 GPIO16 35 18 PCM-FS **GPI020** 38 19 GPIO26 37 PCM-DIN GPIO20 Ground 20 PCM-DOUT

SERIAL PERIPHERAL INTERFACE PINS

19 MOSI-master output, slave input 21 MISO-master input, slave output 23 SCK-serial clock 24 & 26-slave select pins UART - UNIVERAL ASYNCHRONOUS RECEIEVER/TRANSMITTER pins

8 UART-TDX '& 10 UART-RDX

**PWM in RPi.GPIO** is an analog signal, **Pulse Width** Modulation - available ONLY on one of the Pi's pins: board #12 = BCM, #18; used mostly for audio

To create a **software** instance of PWM on any in/out

p = IO.PWM(channel, frequency)

To start PWM: **p.start(dc)** where dc is the duty cycle (0.0 <=  $dc \le 100.0$ 

To change the frequency:

p.ChangeFrequency(freq) freq is the new

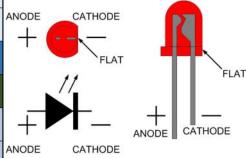
frequency in Hz\*

 $\mathcal{T}$ o change the duty cycle:

p.ChangeDutyCycle(dc) where 0.0 <= dc <= 100.0

To stop PWM:

p.stop()

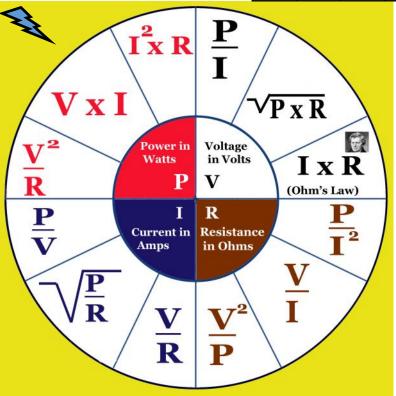


270 $\Omega$  -> red, purple, brown 330Ω -> orange, orange, brown 10KΩ -> brown, black, yellow

Note: RPi maximum current to a single pin is 16ma, to all pins is 50ma

1	<b>†</b> '	\	1
1st Digit	2nd Digit	Multiplier	Tolerance
0	0	1	
1	1	10	1%
2	2	100	2%
3	3	1 K	
4	4	10 K	
5	5	100 K	
6	6	1 M	
7	7	10M	
8	8		5% gold
9	9		10% silver

Shown below: 3600  $\Omega$  with 2% tolerance



comments and suggestions appreciated: john@johnoakey.com