Introduction to Embedded Systems
CSE 211

Textbooks – Hardware - Compiler

- Introduction to ARM Cortex- M Microcontroller, Jonathan Valvano
- Computers as Components, Wayne Wolf
- Hardware
  - Tiva LanuchPad TM4C123
- Compiler
  - Keil – ARM Compiler
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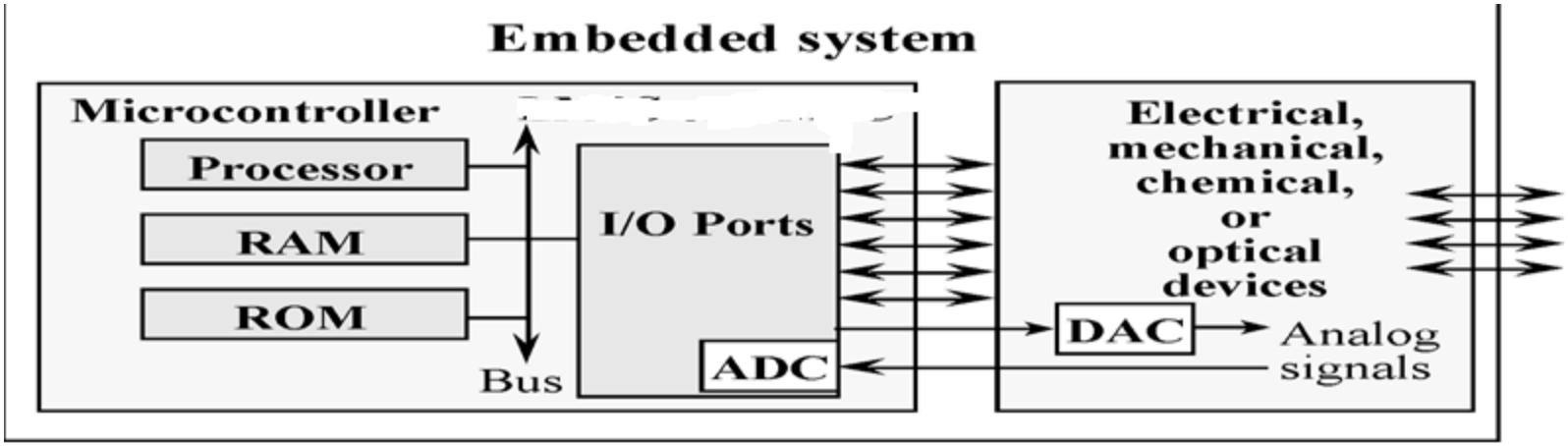
  - ashraf.salem@eng.asu.edu.eg

Course Contents

- CSE 211
  1. ARM Cortex-M architecture
  2. ARM Cortex-M assembly Language
  3. TM4C123 Microcontroller
  4. Input and output ports
  5. SysTick Timer
  6. Serial and Parallel Interfaces
  7. Interrupt Programming
  8. Analog I/I Interface
  9. Real Time Operating System

