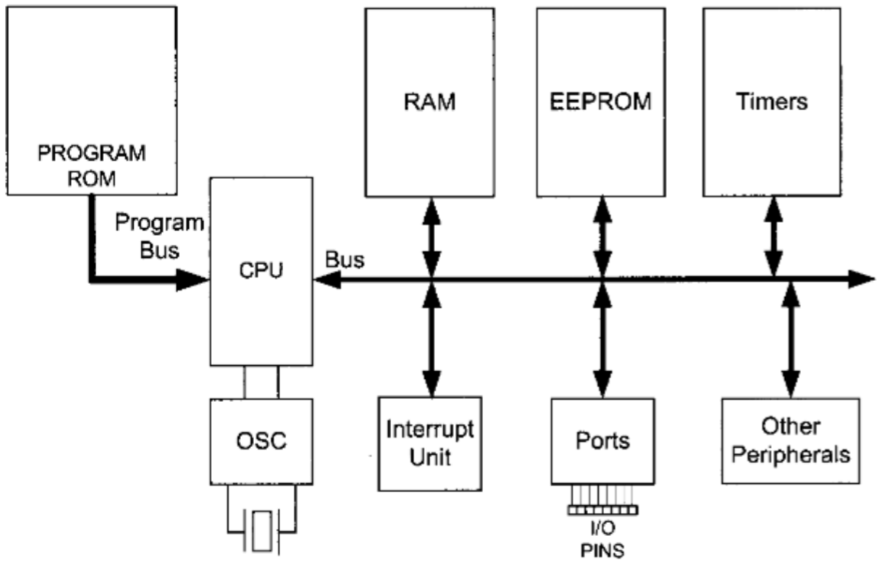
Chapter 1 AVR Architecture Overview

1-1 Introduction

AVR Classifications

- Classic AVR
- **Mega AVR**
- Tiny AVR
- Special purpose AVR



AVR Features

- an 8-bit **RISC**[1] micro controller with *Harvard Architecture*[2]
- high performance with low power
- has a CPU
- has program ROM, RAM, EEPROM, Timers and I/O ports
- owns ADC and PWM
- owns serial interfaces: USART, SPI, TWI, etc

1-2 ATmega16 Architecture Overview

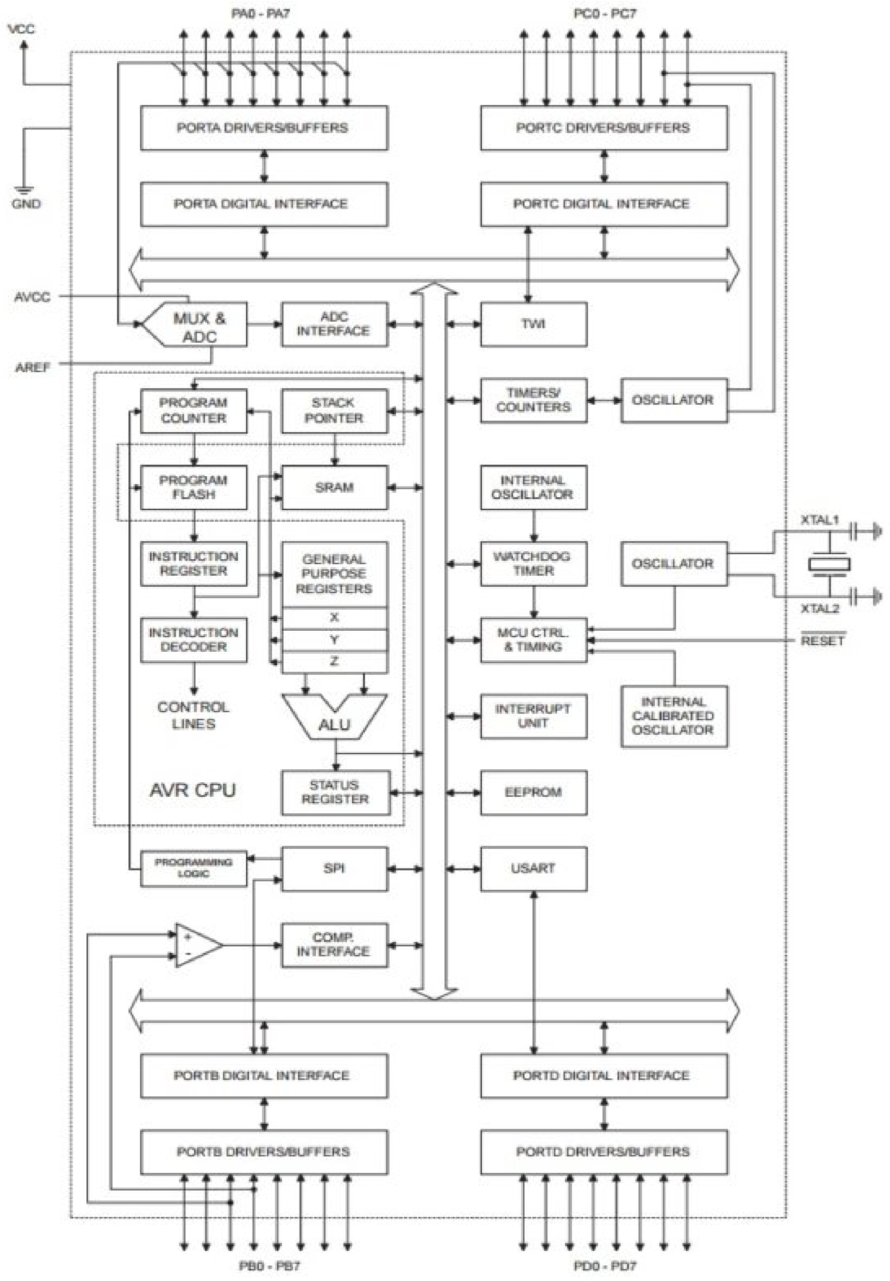
RISC Architecture

- **131** RISC-type instructions
- **32** general purpose 8-bit registers
- operates at a clock speed of **16 MHz** or handles 16 million instructions per second

Assembly Language Instruction Set

- the most efficient and fast execution for a particular micro controller
- need to be familiar with the low-level architecture details of the controller
- C language is easier to read and transfer

ATmega16 Architecture Overview



- a timer subsystem

- a communication system
- an interrupt subsystem
- an analog-to-digital converter (ADC)
- memory components

Pins

- four 8-bit ports (PORTx)
- connections for power supplies (VCC/GND/AVCC/AREF)
- external time base input pins (XTAL1/XTAL2)
- processor reset (RESET)

1-3 Memory Components

EEPROM

EEPROM, stands for electrically erasable programmable read-only memory and is a type of **non-volatile** memory used in computers, integrated in micro controllers for smart cards and remote keyless systems, and other electronic devices to store relatively small amounts of data by allowing individual bytes to be erased and reprogrammed.

Programmable Flash EEPROM

- 16K bytes
- 10 000 write/erase cycles
- stores on-chip boot program

Byte-Addressable EEPROM

- 512 bytes
- 100 000 write/erase cycles
- logs system malfunctions and fault data during program execution
- stores data must be retained during a power failure but might need to be changed periodically

SRAM

Static random-access memory (static RAM or **SRAM**) is a type of random-access memory (RAM) that uses latching circuitry (flip-flop) to store each bit. SRAM is **volatile** memory; data is lost when power is removed.[3]

- 1000 bytes

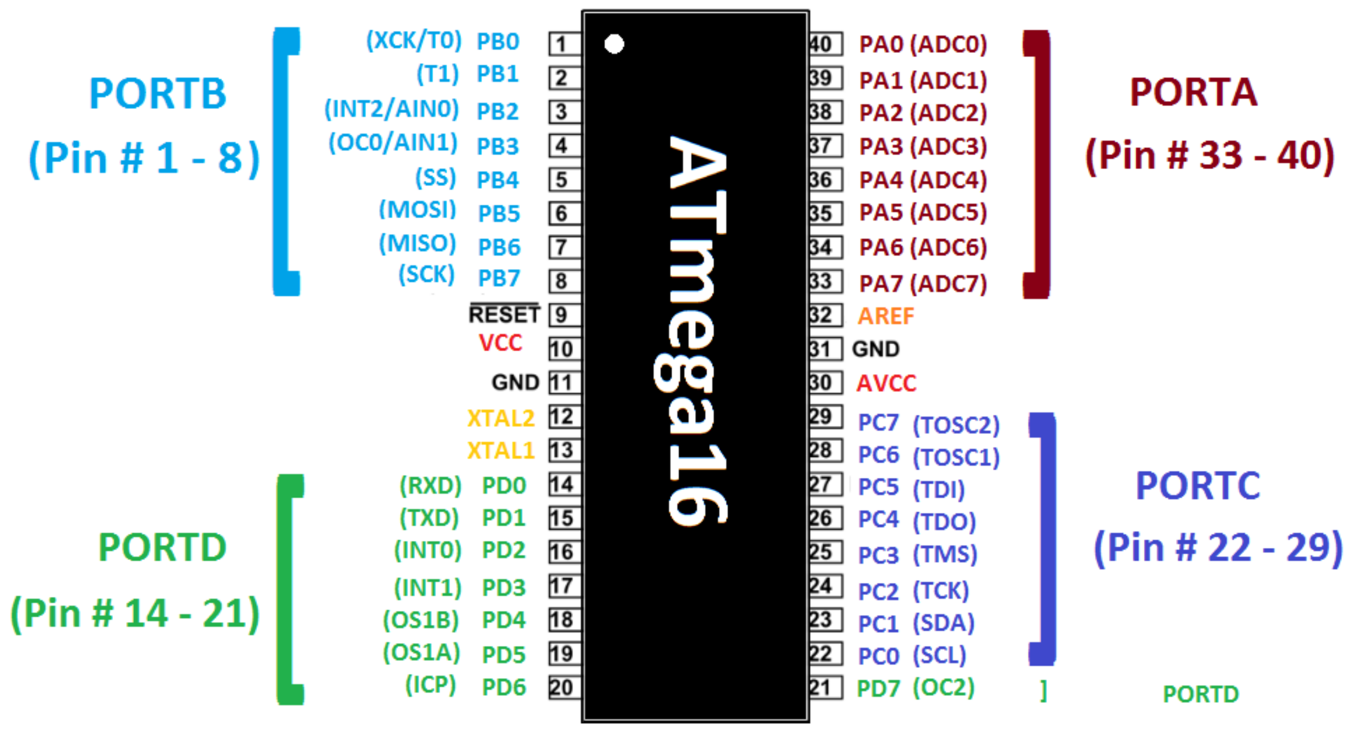
- read and be written data during program execution
- protected by programming lock

Programmable Lock Bits

- six memory lock bits for memory security from tampering
- Atmel STK500 programming board used to program lock bits

1-4 Port System

ATmega16 is equipped with **four** 8-bit general-purpose, digital I/O ports designated PORTA, PORTB, PORTC, and PORTD. And each port has **8 data pins** and is bi-directional.



Atmega16 Pinout

Data Register

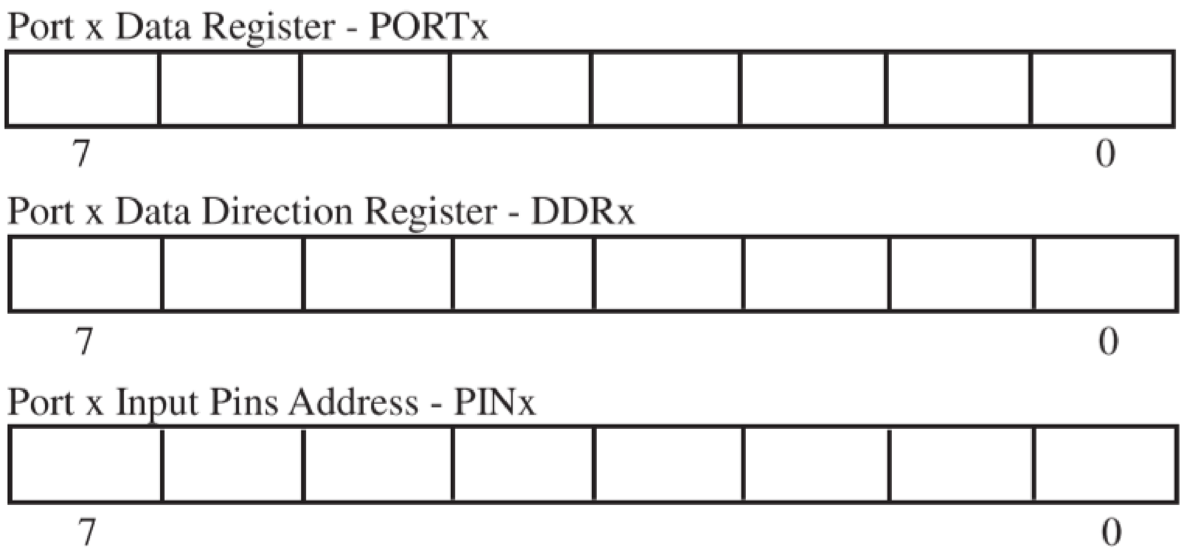
PORTx, used to write output data to the port

Data Direction Register

DDRx, used to set specific port pin to either output (1) or input (0)

Input Pin Address

PINx, used to read input data from the port


Port x Data Register - PORTx
7
0
Port x Data Direction Register - DDRx
7
0
Port x Input Pins Address - PINx
7
0

Port Pin Configuration

DDRxn	PORTxn	I/O	Comment
0	0	input	Tri-state (Hi-Z)
0	1	input	source current if externally pulled low
1	0	output	Output Low (Sink)
1	1	output	Output High (Source)

- x: port designator (A, B, C, D)
- n: pin designator (0 - 7)

Input Pin

- the pull-up resistor is **activated** when PORTxn is written **logic one**
- the pull-up resistor is **off** when PORTxn is written **logic zero** or configure the pin as the **output mode**

Output Pin

- the port is driven **high** when PORTxn is written **logic one**
- the port is drive **low** when PORTxn is written **logic zero**

1-5 Internal Subsystems

Time Base

Time base, also called as the clock, controls the speed at which a micro controller sequences through accomplishing instruction related operations

- User-selectable resistor capacitor time base is used **internally**
- **External time sources** is used to increase accuracy and stability
- Fixed clock operating frequency of **1, 2, 4 or 8** MHz

Timing Subsystem

The ATmega16 is equipped with **two** 8-bit timer/counters and **one** 16-bit timer/counter

- generate a precision output signal
- measure the characteristics of an incoming digital signal
- count external events

Pulse Width Modulation Channels

The ATmega16 is equipped with **four** PWM channels, allows the user to generate a wide variety of PWM signals

Serial Communications

Three serial communication subsystems of ATmega16

- Universal Synchronous and Asynchronous Serial Receiver and Transmitter(**USART**)
- Serial Peripheral Interface (**SPI**)
- Two-Wire Serial Interface (**TWI**)

> All of three are **serial transmission** of data

Analog-to-Digital Converter

The ATmega16 is equipped with an **eight-channel** ADC subsystem, which has **10-bit** resolution which means that an analog voltage between 0 and 5V will be encoded into one of $2^{10} = 1024$ binary representations.

Interrupts

The ATmega16 is equipped with a complement of **21 interrupt sources**[4]

- **three of the interrupts** are provided for external interrupts
- **remaining 18 interrupts** support the efficient operation of peripheral subsystems

Chapter 2 Serial Communication Subsystem

2-1 Serial Communications

Micro controllers transfer data in two ways: **parallel** and **serial**

- parallel: several data bits are transferred simultaneously
- serial: a single data bit is transferred at one time

Advantages of serial communication

- longer distances
- easier to synchronize
- fewer I/O pins and lower cost

Serial communication often requires

- **shift registers**: convert a byte to a serial bits and vice versa
- **modems**: modulate/demodulate serial bits to/from audio tones

2-2 Serial Communication Terminology

Asynchronous versus Synchronous

- Synchronous serial communication
  - the clocks of the sender and receiver are synchronized
  - a clock of characters, enclosed by synchronizing bytes, is sent at a time
  - faster transfer and less overhead
- Asynchronous serial communication
  - the clocks of the sender and receiver are not synchronized
  - one character is sent at a time, enclosed between a start bit and one or two stop bits, a parity bit may be included

Baud Rate

Data transmission rates are typically specified as a **baud** or bits per second rate

Full Duplex

A **single duplex** system has a single complement of hardware that must be switched from transmission to reception configuration

A **full duplex** serial communication system has separate hardware for transmission and reception

Nonreturn to Zero Coding Format

The ATmega16 uses a **nonreturn to zero coding** standard, coding a logic 1 is signaled by a logic high during the entire time slot allocated for a single bit, whereas a logic 0 is signaled by a logic low during the entire time slot allocated for a single bit.