Embedded Systems

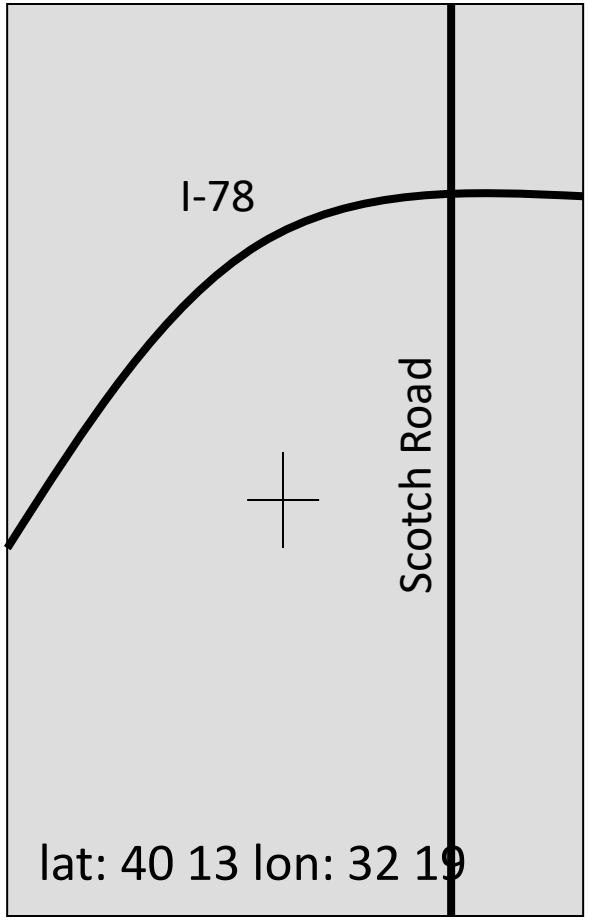


Microcontroller

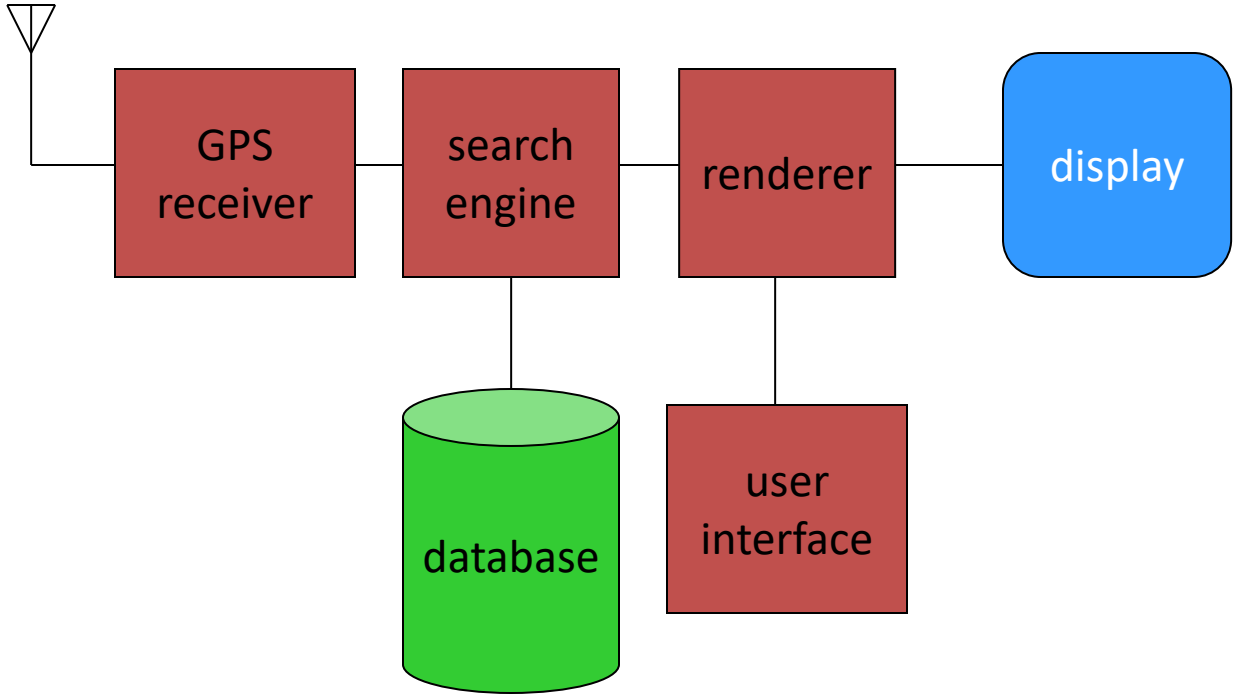
- Processor – Instruction Set + memory + accelerators
- Memory
  - Non-Volatile
    - ROM
    - EPROM, EEPROM, Flash
  - Volatile
    - RAM (DRAM, SRAM)
- Interfaces
  - H/W: Ports
  - S/W: Device Driver
  - Parallel, Serial, Analog, Time

Embedded System Example GPS

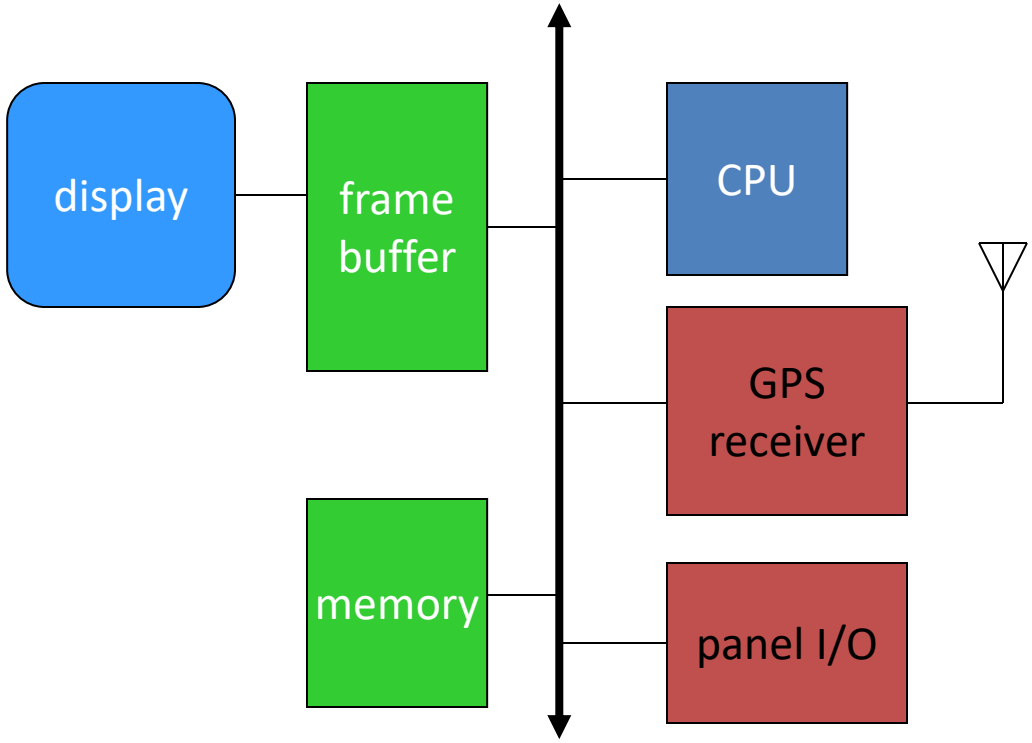
- Moving map obtains position from GPS, paints map from local database.