RS-232 Communication Protocol

The RS-232 is a widely used standard for serial interfacing, which covers four main aspects

- Electrical: voltage level, rise and fall time, data rate and distance
- Functional: function of each signal
- Mechanical: number of pins, shape and dimension of connectors
- Procedural: sequence of events for transmitting data

Logic	RS-232 Levels	TTL Levels
1	$[-15V, -3V]$	$[+2V, +5V]$
0	$[+3V, +15V]$	$[0V, +0.8V]$

Parity

- Parity Bit: a single bit for error checking, sent with data bits to make the total number of 1's
- Start Bit: the **indication** of the start of a character
- Stop Bit: the **indication** of the end of a character

2-3 Serial USART

Hardware Elements

There are mainly **four** basic pieces in USART

- the clock generator
- the transmission hardware
- the receiver hardware
- three control registers (UCSRA, UCSRB and UCSRC)

Clock Generator

- provide clock source
- set **baud rate** using UBRR register

Transmitter

- send a character through **TxD** pin
- handle start/stop bits and parity bit, and shift register

Receiver

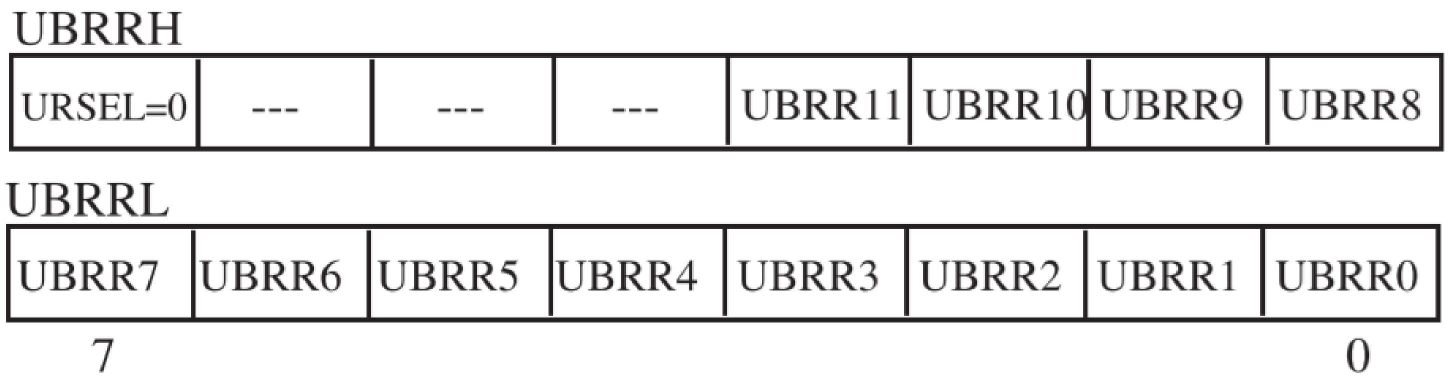
- receive a character through **RxD** pin
- perform the reverse operation of the transmitter

Registers

- configure, control and monitor the serial USART

Registers

Baud Rate Registers



UBRRH

URSEL=0	---	---	---	UBRR11	UBRR10	UBRR9	UBRR8

UBRRL

UBRR7	UBRR6	UBRR5	UBRR4	UBRR3	UBRR2	UBRR1	UBRR0

7 0

Bit Number	Register Bit	Register Bit Name	Function

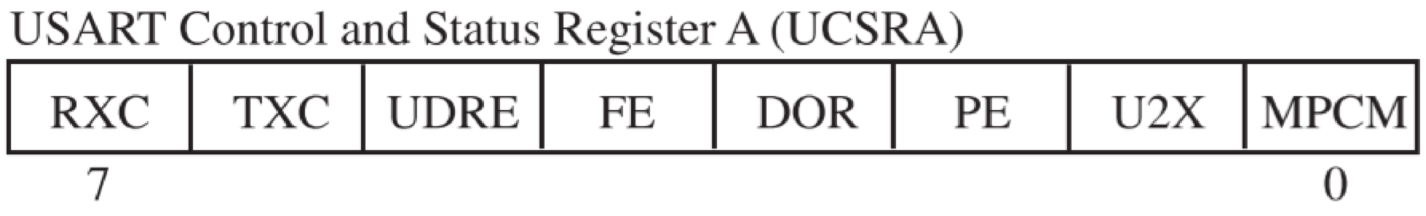
Bit Number	Register Bit	Register Bit Name	Function
15	URSEL	Register Select	Must be set to 0 to write to UBRRH, which shares the same location with UCSRC
14:12		Reversed Bits	Theses bits are reserved for future use
11:0	UBRR 11:0	USART Baud Rate Register	This is a 12-bit register which contains the USART baud rate

The following table contains the equations for calculating baud rate register setting

Operating Mode	Calculate Baud Rate	Calculate UBRR Value
Asynchronous Normal ($\mathrm{U2X} = 0$)	$\mathrm{BAUD} = \frac{f_{OSC}}{16(\mathrm{UBRR}+1)}$	$\mathrm{UBRR} = \frac{f_{OSC}}{16\mathrm{BAUD}} - 1$
Asynchronous Double ($\mathrm{U2X} = 1$)	$\mathrm{BAUD} = \frac{f_{OSC}}{8(\mathrm{UBRR}+1)}$	$\mathrm{UBRR} = \frac{f_{OSC}}{8\mathrm{BAUD}} - 1$
Synchronous Master	$\mathrm{BAUD} = \frac{f_{OSC}}{2(\mathrm{UBRR}+1)}$	$\mathrm{UBRR} = \frac{f_{OSC}}{2\mathrm{BAUD}} - 1$

- BAUD: Baud rate (in bits per second)
- f_{OSC}: System Oscillator clock frequency
- UBRR: Contents of the UBRRH and UBRRL Registers $[0, 2^{11} - 1]$

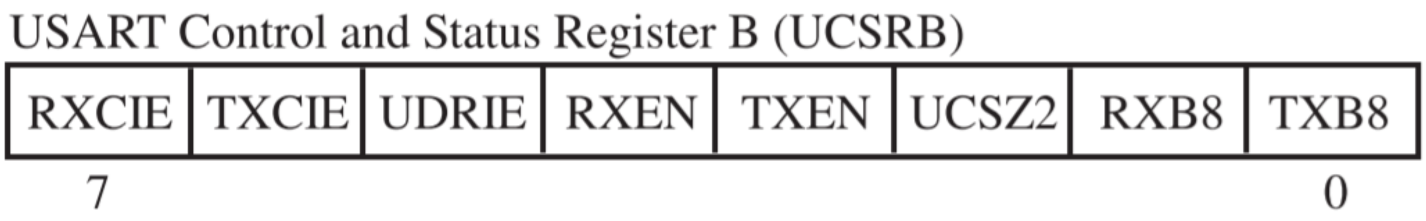
USART Control and Status Register A (UCSRA)



Bit Number	Register Bit	Register Bit Name	Function
7	RXC	USART Receive Complete	1 when receive buffer has unread data (Rx complete)
6	TXC	USART Transmit Complete	1 when no new data in transmit buffer (Tx complete)
5	UDRE	USART Data Register Empty	1 when USART data register is empty

Bit Number	Register Bit	Register Bit Name	Function
4	FE	Frame Error	1 when there is frame error
3	DOR	Data Over-Run	1 when there is data overrun
2	PE	Parity Error	1 when there is parity error
1	U2X	Double the USART Transmission Speed	1 to double the transmission speed
0	MPCM	Multi-processor Communication Mode	1 to enable multi-processor communication mode

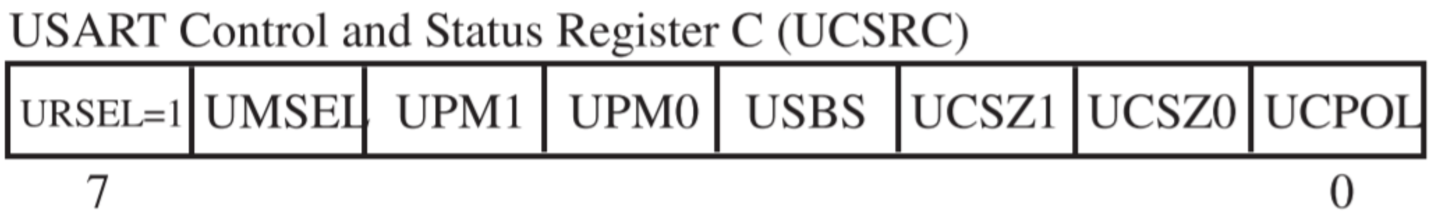
USART Control and Status Register B (UCSRB)



Bit Number	Register Bit	Register Bit Name	Function
7	RXCIE	USART Receive Complete Interrupt Enable	1 to enable RX Complete Interrupt, valid only if Global Interrupt Flag = 1 and RXC = 1
6	TXCIE	USART Transmit Complete Interrupt Enable	1 to enable TX Complete Interrupt, valid only if Global Interrupt Flag = 1 and TXC = 1
5	UDRIE	USART Data Register Empty	1 to enable USART Data Register Empty Interrupt
4	RXEN	Receiver Enable	1 to enable USART receiver
3	TXEN	Transmitter Enable	1 to enable USART transmitter
2	UCSZ2	Character Size	bit UCSZ2 to decide character size, combined with bits 2 and 1 in UCSRC
1	RXB8	Receive Data Bit 8	Rx extra data bit for 9-bit character size

Bit Number	Register Bit	Register Bit Name	Function
0	TXB8	Transmit Data Bit 8	Tx extra data bit for 9-bit character size

USART Control and Status Register C (UCSRC)


USART Control and Status Register C (UCSRC)

URSEL=1	UMSEL	UPM1	UPM0	USBS	UCSZ1	UCSZ0	UCPOL
7							0

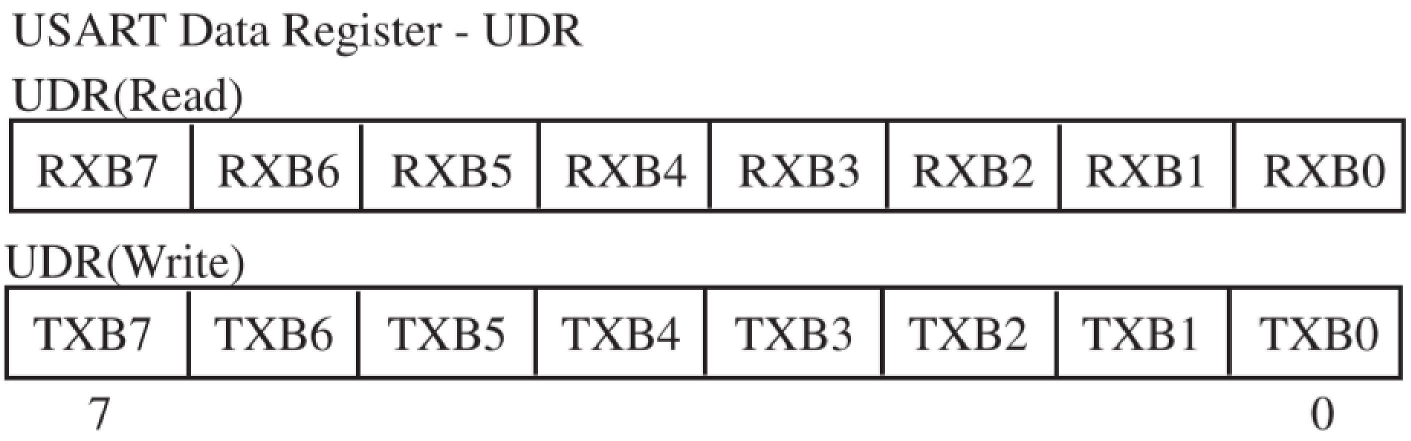
Bit Number	Register Bit	Register Bit Name	Function
7	URSEL	Register Select	Must be set to 1 to write to UCSRC, which shares with UBRRH
6	UMSEL	USART Mode Select	To select USART modes: 0 asynchronous, 1 synchronous
5:4	UPM1:0	Parity Mode	To select parity mode: 00 no parity, 10 even parity, 11 odd parity, 01 Reserved
3	USBS	Stop Bit Select	To select stop bit mode: 0->1 stop bit, 1->2 stop bits
2:1	UCSZ1:0	Character Size	Used with UCSZ2 in UCSRB to select character size
0	UCPOL	Clock Polarity	Used for synchronous mode only

Setting Character Size

UCSZ2	UCSZ1	UCSZ0	Character Size
0	0	0	5-bit
0	0	1	6-bit
0	1	0	7-bit
0	1	1	8-bit

UCSZ2	UCSZ1	UCSZ0	Character Size
1	0	0	Reserved
1	0	1	Reserved
1	1	0	Reserved
1	1	1	9-bit

USART I/O Dat Registers (UDR)



Register UDR is the buffer for characters sent received through the serial port

Sending Character

```
unsigned char data;
data = 'a';
UDR = data; // start sending character
```

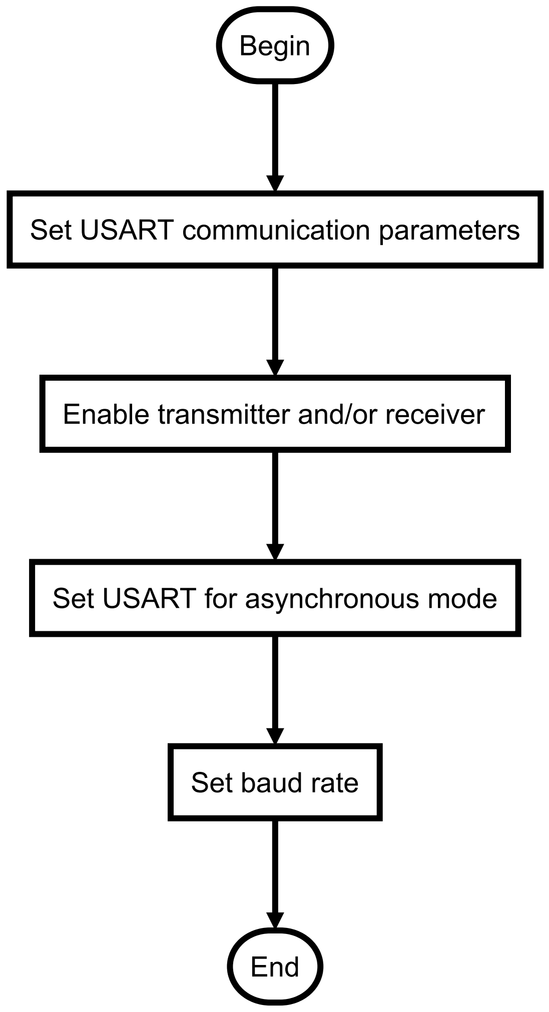
Receiving Character

```
unsigned char data;
data = UDR; // clear UDR
```

System Operation and Programming

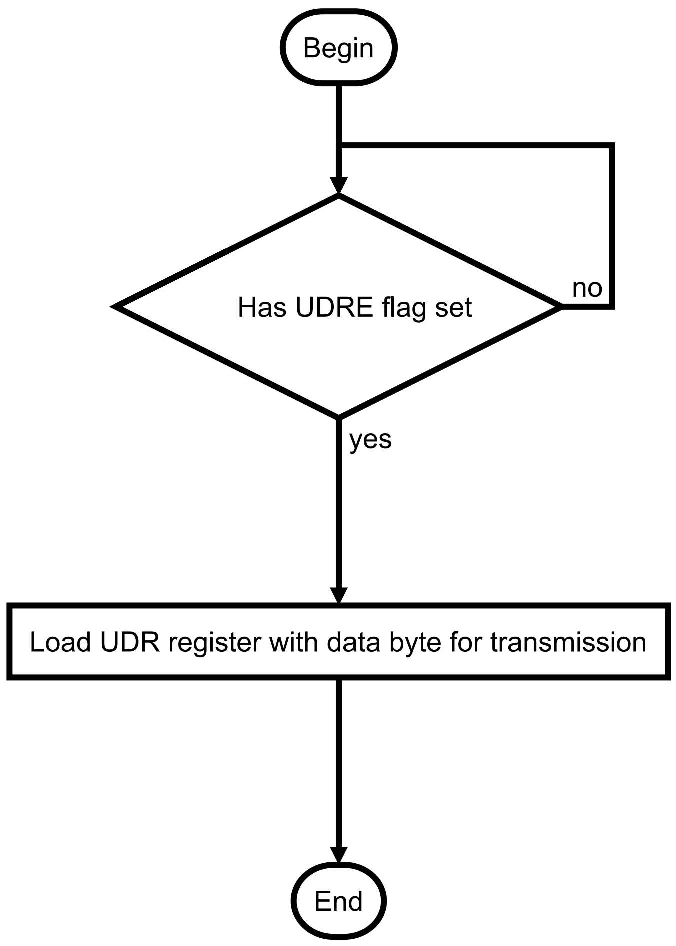
There are 3 main tasks in using the serial port

USART Initialization


Begin
Set USART communication parameters
Enable transmitter and/or receiver
Set USART for asynchronous mode
Set baud rate
End

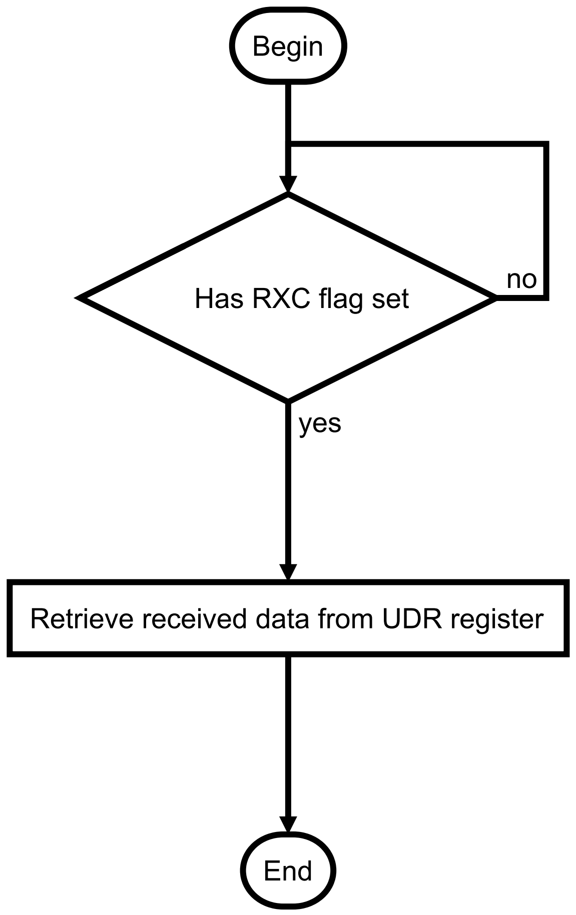
```
void USART_init(void){
    UCSRA = 0x00; // control register initialization
    UCSRB = 0x08; // enable transmitter
    UCSRC = 0x86; // async, no parity; 1 stop bit, 8 data bits

    UBRRH = 0x00;
    UBRRL = 0x40;
}
```

USART Transmission



```
void USART_transmit(unsigned char data){
        while((UCSRA & 0x20)==0x00){
                ;
        }

        UDR = data;
}
```

USART Reception

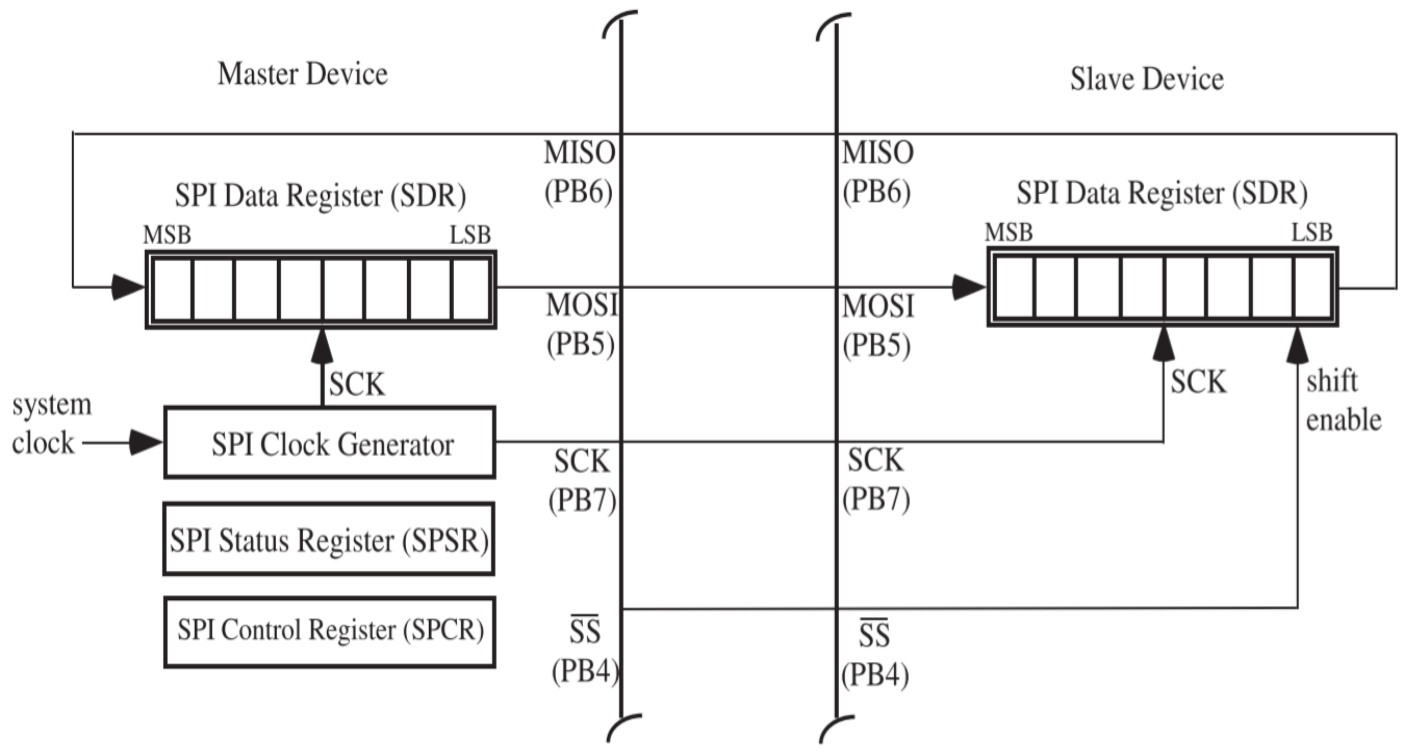


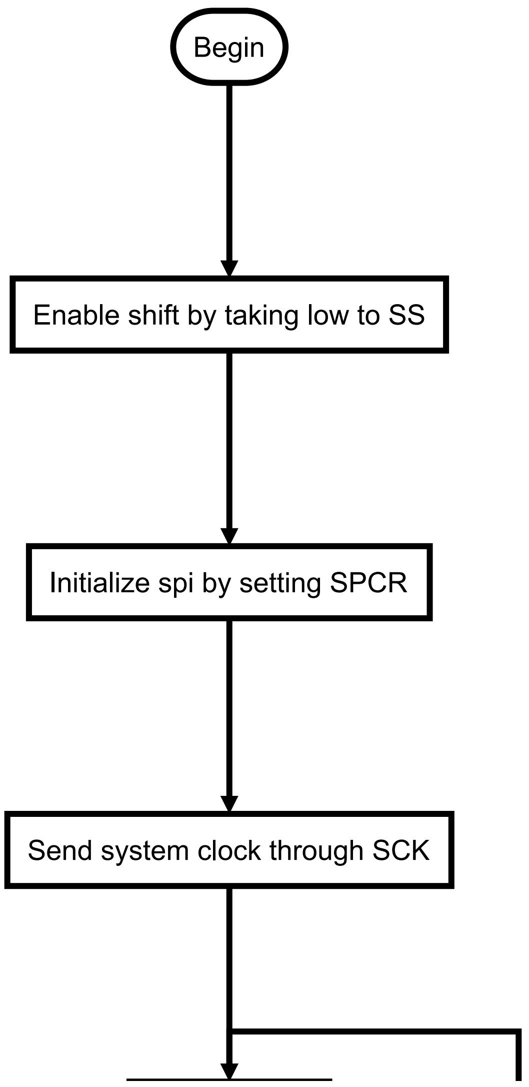
```c
unsigned char USART_receive(void){
        while((UCSRA & 0x80) == 0x00){
                ;
        }
        unsigned char data = UDR;
        return data;
}
```

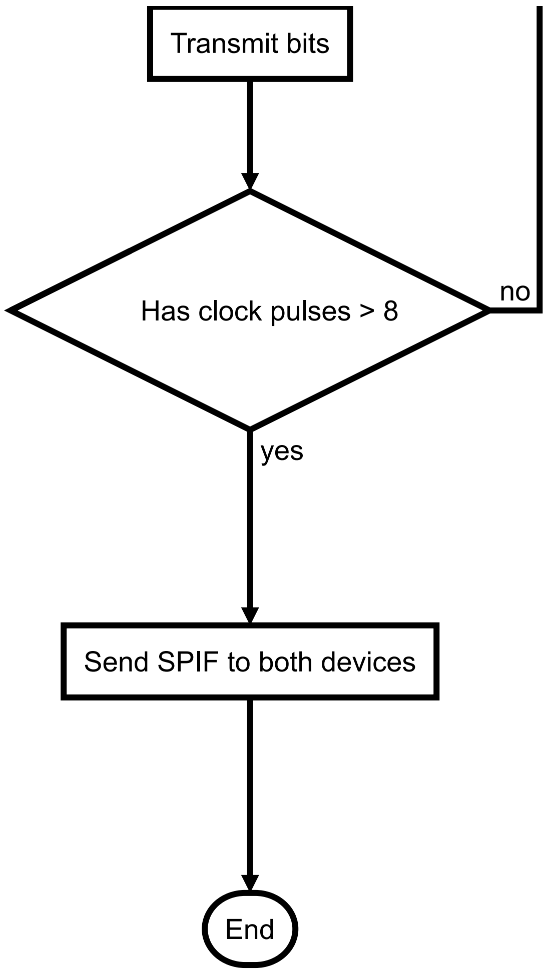
2-4 Serial Peripheral Interface

The serial peripheral interface allows **high-speed synchronous data transfer** between the ATmega16 and peripheral devices or between several AVR devices. And there are **3 wires** in SPI.

SPI Operation

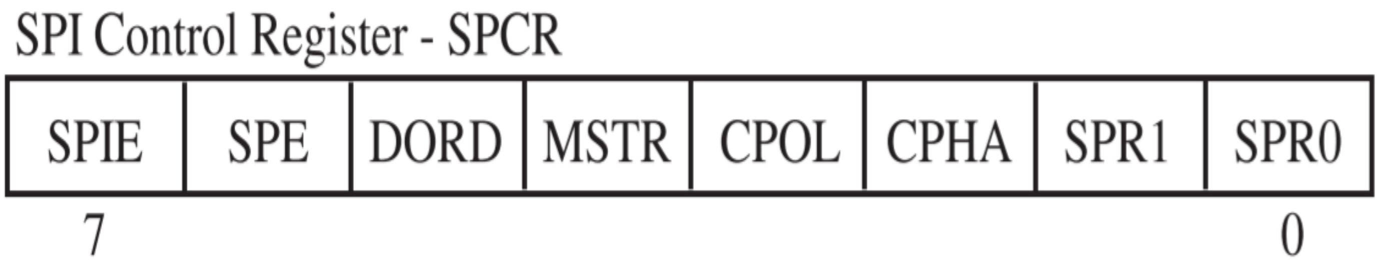

Master Device
Slave Device
MISO
(PB6)
MISO
(PB6)
SPI Data Register (SDR)
MSB
LSB
SPI Data Register (SDR)
MSB
LSB
MOSI
(PB5)
MOSI
(PB5)
SCK
SCK
shift
enable
system
clock
SPI Clock Generator
SCK
(PB7)
SCK
(PB7)
SPI Status Register (SPSR)
SPI Control Register (SPCR)
$\overline{SS}$
(PB4)
$\overline{SS}$
(PB4)


Begin
Enable shift by taking low to SS
Initialize spi by setting SPCR
Send system clock through SCK



SPI Registers

SPI Control Register (SPCR)



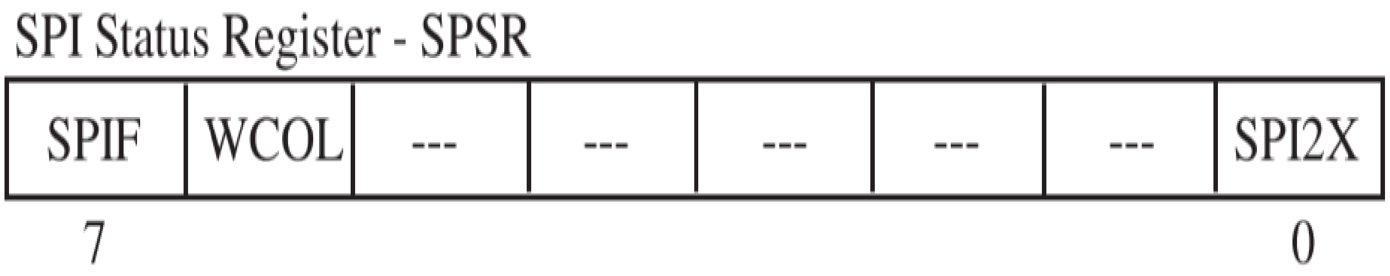
SPI Control Register - SPCR

SPIE	SPE	DORD	MSTR	CPOL	CPHA	SPR1	SPR0
7							0

Bit Number	Register Bit	Register Bit Name	Function
7	SPIE		
6	SPE	SPI Enable	1 to turn on the system and 0 to turn it off
5	DORD	Data Order	1 to send LSB first and 0 to send MSB first

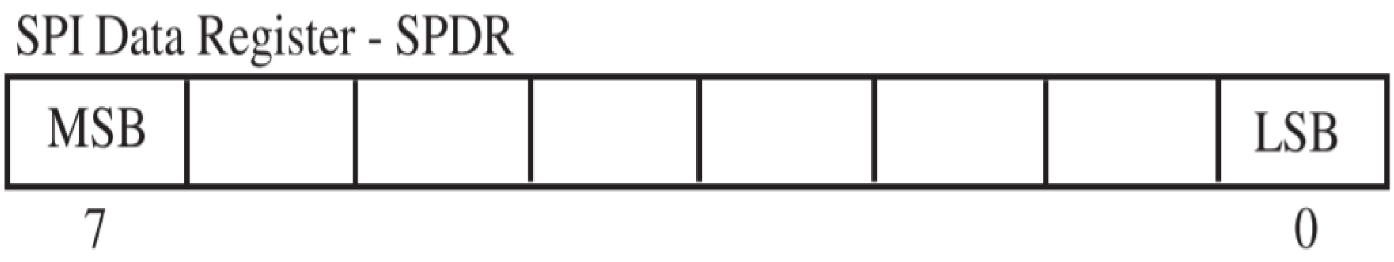
Bit Number	Register Bit	Register Bit Name	Function
4	MSTR	Master/Slave Select	1 for master and 0 for slave
3	CPOL	Clock Polarity	1 for idle logic high of SCK and 0 for idle logic low
2	CPHA	Clock Phase	if data will be sampled on leading (0) or trailing (1) edge of the SCK
1:0	SPR1:0	SPI Clock Rate Select	used to set the division factor

SPI Status Register (SPSR)



Bit Number	Register Bit	Register Bit Name	Function
7	SPIF	SPI Interrupt Flag	set when transmission finished
6	WCOL	Writing Collision	
5:1	Reserved		
0	SPI2X	Double SPI Speed	set the SCK frequency

SPI Data Register (SPDR)



Writing a data byte to the SPDR initiates SPI transmission

SCK Frequency

The SPR 1:0 bits and the SPI2X bit are used to set the division factor

SPI2X	SPR1	SPR0	SCK Frequency
0	0	0	$\frac{1}{4} f_{OSC}$
0	0	1	$\frac{1}{16} f_{OSC}$
0	1	0	$\frac{1}{64} f_{OSC}$
0	1	1	$\frac{1}{128} f_{OSC}$
1	0	0	$\frac{1}{2} f_{OSC}$
1	0	1	$\frac{1}{8} f_{OSC}$
1	1	0	$\frac{1}{32} f_{OSC}$
1	1	1	$\frac{1}{64} f_{OSC}$

Coding with SPI

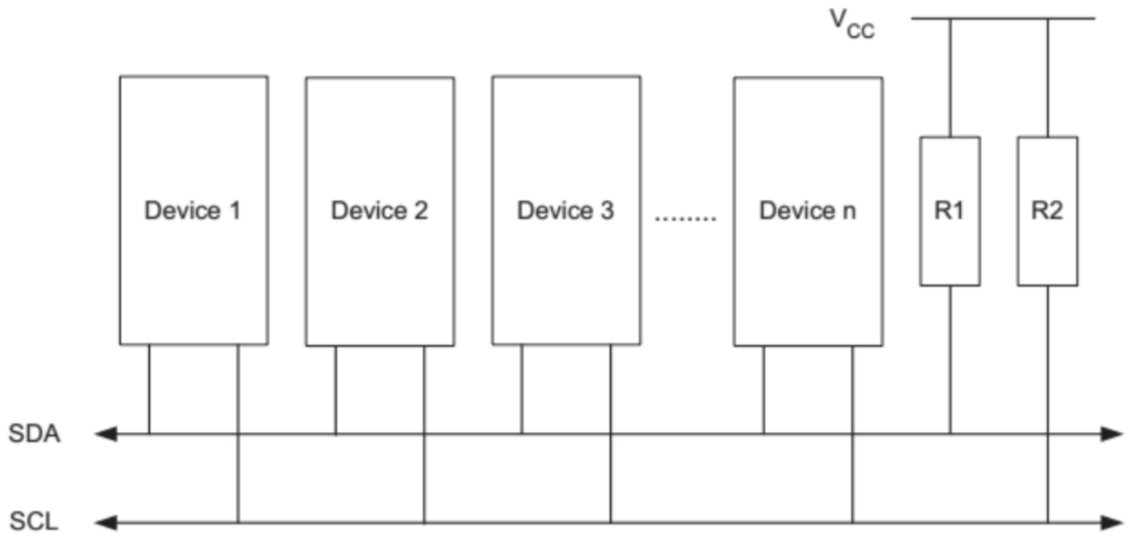
```
void SPI_init(unsigned char control){
        DDRB = 0xA0; // SCK(PB7), MOSI(PB5) for output, others to input
        SPCR = 0x53; // SPIE:0, SPE:1, DORD:0, MSTR:1, CPOL:0, CPHA:0, SPR:1, SPR0:1
}

void SPI_write(unsigned char byte){
        SPDR = byte;
        while(!(SPSR & 0x80)){
                ;
        }
}

unsigned char SPI_read(void){
        while(!(SPSR & 0x80)){
                ;
        }

        unsigned char data = SPDR;
        return data;
}
```

2-5 Two-Wire Serial Interface

The TWI subsystem allows the system designer to network a number of related devices together into a system using a **two-wire** interconnecting scheme.

The TWI allows a maximum of **128 devices** to be connected together. Each device has its own unique address and may both transmit and receive over the two-wire bus at frequencies up to **400 kHz**.