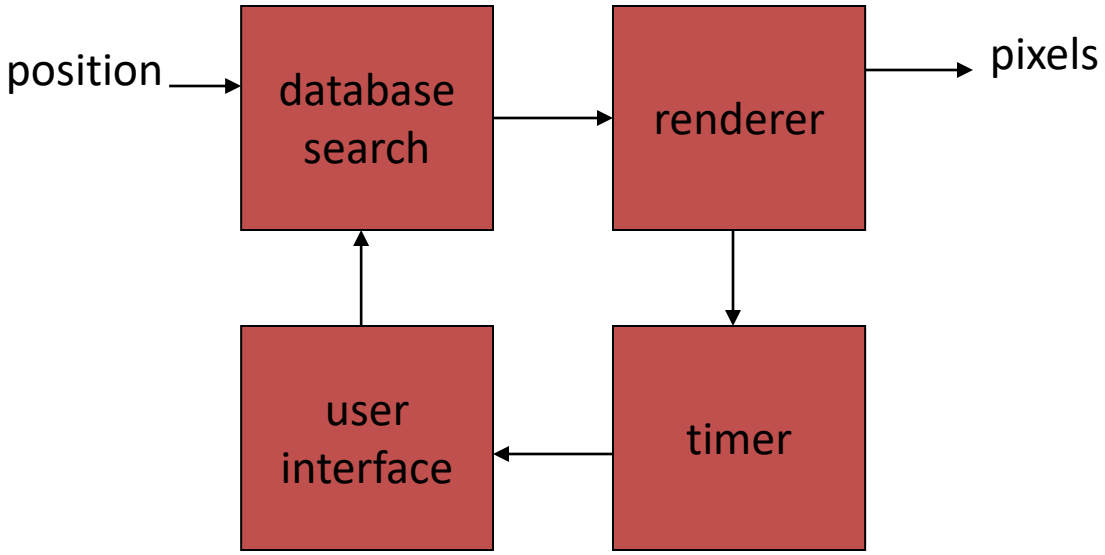
GPS moving map block diagram



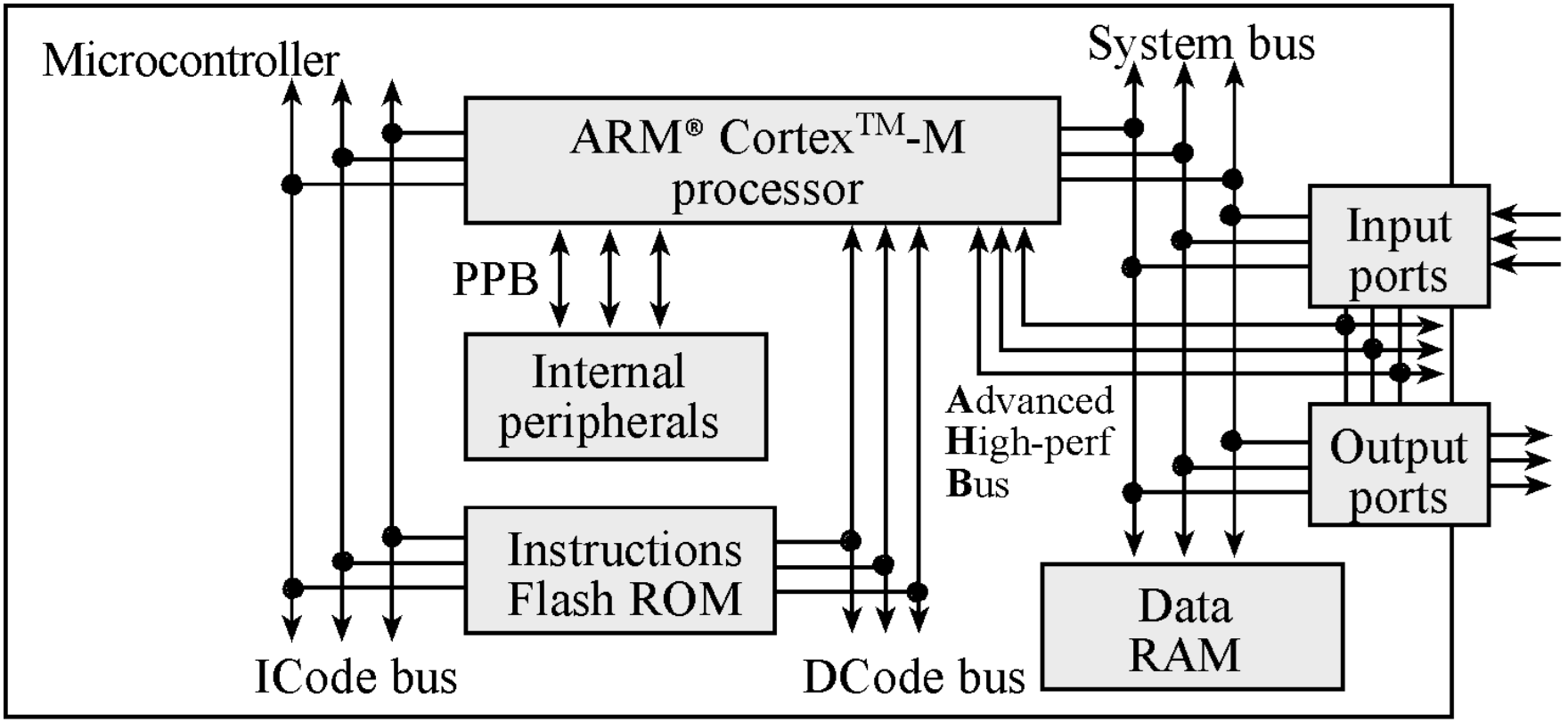
GPS moving map hardware architecture