TWI Bus



The TWI protocol allows the systems designer to interconnect up to 128 different devices using only two bi-directional bus lines, one for clock (**SCL**) and one for data (**SCA**)

The only external hardware needed to implement the bus is as single pull-up resistor for each of the TWI bus lines.

Chapter 3 Analog to Digital Conversion

3-1 Analog to Digital Conversion Process

The goal of the ADC process is to accurately represent analog signals as digital signals. And there are three signal processing procedures: **sampling**, **quantization** and **encoding**.

Transferring

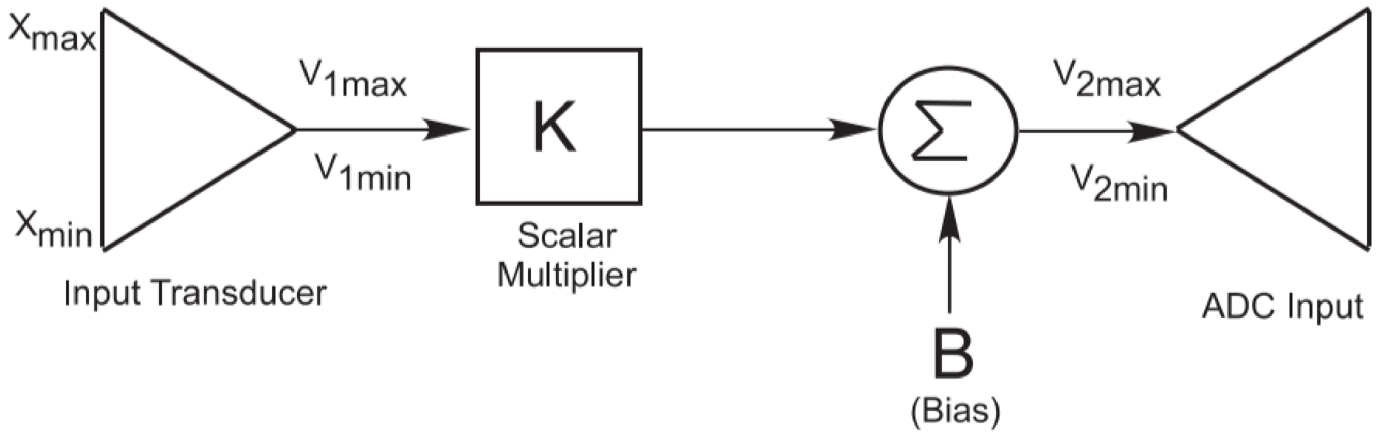
But before the ADC process takes place, the physical signal must be converted into an electrical signal with the help of the **transducer**

A **transducer** is an electrical and/or mechanical system that converts physical signals into electrical signals or electrical signals to physical signals.

Conditioning

In addition to transducers, we also need signal conditioning circuity before we apply the ADC/DAC process. The signal conditioning circuity is called the **transducer interface**.

The objective of the **transducer interface** circuit is to **scale and shift** the electrical signal range to map the **output of the input transducer** to the **input of the ADC**.

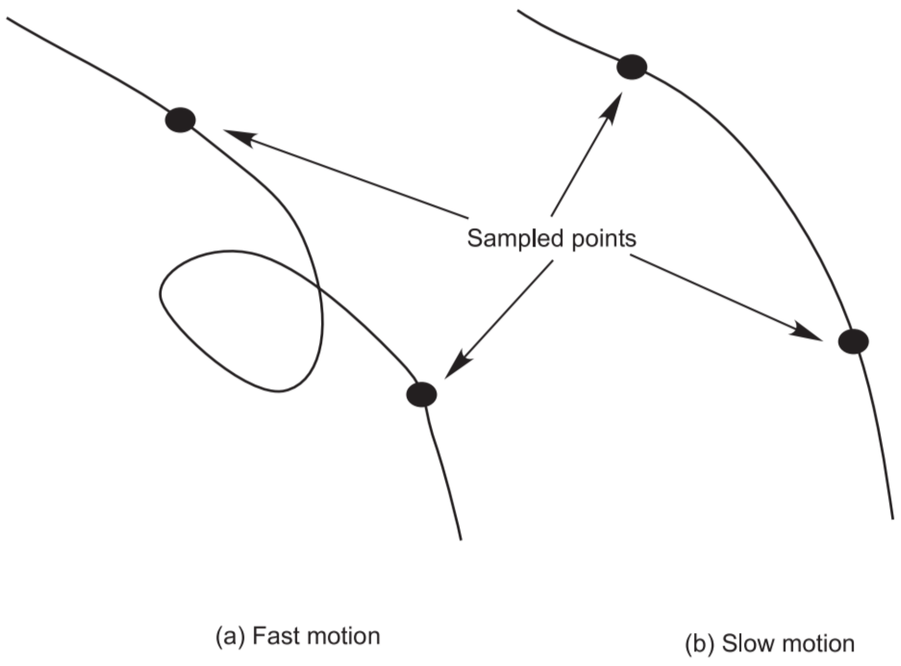


In general, the scaling and bias process may be described by two equations

$$\begin{cases} V_{2\ max} &= (V_{1\ max} \times K) + B \\ V_{2\ min} &= (V_{1\ min} \times K) + B \end{cases}$$

- $V_{1\ max}$: the maximum output voltage from the input transducer
- $V_{1\ min}$: the minimum output voltage from the input transducer
- $V_{2\ max}$: the maximum output voltage of the input voltage of ADC
- $V_{2\ min}$: the minimum output voltage of the input voltage of ADC

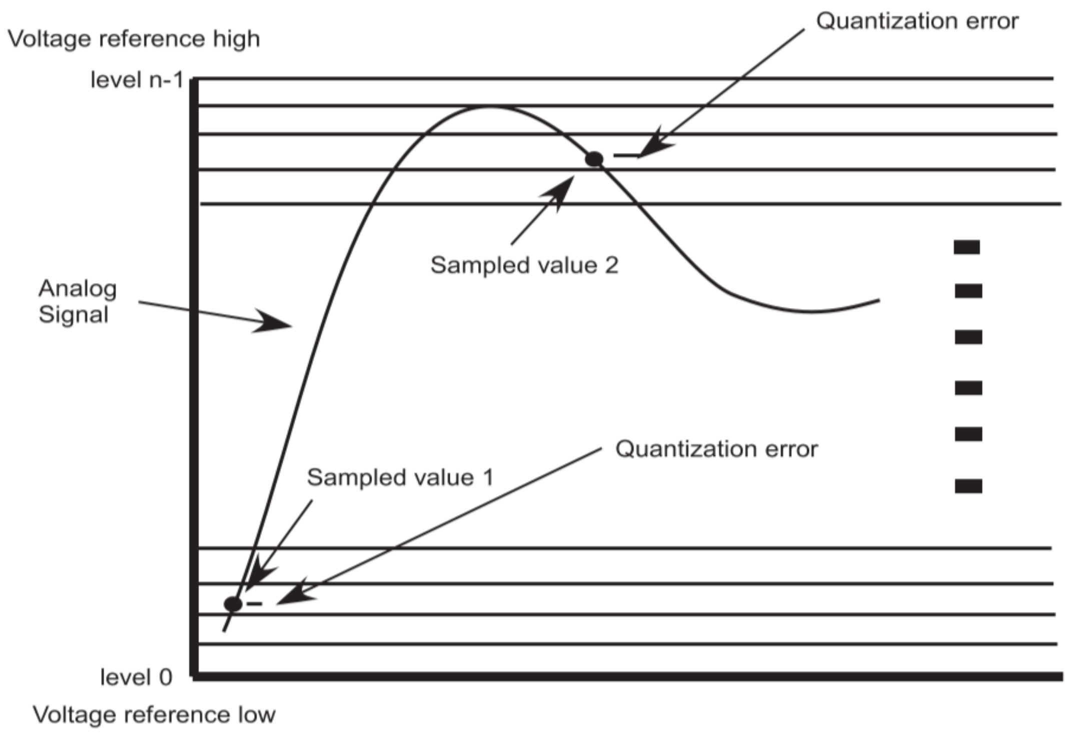
Sampling



The first step of the ADC process is the sampling of the analog signal. When selecting a converter, one must consider the type of physical signal that is being converted to properly ensure the sampling rate.

Using the proper sampling rate is the first step that determined whether an analog signal will be represented correctly in digital systems，which means to select an ADC that can handle a required conversion rate

Quantization



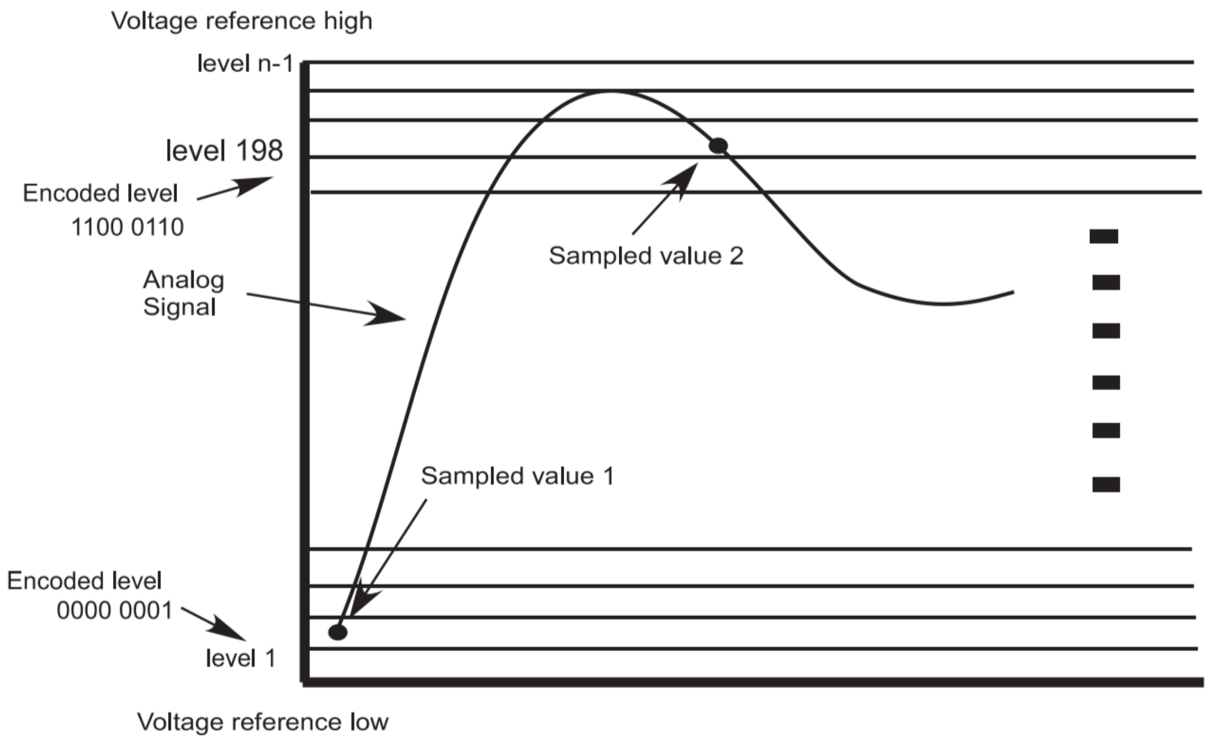
Once the analog signal has been sampled, the quantization process takes place. For this process, again one must decide how much quantization error can be allowed.

To determine the number of bits and its corresponding maximum quantization error, we use the following equation

$$\text{Resolution} = \frac{\text{range}}{2^b}$$

- b: the encoding bits

Encoding

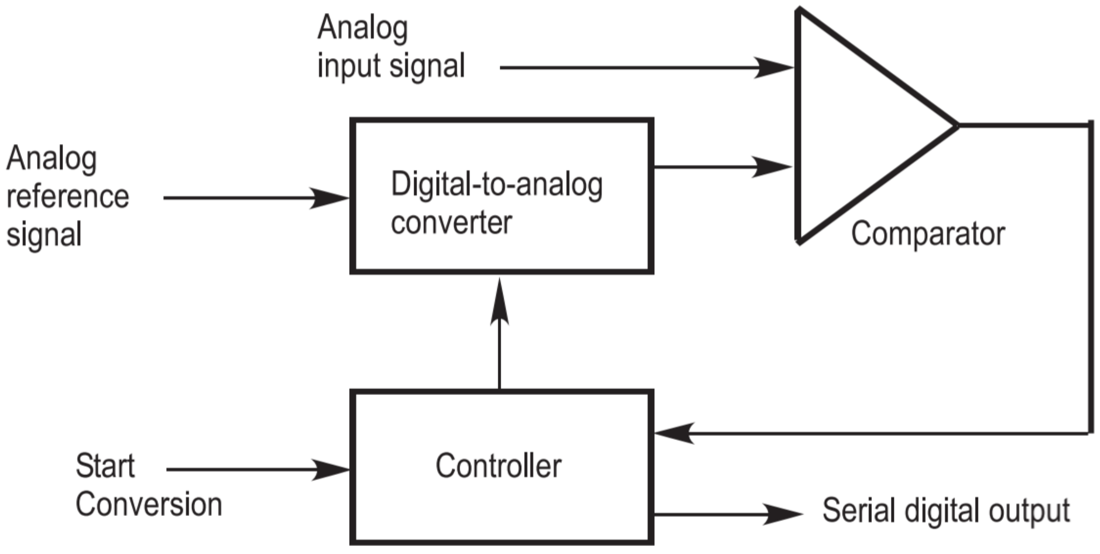


Once the quantization level has been determined, we can now encode it using the available bits.

3-2 ADC Conversion Technologies

There are numerous types of conversion process in ADC: the **successive approximation conversion**, **integration conversion**, **counter-based conversion** and **parallel conversion**

Successive Approximation

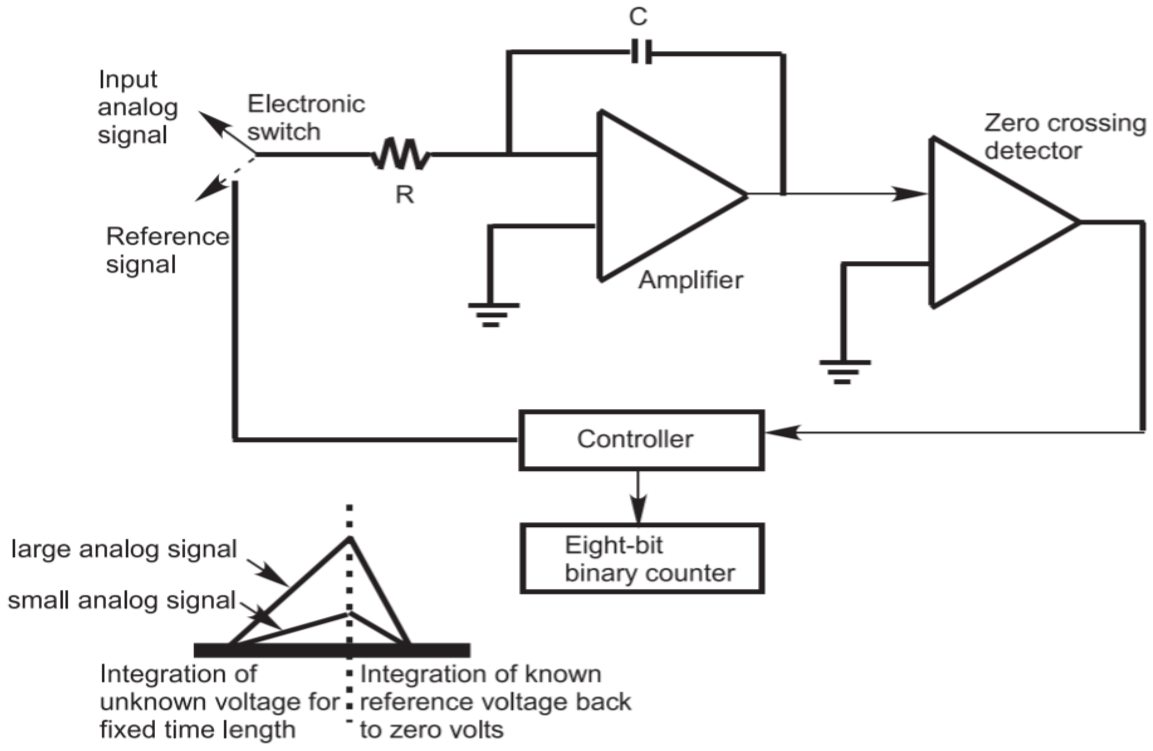


The successive approximation technique uses a DAC, a controller and a comparator to perform the ADC process.

1. Starting from MSB to LSB, the controller turns on each bit at a time and generates an analog signal
2. Using DAC, the analog signal is conversed to the analog signal
3. The comparator then compares the analog input signal and the "analog signal" and sends feedback to the controller
4. Based on the result of the comparison, the controller changes or leaves the current bit and turns on the next MSB

- advantage: the conversion time is uniform for any input
- disadvantage: the use of complex hardware for implementation

Integration

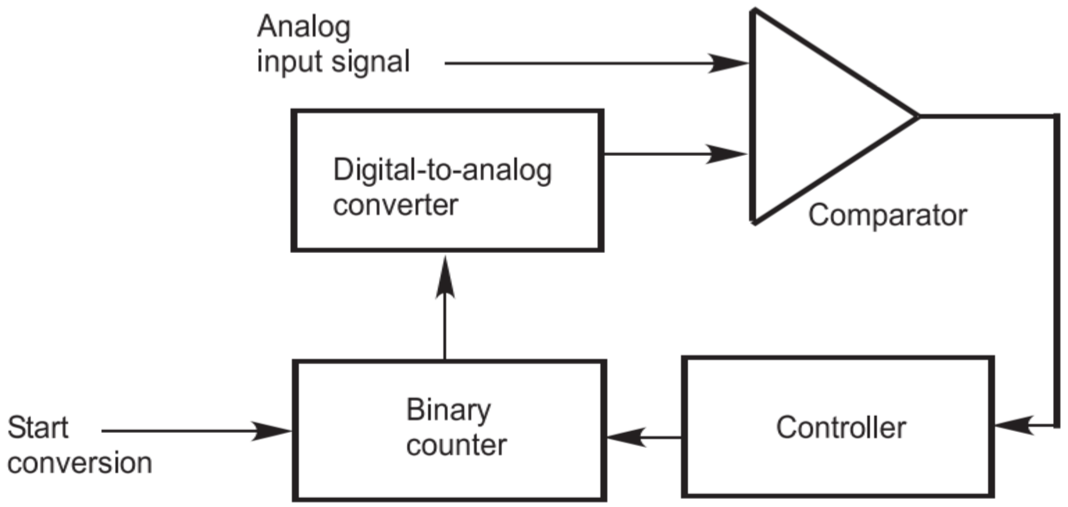


The integration technique uses an integrator, a comparator, and a controller to convert analog signals to digital signals

1. The analog signal is integrated over a fixed period
2. The fixed reference signal is also integrated over time and compared with the input analog signal
3. When the two integrated values equal, the measured time of the fixed reference signal is converted to a digital encoded value.

- disadvantage: the varying time for the conversion process

Counter-Based Conversion

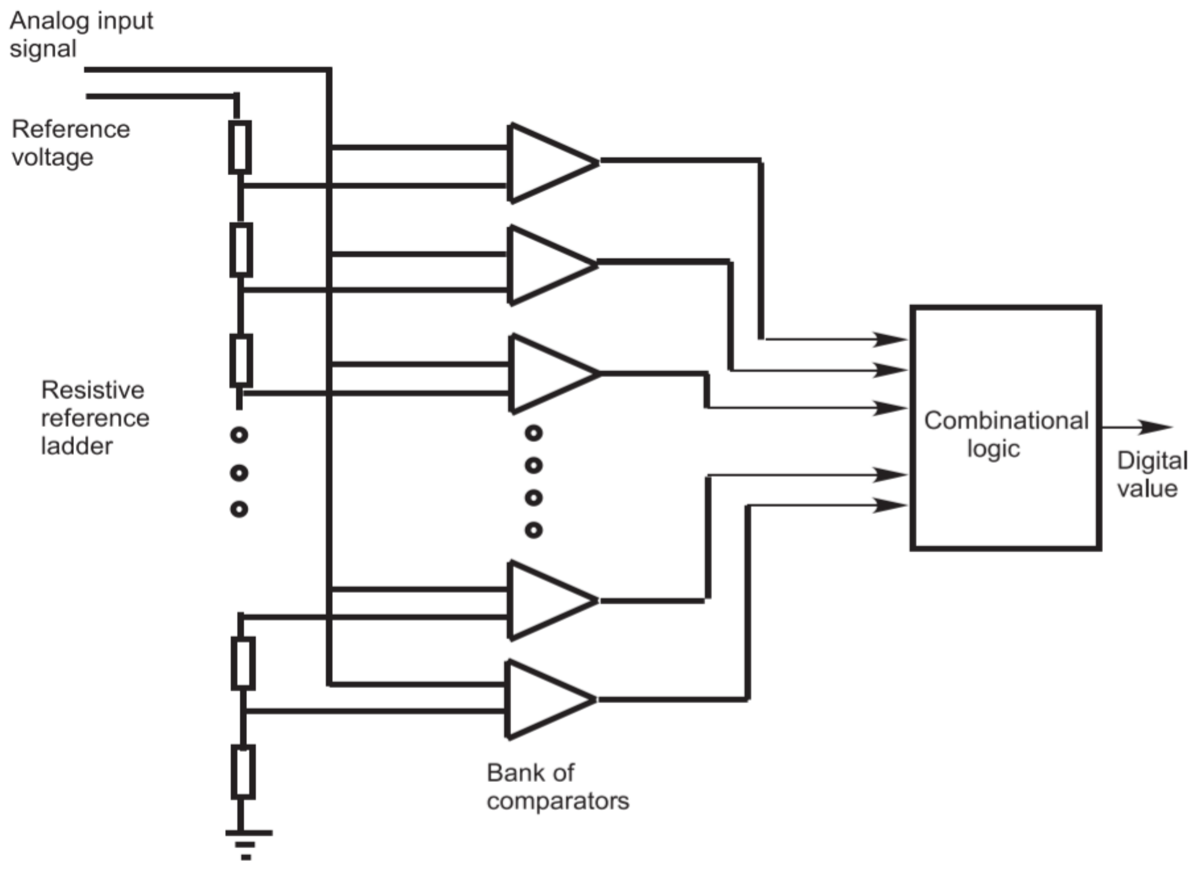


The third technique to convert an analog signal to a digital signal is the counter-based conversion. This conversion is performed with the help of a counter, a DAC, and a comparator.

1. The counter starts at 0 and counts up
2. As the counter counts up, the corresponding value is converted to an analog value and compared with an input analog signal
3. As long as the input analog signal is greater than the signal generated by the DAC, the counter counts up and the process continues
4. When the comparator detects that the signal from the DAC is greater than the input analog signal, the counter value is then converted to a digital value representing the sampled analog signal

- disadvantage: the varying time for the conversion process

Parallel Conversion



A parallel converter uses a large number of comparators and circuity to simultaneously measure the input signals and convert it to a digital value

- advantage: the quickest conversion time
- disadvantage: the cost involved in building the circuity

3-3 ATMEL ATmega16 ADC System

ATmega16 is equipped with a flexible and powerful ADC system, which has the following features

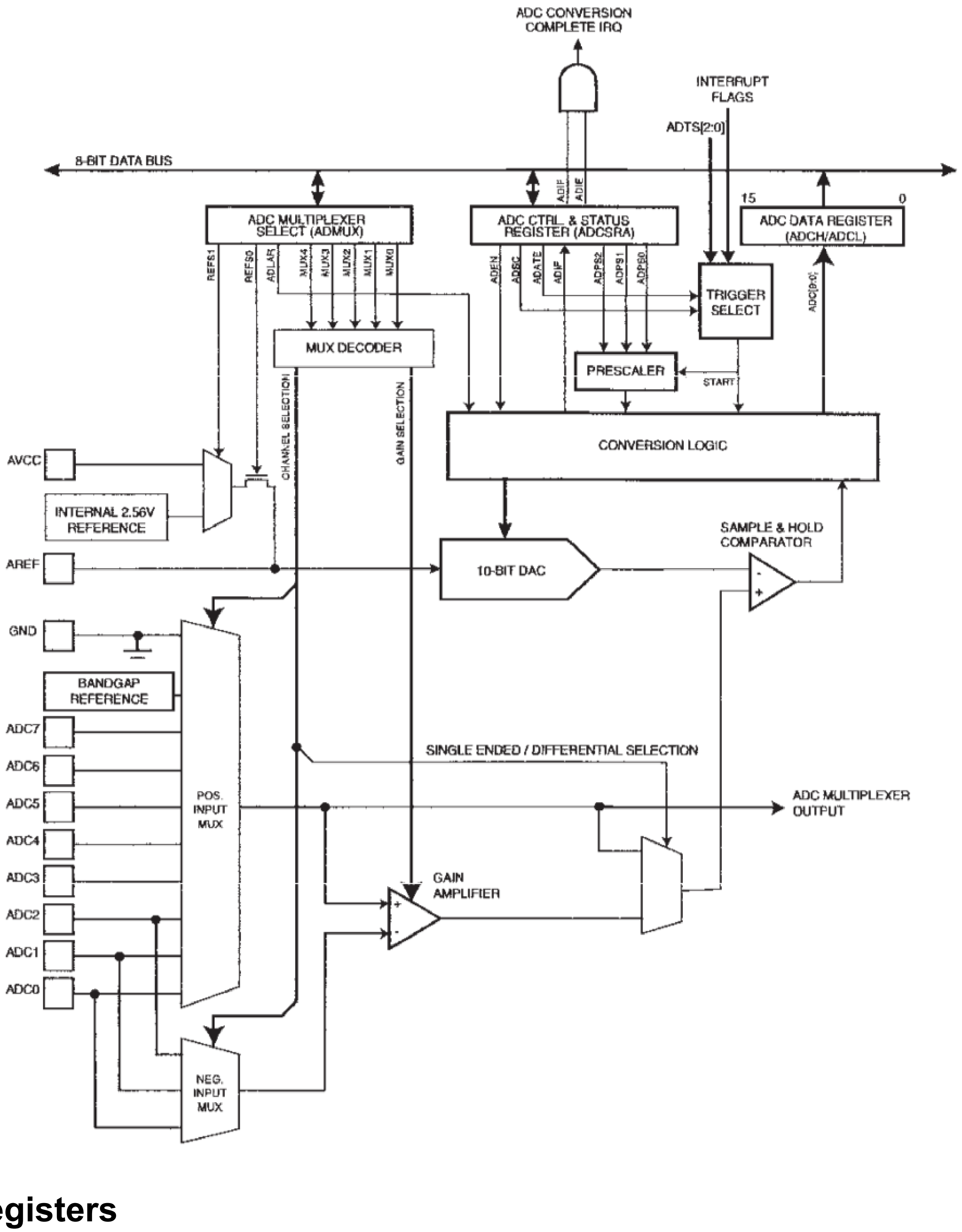
- 10 bit resolution
- ± 2 LSB absolute accuracy
- 13 ADC clock rate cycle conversion time
- 8 multiplexed single-ended input channels
- selectable right or left result justification
- 0 to V_{cc} ADC input voltage range

where the resolution is

$$\text{resolution} = (V_{RH} - V_{RL})/2^b$$

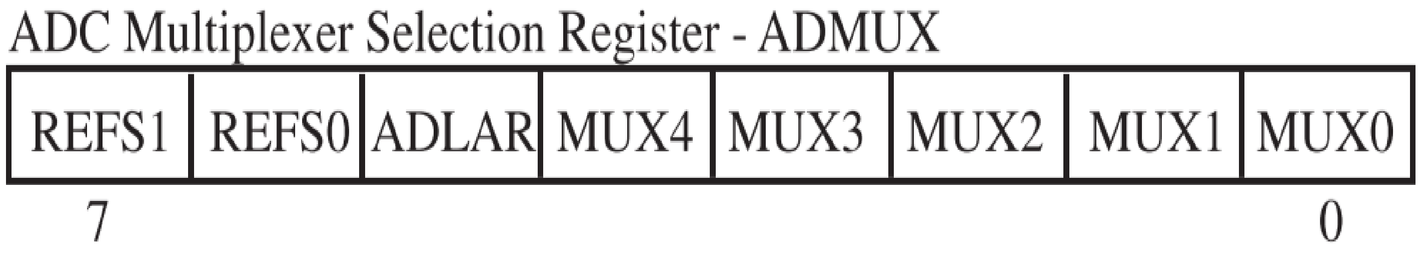
- V_{RH}: ADC high reference voltage

- V_{RL}: ADC low reference voltage



Registers

ADC Multiplexer Selection Register (ADMUX)


ADC Multiplexer Selection Register - ADMUX

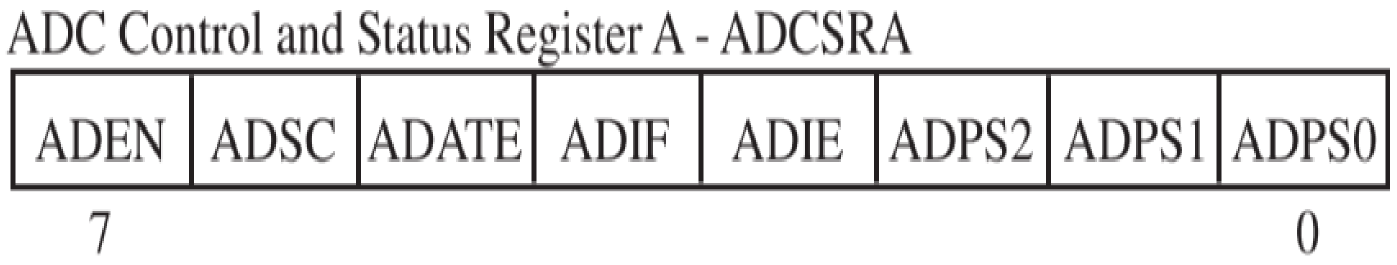
REFS1	REFS0	ADLAR	MUX4	MUX3	MUX2	MUX1	MUX0
7							0

Bit Number	Register Bit	Register Bit Name	Function
7:6	REFS1:0	Reference Voltage Source	Determine the reference voltage source for the ADC system
5	ADLAR	ADC Left Adjust Result	1 for left justification and 0 for right one
4:0	MUX 4:0	ADC Multiplexer Selection Register	Select the analog input for conversion

The bits of REFS may be set to the following values

- REFS[1:0]=00: AREF used for ADC voltage reference
- REFS[1:0]=01: AVCC with external capacitor at the AREF pin
- REFS[1:0]=10: reversed
- REFS[1:0]=11: internal 2.56V DC voltage reference with an external capacitor at the AREF pin

ADC Control and Status Register A (ADCSRA)


ADC Control and Status Register A - ADCSRA

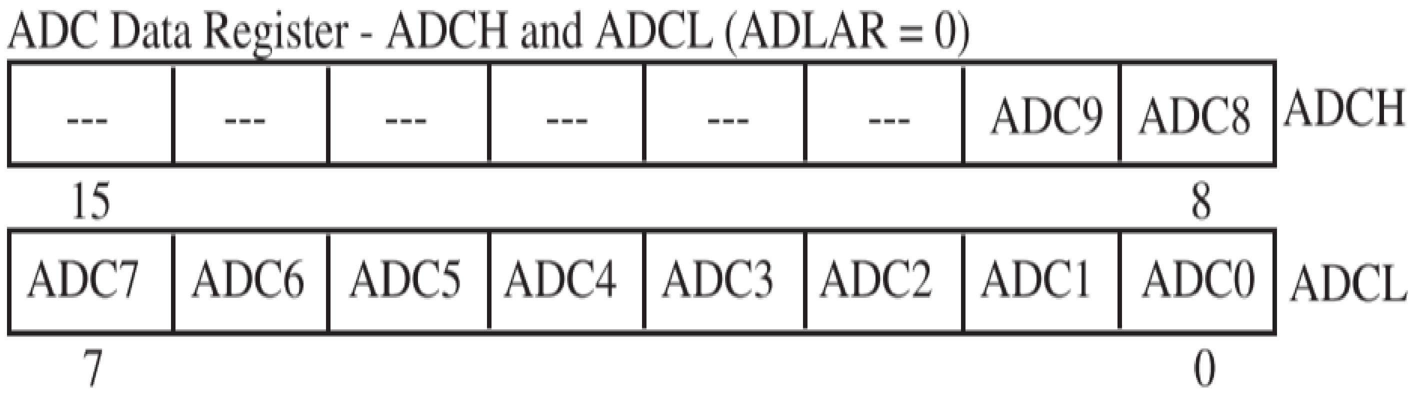
ADEN	ADSC	ADATE	ADIF	ADIE	ADPS2	ADPS1	ADPS0
7							0

Bit Number	Register Bit	Register Bit Name	Function
7	ADEN	ADC Enable	Enable/Disable the ADC system by setting 1/0
6	ADSC	ADC Start Conversion	Initiate ADC by setting to 1

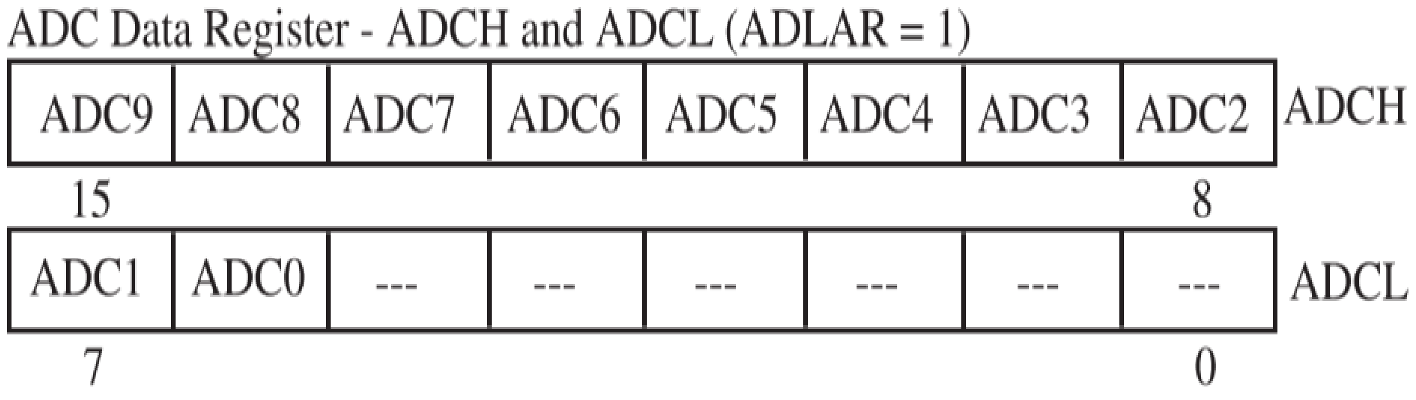
Bit Number	Register Bit	Register Bit Name	Function
5	ADATE	ADC Auto Trigger Enable	Set 1 to enable auto triggering in ADC
4	ADIF	ADC Interrupt Flag	Set to 1 when the ADC is complete
3	ADIE	ADC Interrupt Enable	Set to 1 to enable the interrupt of the ADC
2:0	ADPS2:0	ADC Prescaler Select	Use to set the ADC clock frequency