GPS moving map software architecture

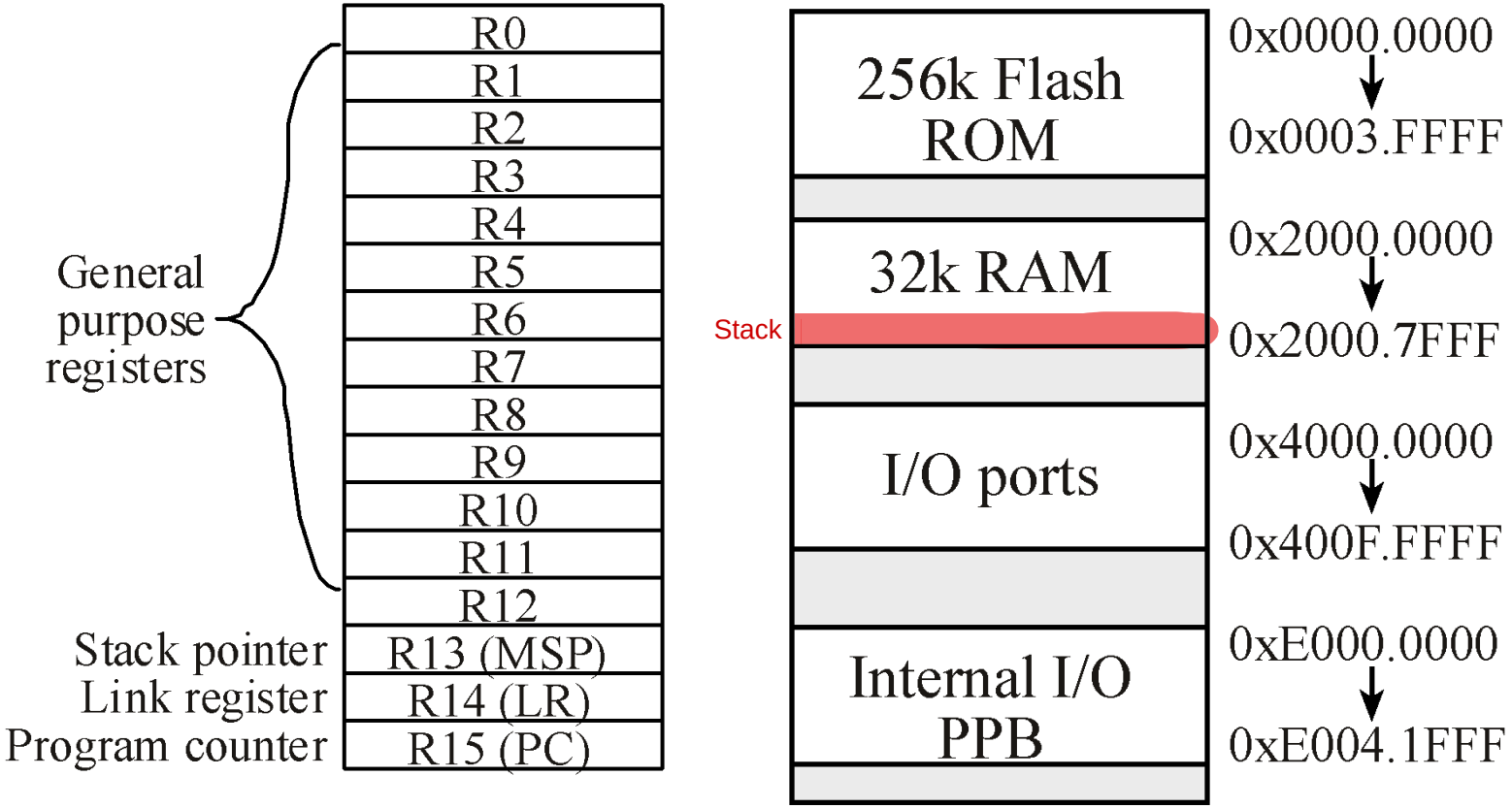


ARM Cortex M4-based System