- ADPS[2:0]=000: devision factor 2
- ADPS[2:0]=001: devision factor 2
- ADPS[2:0]=010: devision factor 4
- ADPS[2:0]=011: devision factor 8
- ADPS[2:0]=100: devision factor 16
- ADPS[2:0]=101: devision factor 32
- ADPS[2:0]=110: devision factor 64
- ADPS[2:0]=111: devision factor 128

ADC Data Register (ADCH and ADCL)


ADC Data Register - ADCH and ADCL (ADLAR = 0)

---	---	---	---	---	---	ADC9	ADC8	ADCH
15							8	
ADC7	ADC6	ADC5	ADC4	ADC3	ADC2	ADC1	ADC0	ADCL
7							0	


ADC Data Register - ADCH and ADCL (ADLAR = 1)

ADC9	ADC8	ADC7	ADC6	ADC5	ADC4	ADC3	ADC2	ADCH
15							8	
ADC1	ADC0	---	---	---	---	---	---	ADCL
7							0	

3-4 Programming the ADC

Initiate ADC

```
void InitADC(void){
    ADMUX = 0x00;
    ADCSRA = 0xC3; // 0b 1100 0011

    while(!(ADCSRA & 0x10)) // check is conversion is ready
        ;

    ADCSRA |= 0x10; // clear the conversion ready flag
}
```

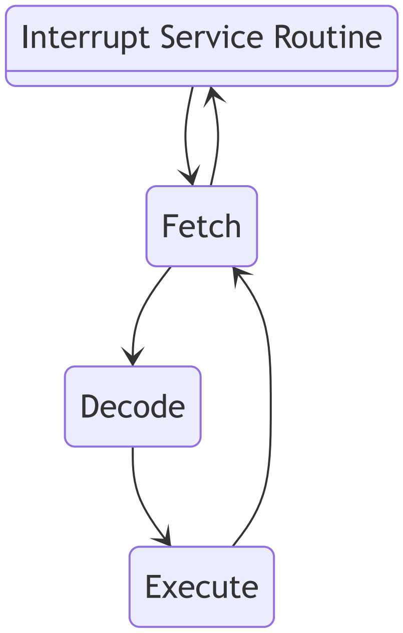
Read ADC

```
unsigned int ReadADC(unsigned char channel){
    unsigned int binary_weighted_voltage
    unsigned int binary_weighted_voltage_low;
    unsigned int binary_weighted_voltage_high;

    ADMUX = channel;
    ADCSRA |= 0x43; // 0b 0100 0011

    while(!(ADCSRA & 0x10))
        ;

    ADCSRA |= 0x10;

    binary_weighted_voltage_low = ADCL;
    binary_weighted_voltage_high = ((unsigned int)(ADCH << 8));

    binary_weighted_voltage = binary_weighted_voltage_low | binary_weighted_voltage_high;

    return binary_weighted_voltage;
}
```

Chapter 4 Interrupt Subsystem

4-1 Interrupt Theory

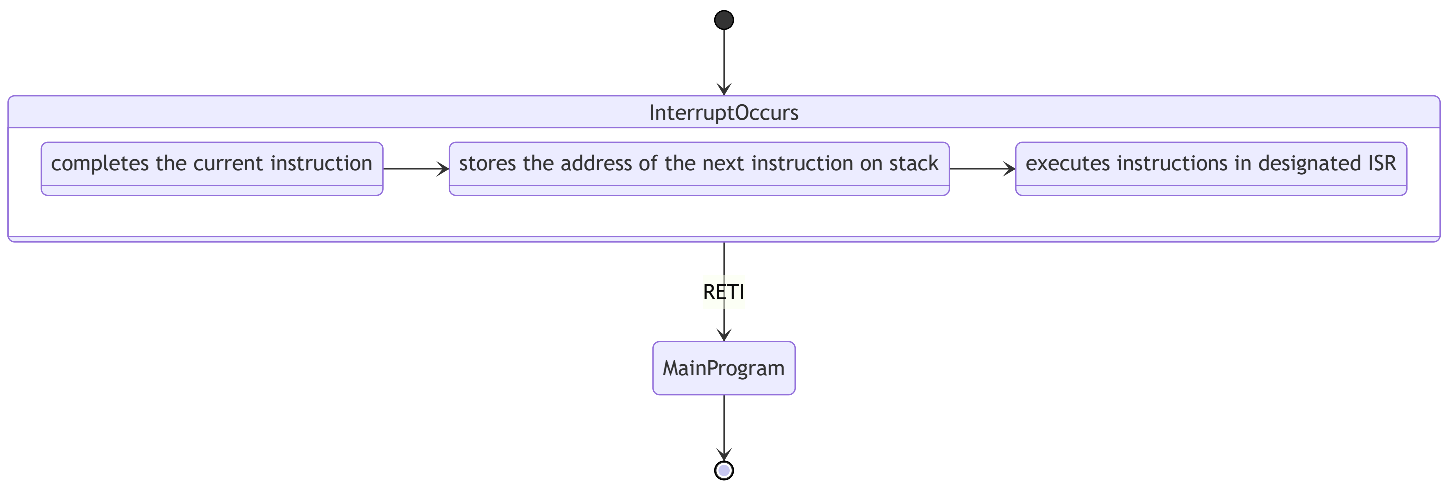
A microcontroller normally executes instructions in an orderly **fetch-decode-execute** sequence, but it must be equipped to handle unscheduled, high-priority events thant might occur inside or outside. Therefore, a microcontroller requires an interrupt system



4-2 ATmega16 Interrupt System

The ATmega16 is equipped 21 interrupt sources. **Three** originate from external interrupt sources, the remaining **eighteen** interrupts interrupts onboard.

Vector No.	Program Address[2]	Source	Interrupt Definition
1	\$000[1]	RESET	External Pin, Power-on Reset, Brown-out Reset, Watchdog Reset, and JTAG AVR Reset
2	\$002	INT0	External Interrupt Request 0
3	\$004	INT1	External Interrupt Request 1
4	\$006	TIMER2 COMP	Timer/Counter2 Compare Match
5	\$008	TIMER2 OVF	Timer/Counter2 Overflow
6	\$00A	TIMER1 CAPT	Timer/Counter1 Capture Event
7	\$00C	TIMER1 COMPA	Timer/Counter1 Compare Match A
8	\$00E	TIMER1 COMPB	Timer/Counter1 Compare Match B
9	\$010	TIMER1 OVF	Timer/Counter1 Overflow
10	\$012	TIMER0 OVF	Timer/Counter0 Overflow
11	\$014	SPI, STC	Serial Transfer Complete
12	\$016	USART, RXC	USART, Rx Complete
13	\$018	USART, UDRE	USART Data Register Empty
14	\$01A	USART, TXC	USART, Tx Complete
15	\$01C	ADC	ADC Conversion Complete
16	\$01E	EE_RDY	EEPROM Ready
17	\$020	ANA_COMP	Analog Comparator
18	\$022	TWI	Two-wire Serial Interface
19	\$024	INT2	External Interrupt Request 2
20	\$026	TIMER0 COMP	Timer/Counter0 Compare Match
21	\$028	SPM_RDY	Store Program Memory Ready


InterruptOccurs
completes the current instruction
stores the address of the next instruction on stack
executes instructions in designated ISR
RETI
MainProgram

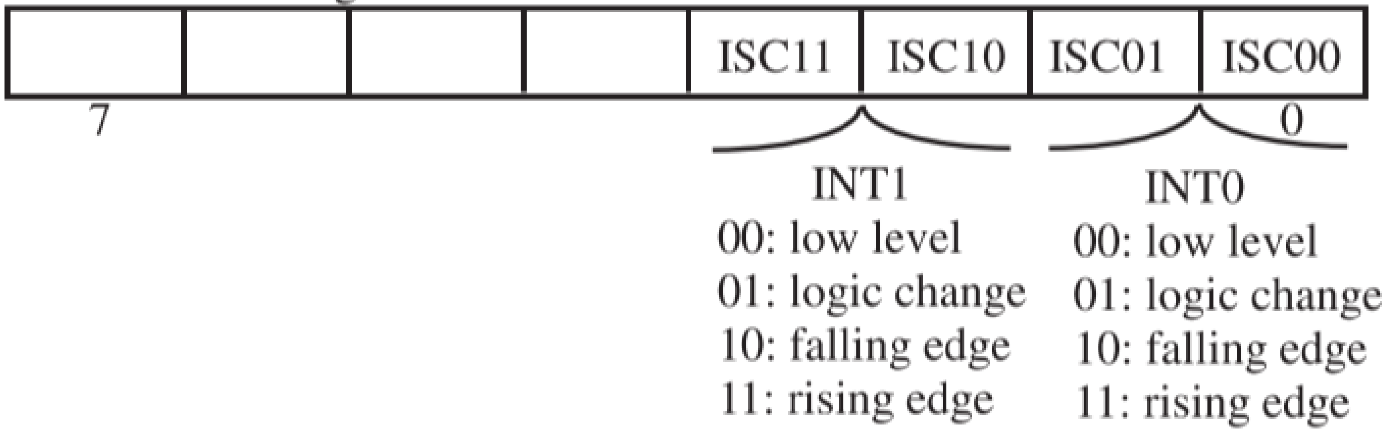
- ISR: interrupt service routine
- RETI: return from interrupt instruction

4-3 Programming An Interrupt

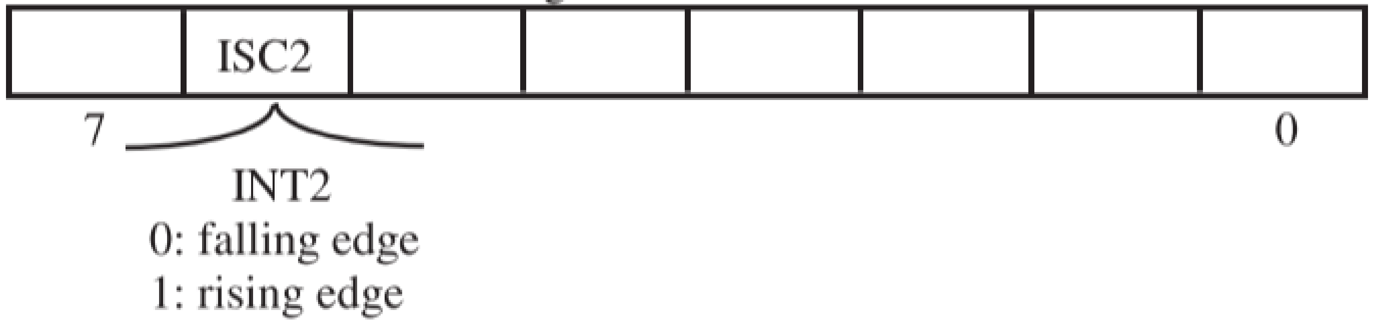
- Ensure the ISR for a specific interrupt is tied to the correct interrupt vector address, which points to the starting address of the ISR
- Ensure the interrupt system has been globally enabled, which is accomplished with the assembly language instruction SEI
- Ensure the specific interrupt subsystem has been locally enabled
- Ensure the registers associated with the specific interrupt have been configured correctly

External Interrupts

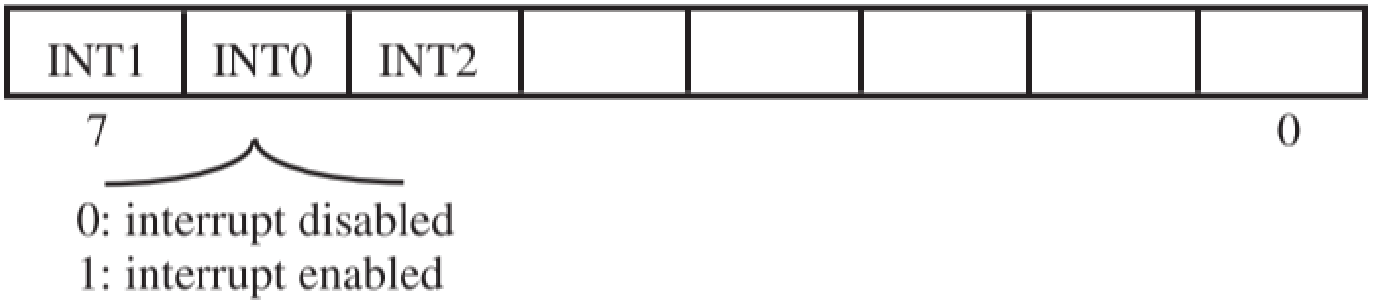
MCU Control Register - MCUCR



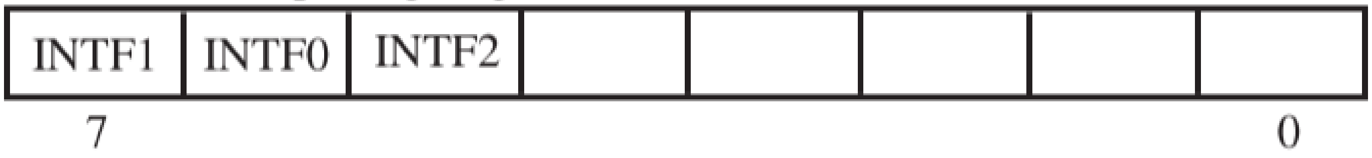
MCU Control and Status Register - MCUCSR



General Interrupt Control Register - GICR



General Interrupt Flag Register - GIFR



Notes:
- INTFx flag sets when corresponding interrupt occurs.
- INTFx flag reset by executing ISR or writing logic one to flag.

```
#pragma interrupt_handler int0_ISR:2 // interrupt handler definition

void int0_Init(void);
void int0_ISR(void);

void int0_Init(void){
    DDRD = 0xFB;    // Set PD2 as input
    PORTD &= ~0x04; // Disable pull-up resistor of PD2

    GICR = 0x40;    // Enable INT0
    MCUCR = 0x03;   // Set for rising edge

    asm("SEI");     // Enable global interrupt
}

void ISR(INT0_vect){
    /**
     * Insert interrupt specific actions here
     */
}
```

Internal Interrupts

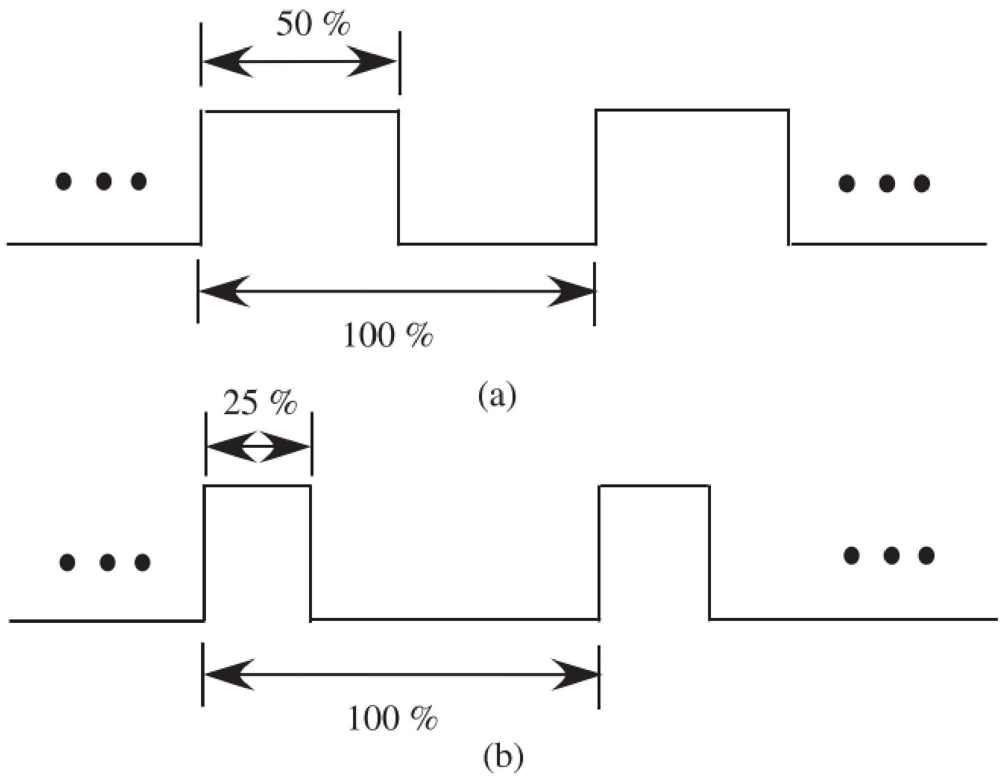
```c
#pragma interrupt_handler timer0_interrupt_isr:10

typedef unsigned char u8;
typedef unsigned int u16;

void delay(u16 number_of_interrupts);
void timer0_Init(void);

u16 input_delay;

void timer0_Init(void){
    TCCR0 = 0x04; // divide timer0 timebase by 256
    TIMSK = 0x01; // enable timer0 overflow interrupt

    asm("SEI");
}

void delay(u16 number_of_interrupts){
    TCNT = 0x00;     // reset timer0
    input_delay = 0; // reset timer0 overflow counter

    while(input_delay <=number_of_interrupts)
        ;
}

void timer0_interrupt_isr(void){
    input_delay++;
}
```

Chapter 5 Timing Subsystem

5-1 Timing-Related Terminology

duty Cycle

To control the direction and sometimes the speed of a motor, a **periodic pulse** with a **changing duty cycle** over time is used.