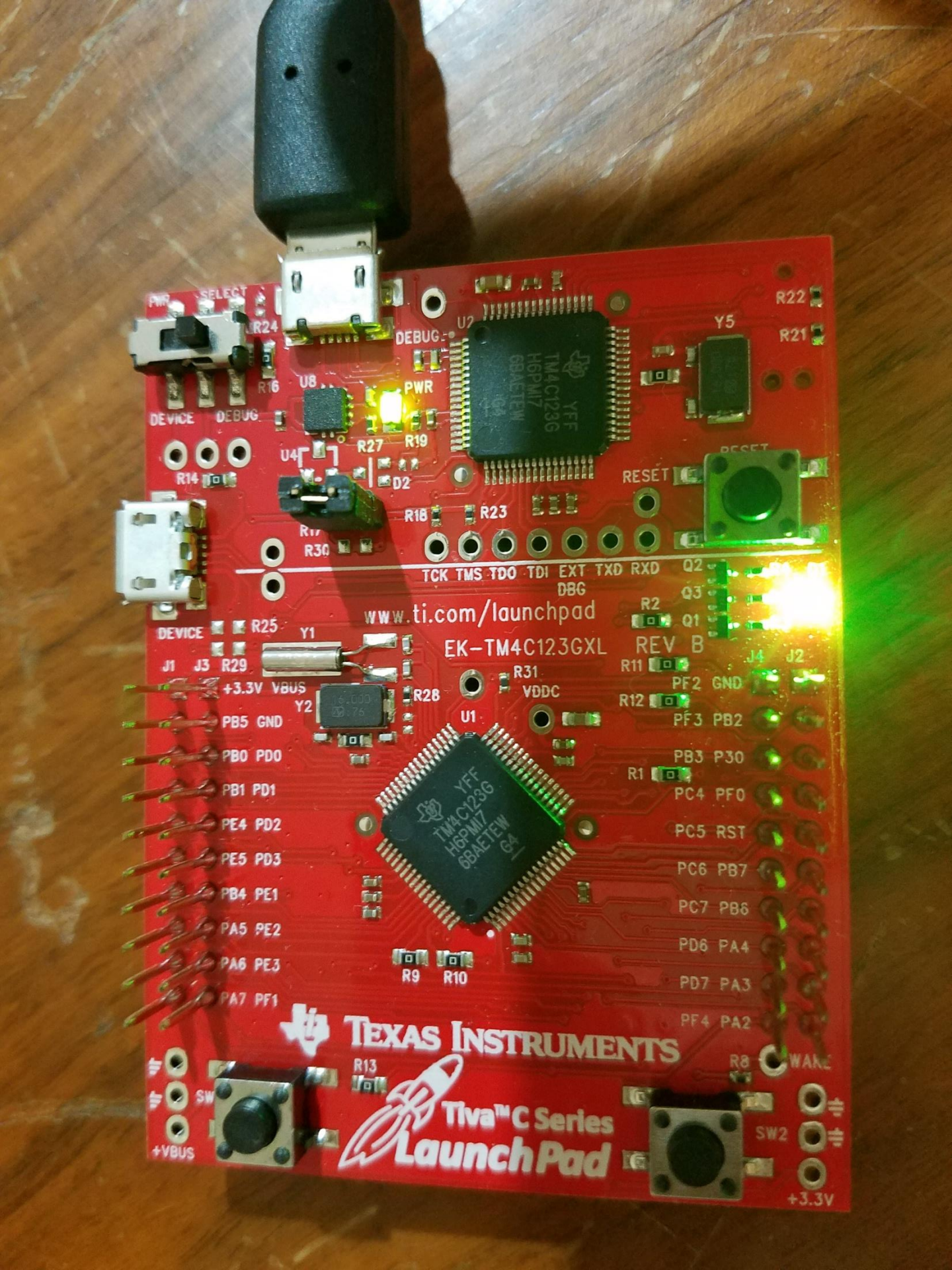
- ARM Cortex-M4 processor
- *Harvard* architecture
  - Different busses for instructions and data

ARM ISA: Registers, Memory-map

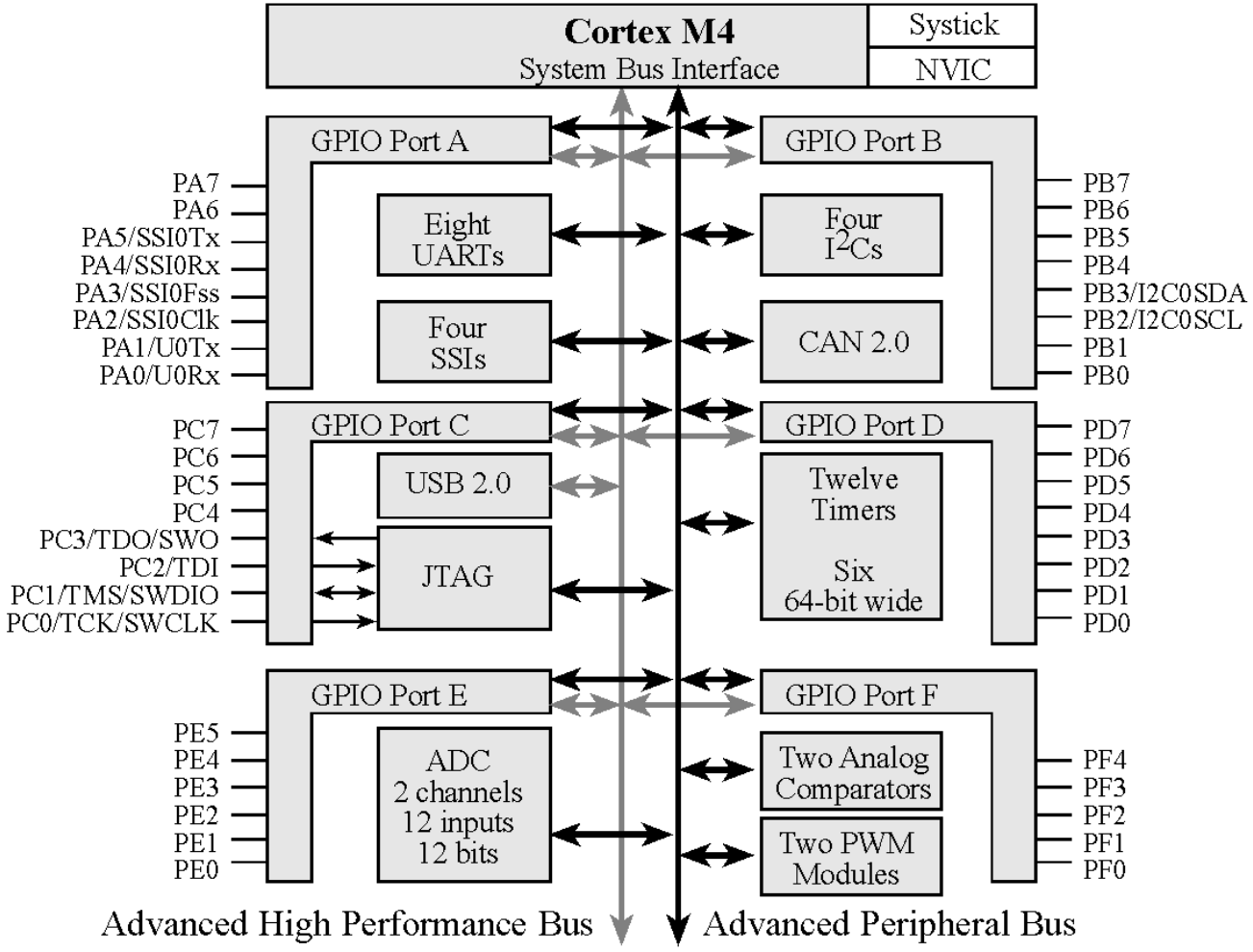


Condition Code Bits		***Indicates***
N	negative	Result is negative
Z	zero	Result is zero
V	overflow	Signed overflow
C	carry	Unsigned overflow

TI TM4C123 Microcontroller


SELECT
R24
DEBUG
U2
Y5
R22
R21
DEVICE
DEBUG
R16
U8
PWR
R27
R19
U4
R14
D2
RESET
R18
R23
R17
R30
TCK TMS TDO TDI EXT TXD RXD
DBG
Q2
Q3
Q1
R2
www.ti.com/launchpad
DEVICE
R25
Y1
EK-TM4C123GXL
REV B
J1
J3
R29
R11
J4
J2
+3.3V
VBUS
R31
VDDC
R28
Y2
R12
PF2 GND
PB5 GND
U1
PF3 PB2
PB0 PD0
PB3 P30
R1
PB1 PD1
PC4 PF0
PE4 PD2
PC5 RST
PE5 PD3
PC6 PB7
PB4 PE1
PC7 PB6
PA5 PE2
PD6 PA4
PA6 PE3
PD7 PA3
PA7 PF1
PF4 PA2
R9
R10
TEXAS INSTRUMENTS
R13
R8
WAKE
SW1
Tiva™C Series
SW2
+VBUS
LaunchPad
+3.3V

Texas Instruments TM4C123



ARM Cortex-M4
+ 256K Flash
+ 32K RAM
+ JTAG
+ 43 Ports
+ SysTick
+ ADC
+ UART

ARM data instructions

- Basic format:

  `ADD R0,R1,R2`

  – Computes R1+R2, stores in R0.

- Immediate operand:

  `ADD R0,R1,#2`

  – Computes R1+R2, stores in R0.

ARM data instructions

- ADD, ADC : add (w. carry)
- SUB, SBC : subtract (w. carry)
- MUL: multiply
- AND, ORR, EOR
- BIC : bit clear
- LSL, LSR : logical shift left/right
- ROR : rotate right

ARM load/store instructions

- LDR, LDRH, LDRB : load (half-word, byte)
- STR, STRH, STRB : store (half-word, byte)
- Addressing modes:
  - register indirect : `LDR R0,[R1]`
  - with constant : `LDR R0,[R1,#4]`

ARM LDR instruction

- Load from memory into a register

```
LDR R8,[R10]
```

Example: C assignments

- C:

```
x = (a + b) - c;
```

- Assembler:

```
LDR R4,=A          ; get address for a
LDR R0,[R4]              ; get value of a
LDR R4,=B          ; get address for b, reusing r4
LDR R1,[R4]              ; get value of b
ADD R3,R0,R1             ; compute a+b
LDR R4,=C          ; get address for c
LDR R2,[R4]              ; get value of c
```