- (a): the periodic signal with 50% duty cycle
- (b): the periodic signal with 25% duty cycle

5-2 Timing System Overview

The very heart of the timing system is the crystal time base, which is used to generate a baseline clock signal for the microcontroller.

For a timer system, the system clock is used to update the contents of a special register which is called a **free-running counter**.

The job of a free-running counter is to count each time it sees a **rising/falling edge** of a clock signal, where other timer-related units reference it to perform I/O time-related activities: measurements, capture of timing events and generation of time-related signals

Input Time-Related Activities

All microcontrollers typically have timer hardware components, based on a free-running counter to capture external event times, that detect signal logic changes on one or input pins.

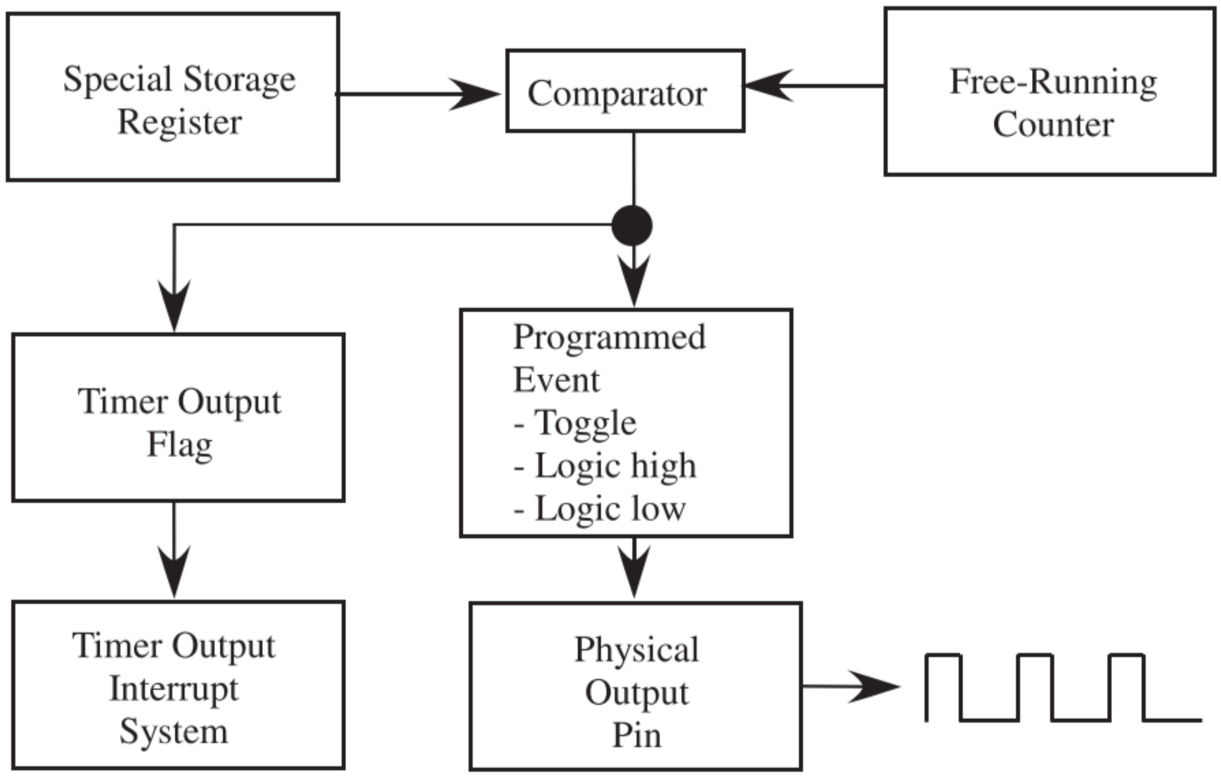
We can use such ability to measure the **period of an incoming signal**, the **width of a pulse** and the **time of a signal logic change**.

Output Timer Functions

The microcontroller uses a comparator to check the value of the free-running counter for a match with the contents of another special-purpose register where a programmer stores a specified time in terms of free-running counter value.

The checking process is executed at each clock cycle, and when a match occurs, the corresponding hardware system induces a programmed logic change on a programmed output port pin.

Using such capability, one can generate a simple logic change at designated time incident or a PWM signal to control DC motors



5-3 Applications

Input Capture

- an input signal is connected to pin, called input capture, of the timer
- an interrupt triggered when there's a change in **interrupt capture pin**
- when a preset event occurs on this pin, the current timer value is stored in a register

Output Compare

- a timer usually has a pin which is called output compare
- the output compare could be used to generate time critical signals for external devices

- when the timer reaches a preset value, the output compare pin can be automatically changed to logic 0 or logic 1
- output compare allows custom processing to be done when the timer reaches a preset target value

Counting Event

- the timer could be used to count external events
- the polling technique or the interrupt technique could be used to count events

Pulse Width Modulation

- the timer could be used to generate an PWM signal with the desired duty cycle
- PWM signal is the most common way to control industrial devices

5-4 The ATmega 16 Timers

The ATMEL ATmega16 is equipped with a flexible and powerful three-channel timing Timer 0, Timer 1 and Timer 2.

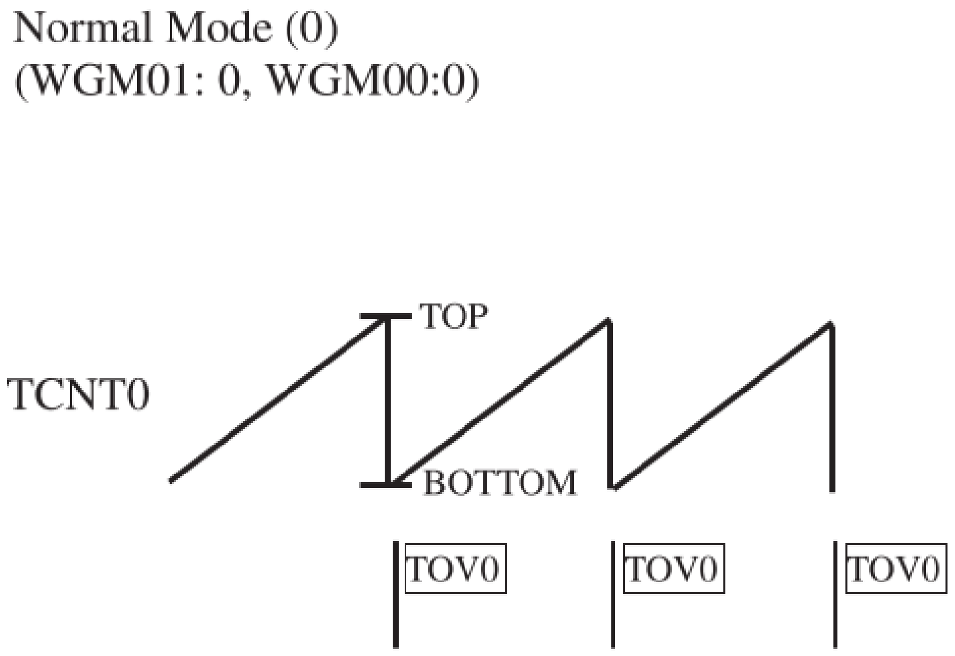
Both timer 0 and timer 2 are 8-bit timers, and the timer 1 is the 16-bit timer. Each timer is equipped with a prescaler, which is used to subdivide the main controller clock source down to the clock source for the timing system.

Each timing system has the capability to generate PWM signals, signal with a specific frequency, counting events and generate a precision signal. And the timer 1 is equipped with the input capture feature.

All timing could be configured into four modes: Normal, Clear TImer on Compare Match, Fast PWM.

Basic Operation Modes

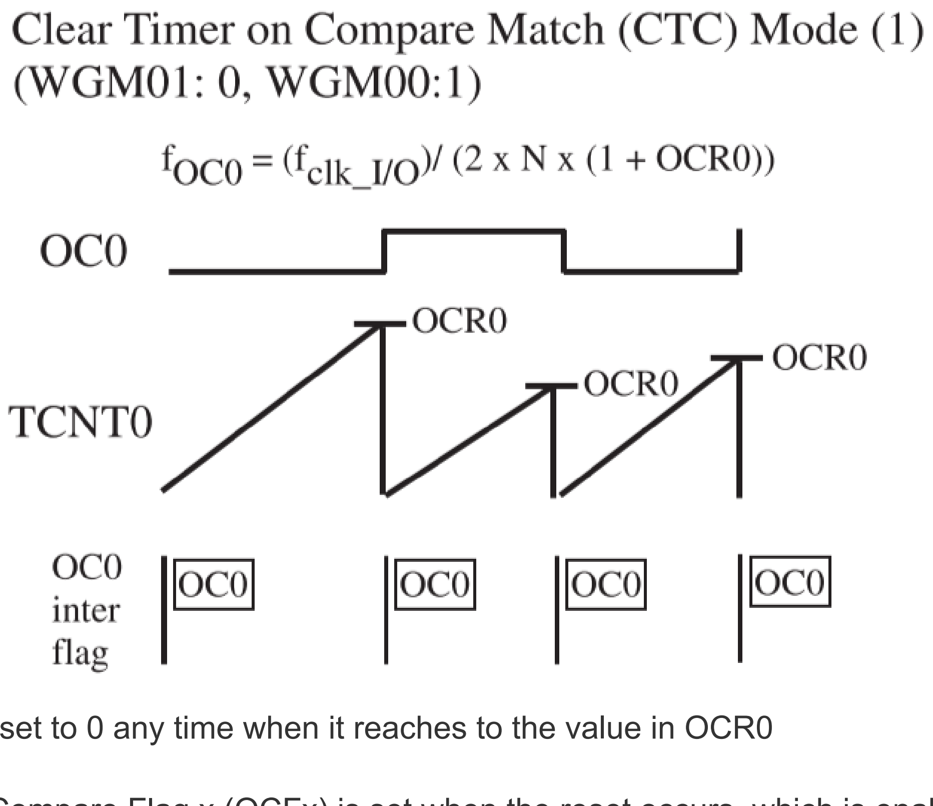
Normal Mode



The timer will continually counts from BOTTOM to TOP

As the TCNTx returns to 0 on each time cycle, the Timer/Counter Overflow Flag (TOVx) will be set

Clear Timer on Compare Match

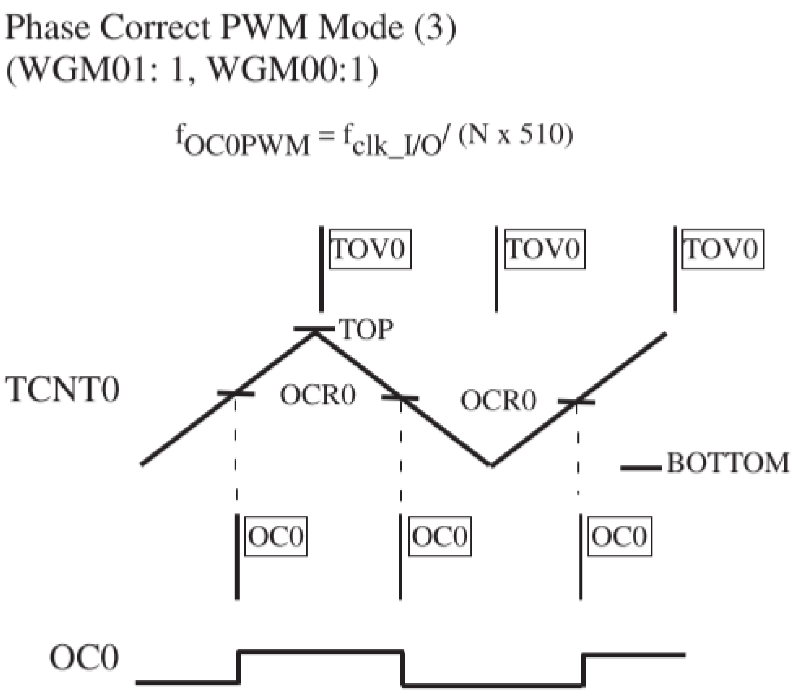


Clear Timer on Compare Match (CTC) Mode (1)
(WGM01: 0, WGM00:1)
$f_{OC0} = (f_{clk\_I/O}) / (2 \times N \times (1 + OCR0))$
OC0
OCR0
OCR0
OCR0
TCNT0
OC0 inter flag
OC0
OC0
OC0
OC0

TCNTx will be reset to 0 any time when it reaches to the value in OCR0

And the Output Compare Flag x (OCFx) is set when the reset occurs, which is enabled in Timer/Counter x Output Compare Match Interrupt Enable (OCIEx) flag in the TIMSK

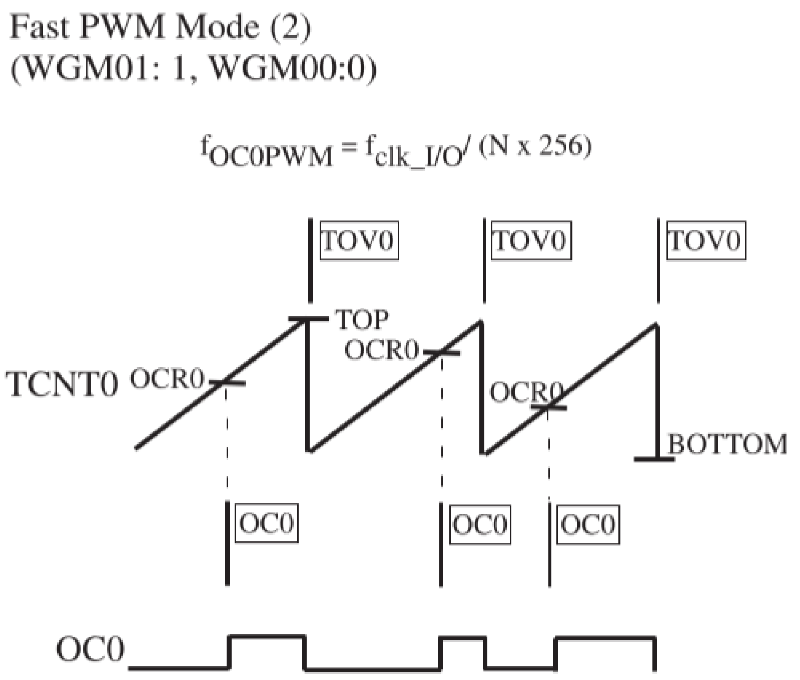
Phase Correct PWM Mode


Phase Correct PWM Mode (3)
(WGM01: 1, WGM00:1)
$f_{OC0PWM} = f_{clk\_I/O} / (N \times 510)$
TOV0
TOV0
TOV0
TOP
TCNT0
OCR0
OCR0
BOTTOM
OC0
OC0
OC0
OC0

TCNTx register will counts from BOTTOM to TOP, then decreases to BOTTOM continuously

Every time the TCNTx value matches the value set in the OCRx register, the OCFx is set

Fast PWM Mode

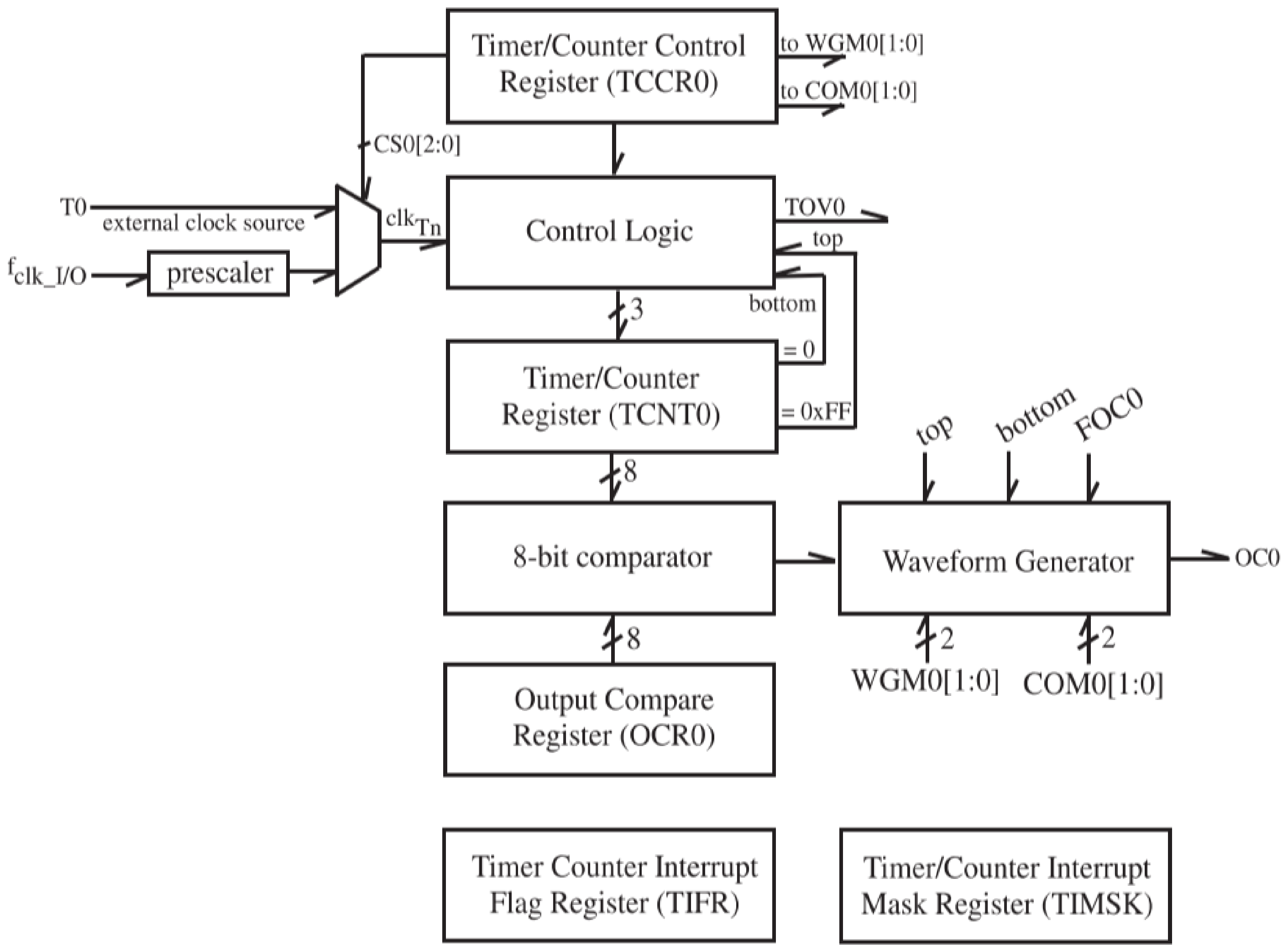


When the TCNTx register value reaches the value set in OCRx register, it will cause a change in the PWM output.

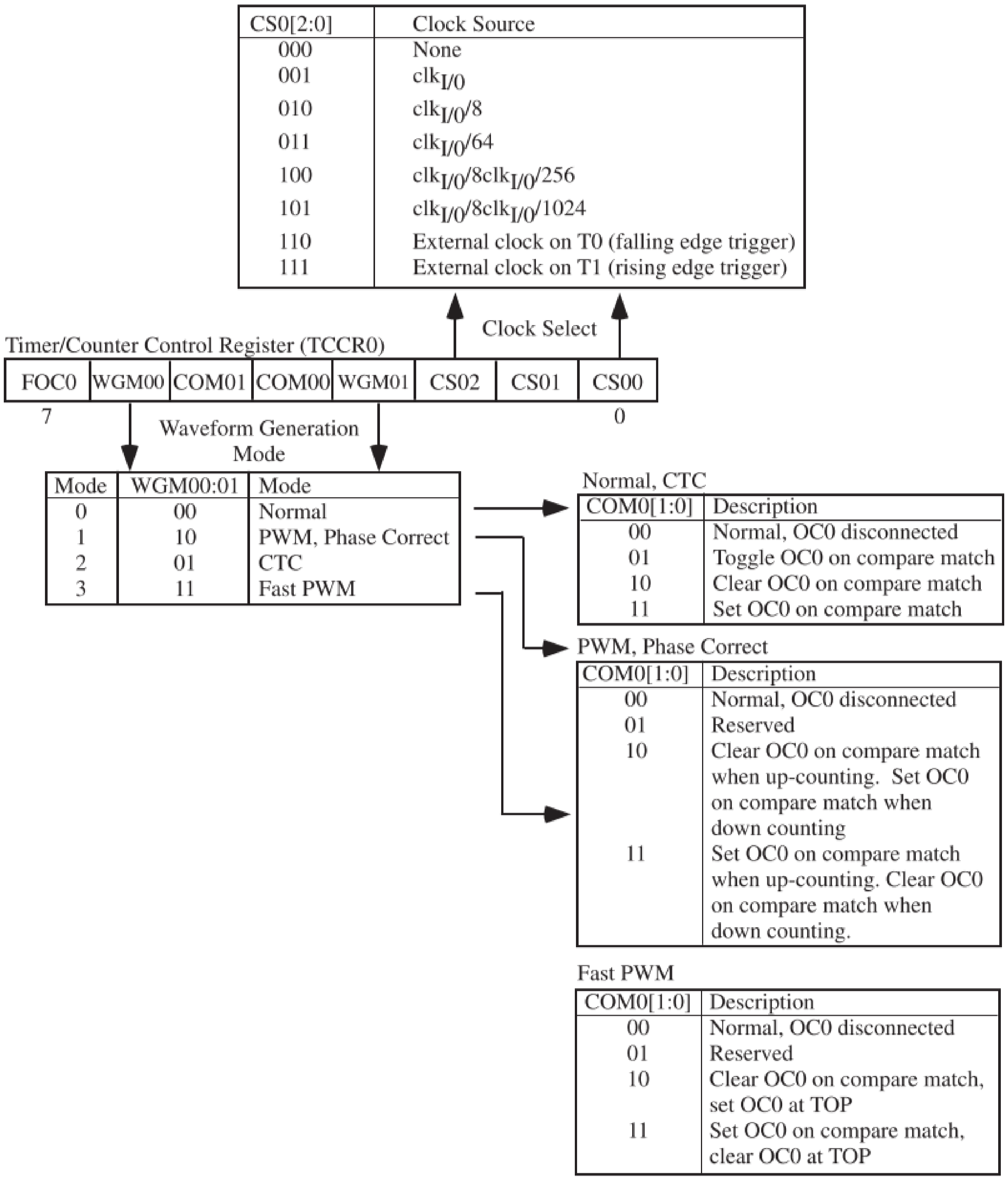
And the TCNTx continues to count up to the TOP value, at which time the Timer/Counter x Overflow Flag (TOVx) is set

Timer 0/2

- 8-bit timer/counter
- 10-bit clock prescaler
- Functions:
  - Pulse width modulation
  - Frequency generation
  - Event counter
  - Output compare
- Modes of operation
  - Normal
  - Clear timer on compare match
  - Fast PWM
  - Phase correct PWM



Timer 0/2 Registers



CS0[2:0]	Clock Source
000	None
001	$clk_{I/0}$
010	$clk_{I/0}/8$
011	$clk_{I/0}/64$
100	$clk_{I/0}/8clk_{I/0}/256$
101	$clk_{I/0}/8clk_{I/0}/1024$
110	External clock on T0 (falling edge trigger)
111	External clock on T1 (rising edge trigger)

Timer/Counter Control Register (TCCR0)

FOC0	WGM00	COM01	COM00	WGM01	CS02	CS01	CS00
7							0

Mode	WGM00:01	Mode
0	00	Normal
1	10	PWM, Phase Correct
2	01	CTC
3	11	Fast PWM

Normal, CTC

COM0[1:0]	Description
00	Normal, OC0 disconnected
01	Toggle OC0 on compare match
10	Clear OC0 on compare match
11	Set OC0 on compare match

PWM, Phase Correct

COM0[1:0]	Description
00	Normal, OC0 disconnected
01	Reserved
10	Clear OC0 on compare match when up-counting. Set OC0 on compare match when down counting
11	Set OC0 on compare match when up-counting. Clear OC0 on compare match when down counting.

Fast PWM

COM0[1:0]	Description
00	Normal, OC0 disconnected
01	Reserved
10	Clear OC0 on compare match, set OC0 at TOP
11	Set OC0 on compare match, clear OC0 at TOP

> FOC0/2 could only be active (set to logic one) in non-PWM mode,

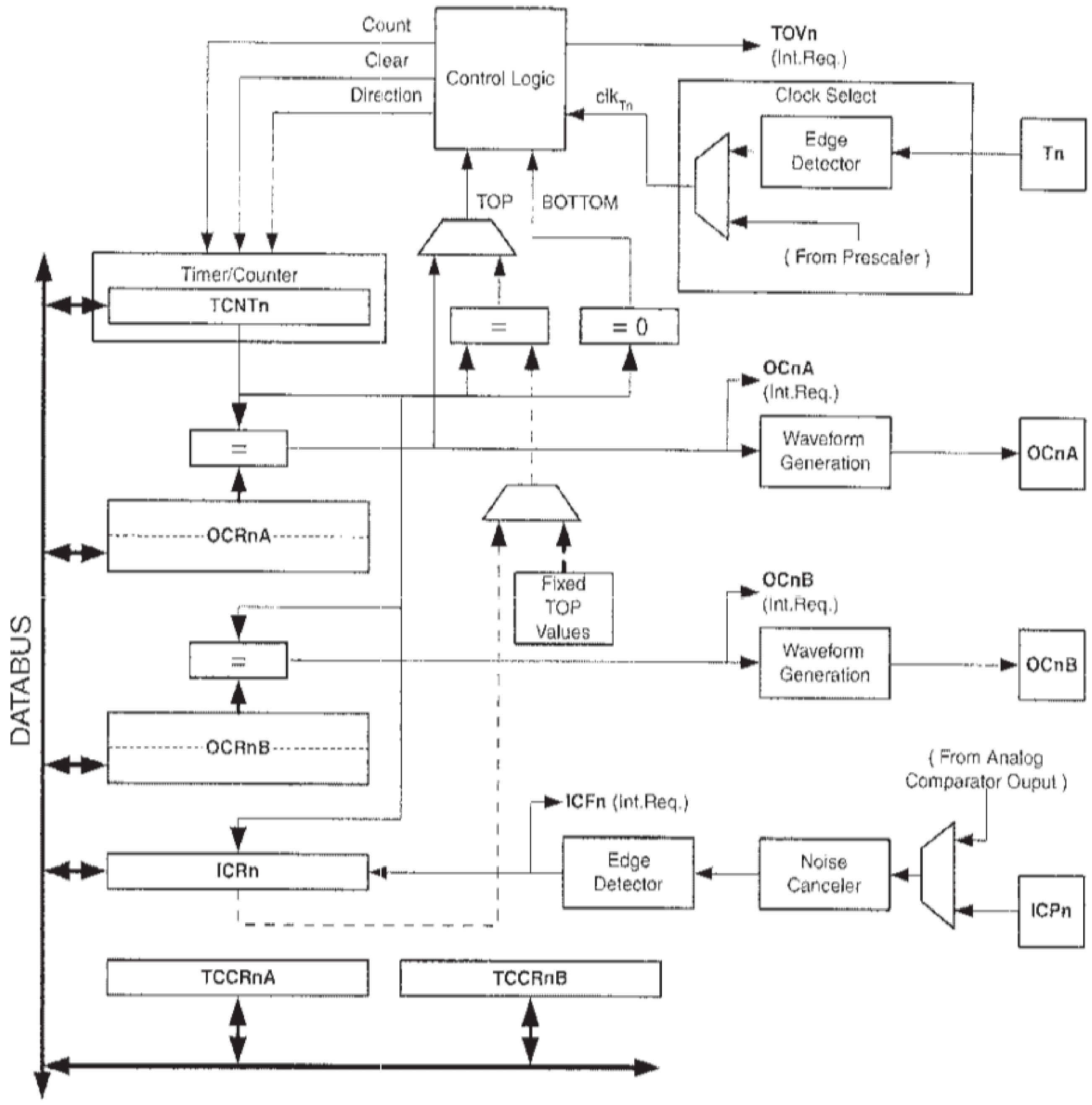
Timer/Counter Interrupt Mask Register (TIMSK)

OCIE2	TOIE2	TICIE1	OCIE1A	OCIE1B	TOIE1	OCIE0	TOIE0
7							0

Bit Number	Register Bit	Register Bit Name	Function
7	OCIE2	Timer 2 Output Compare Match Interrupt Enable	1 to enable the compare match interrupt
6	TOIE2	Timer 2 Overflow Interrupt Enable	1 to enable the overflow interrupt
1	OCIE0	Timer 0 Output Compare Match Interrupt Enable	1 to enable the compare match interrupt
0	TOIE0	Timer 0 Overflow Interrupt Enable	1 to enable the overflow interrupt

Timer 1

- 16-bit timer/counter
- 10-bit clock prescaler
- Functions:
  - Pulse width modulation
  - Frequency generation
  - Event counter
  - Output compare - 2 channel
  - Input capture
- Modes of operation
  - Normal
  - Clear timer on compare match
  - Fast PWM
  - Phase correct PWM



Input Capture Mode

The input capture feature is used to capture the characteristics of an input signal, including period, frequency, duty cycle, or pulse length, which is accomplished by monitoring for a user-specified edge on the ICP1 microcontroller pin

When the desired edge occurs, the value of the Timer/Counter 1 (TCNT1) register is captured and stored in the Input Capture Register 1 (ICR1)

Timer 1 Registers

CS0[2:0]	Clock Source
000	None
001	$\text{clk}_{I/0}$
010	$\text{clk}_{I/0}/8$
011	$\text{clk}_{I/0}/64$
100	$\text{clk}_{I/0}/8\text{clk}_{I/0}/256$
101	$\text{clk}_{I/0}/8\text{clk}_{I/0}/1024$
110	External clock on T0 (falling edge trigger)
111	External clock on T1 (rising edge trigger)

Clock Select

Timer/Counter 1 Control Register B (TCCR1B)

ICNC1	ICES1	—	WGM13	WGM12	CS12	CS11	CS10
7							0

Timer/Counter 1 Control Register A (TCCR1A)

COM1A1	COM1A0	COM1B1	COM1B0	FOC1A	FOC1B	WGM11	WGM10
7							0

Waveform Generation Mode

Mode	WGM[13:12:11:10]	Mode
0	0000	Normal
1	0001	PWM, Phase Correct, 8-bit
2	0010	PWM, Phase Correct, 9-bit
3	0011	PWM, Phase Correct, 10-bit
4	0100	CTC
5	0101	Fast PWM, 8-bit
6	0110	Fast PWM, 9-bit
7	0111	Fast PWM, 10-bit
8	1000	PWM, Phase & Freq Correct
9	1001	PWM, Phase & Freq Correct
10	1010	PWM, Phase Correct
11	1011	PWM, Phase Correct
12	1100	CTC
13	1101	Reserved
14	1110	Fast PWM
15	1111	Fast PWM

Normal, CTC

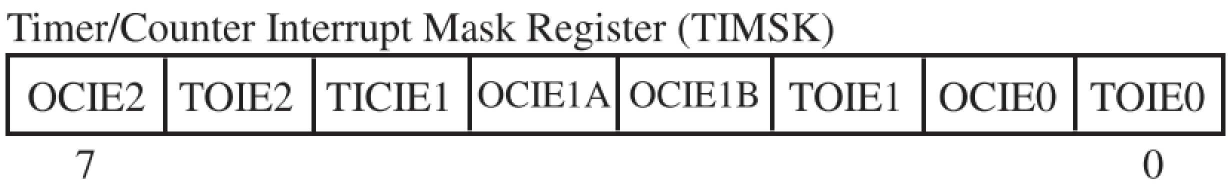
COMx[1:0]	Description
00	Normal, OC1A/1B disconnected
01	Toggle OC1A/1B on compare match
10	Clear OC1A/1B on compare match
11	Set OC1A/1B on compare match

PWM, Phase Correct, Phase & Freq Correct

COMx[1:0]	Description
00	Normal, OC0 disconnected
01	WGM1[3:0] = 9 or 14: toggle OCnA on compare match, OCnB discon-nected WGM1[3:0]= other settings, OC1A/1B disconnected
10	Clear OC0 on compare match when up-counting. Set OC0 on compare match when down counting
11	Set OC0 on compare match when up-counting. Clear OC0 on compare match when down counting.

Fast PWM

COMx[1:0]	Description
00	Normal, OC1A/1B disconnected
01	WGM1[3:0] = 15, toggle OC1A on compare match OC1B disconnected WGM1[3:0] = other settings, OC1A/1B disconnected
10	Clear OC1A/1B on compare match, set OC1A/1B at TOP
11	Set OC1A/1B on compare match, clear OC1A/1B at TOP


Timer/Counter Interrupt Mask Register (TIMSK)

7							0
OCIE2	TOIE2	TICIE1	OCIE1A	OCIE1B	TOIE1	OCIE0	TOIE0

Bit Number	Register Bit	Register Bit Name	Function
5	TICIE1	Timer 1 Input Capture Interrupt Enable	1 to enable the input capture interrupt
4:3	OCIE1A:B	Timer 1 Channel A:B Output Compare Match Interrupt Enable	1 to enable the compare match interrupt
2	TOIE1	Timer 1 Overflow Interrupt Enable	1 to enable the overflow interrupt

1. **RISC**, acronym for Reduced-instruction-set Computing, information processing using any of a family of microprocessors that are designed to execute computing tasks with the simplest instructions in the shortest amount of time possible. RISC is the opposite of **CISC** (Complex-instruction-set Computing). ↩
2. **Harvard architecture** is a computer architecture with separate storage and signal pathways for instructions and data. It contrasts with the **von Neumann architecture**, where program instructions and data share the same memory and pathways. ↩
3. The term static differentiates **SRAM** from **DRAM** (dynamic random-access memory) which must be **periodically** refreshed. SRAM is faster and more expensive than DRAM; it is typically used for the cache and internal registers of a CPU while DRAM is used for a computer's main memory. ↩
4. When these higher-priority events occur, the micro controller must temporarily suspend normal operation and execute event specific actions, called an **interrupt service routine**. ↩