C assignment, cont’d.

```
SUB R3,R3,R2      ; complete computation of x
LDR R4,=X         ; get address for x
STR R3,[R4]       ; store value of x
```

Example: C assignment

- C:

```
y = a*(b+c);
```

- Assembler:

```
LDR R4,=B ; get address for b
LDR R0,[R4] ; get value of b
LDR R4,=C ; get address for c
LDR R1,[R4] ; get value of c
ADD R2,R0,R1 ; compute partial result
LDR R4,=A ; get address for a
LDR R0,[R4] ; get value of a
```

C assignment, cont’d.

```
MUL R2,R2,R0 ; compute final value for y
LDR R4,=Y ; get address for y
STR R2,[R4] ; store y
```

Example: C assignment

- C:

```
Z = (A << 2) |  (B & 15);
```

- Assembler:

```
LDR R4,=A ; get address for a
LDR R0,[R4] ; get value of a
LSL R5,R0,#2 ; perform shift
LDR R4,=B ; get address for b
LDR R1,[R4] ; get value of b
AND R1,R1,#15 ; perform AND
ORR R1,R5,R1 ; perform OR
```

C assignment, cont’d.

```
LDR R4,=Z ; get address for z
STR R1,[R4] ; store value for z
```

If statement, cont'd.

```
; false block
fblock LDR R4,=C ; get address for c
   LDR R0,[R4] ; get value of c
   LDR R4,=D ; get address for d
   LDR R1,[R4] ; get value for d
   SUB R0,R0,R1 ; compute a-b
   LDR R4,=X ; get address for x
   STR R0,[R4] ; store value of x
after ...
```

Example: if statement

- C:

```
if (a > b) { x = 5; y = c + d; } else x = c - d;
```

- Assembler:

```
; compute and test condition
   LDR R4,=A ; get address for a
   LDR R0,[R4] ; get value of a
   LDR R4,=B ; get address for b
   LDR R1,[R4] ; get value for b
   CMP R0,R1 ;
   BLE fblock ;
```

If statement, cont'd.

```
; true block
   MOV R0,#5 ; generate value for x
   LDR R4,=X ; get address for x
   STR R0,[R4] ; store x
   LDR R4,=C ; get address for c
   LDR R0,[R4] ; get value of c
   LDR R4,=D ; get address for d
   LDR R1,[R4] ; get value of d
   ADD R0,R0,R1 ; compute y
   LDR R4,=Y ; get address for y
   STR R0,[R4] ; store y
   B after ; branch around false block
```

If statement, cont'd.

```
; false block
fblock LDR R4,=C ; get address for c
   LDR R0,[R4] ; get value of c
   LDR R4,=D ; get address for d
   LDR R1,[R4] ; get value for d
   SUB R0,R0,R1 ; compute a-b
   LDR R4,=X ; get address for x
   STR R0,[R4] ; store value of x
after ...
```

Example

- C:

```
for (i=0, f=0; i<N; i++)
  f = f + c[i]*x[i];
```

- Assembler

```
; loop initiation code
  MOV R0,#0 ; use r0 for I
  MOV R8,#0 ; use separate index for arrays
  LDR R2,=N ; get address for N
  LDR R1,[R2] ; get value of N
  MOV R2,#0 ; use r2 for f
```

Example, cont'.d

```
      LDR R3,=C ; load r3 with base of c
      LDR R5,=X ; load r5 with base of x
; loop body
loop   LDR R4,[R3,R8] ; get c[i]
       LDR r6,[R5,R8] ; get x[i]
       MUL R4,R4,R6 ; compute c[i]*x[i]
       ADD R2,R2,R4 ; add into running sum
       ADD R8,R8,#4 ; add one word offset to array index
       ADD R0,R0,#1 ; add 1 to i
       CMP R0,R1 ; exit?
       BLT loop ; if i < N, continue
```

To set

The **or** operation to set bits 1 and 0 of a register.
The other six bits remain constant.

Friendly software modifies just the bits that need to be.

```
X |= 0x03;
```

Assembly:

```
LDR   R0,=X
LDR   R1,[R0]        ; read previous value
ORR   R1,R1,#0x03    ; set bits 0 and 1
STR   R1,[R0]        ; update
```

c_7	c_6	c_5	c_4	c_3	c_2	c_1	c_0	
0	0	0	0	0	0	1	1	0x03 constant
c_7	c_6	c_5	c_4	c_3	c_2	1	1	result of the ORR

value of R1

To toggle

The **exclusive or** operation can also be used to toggle bits.

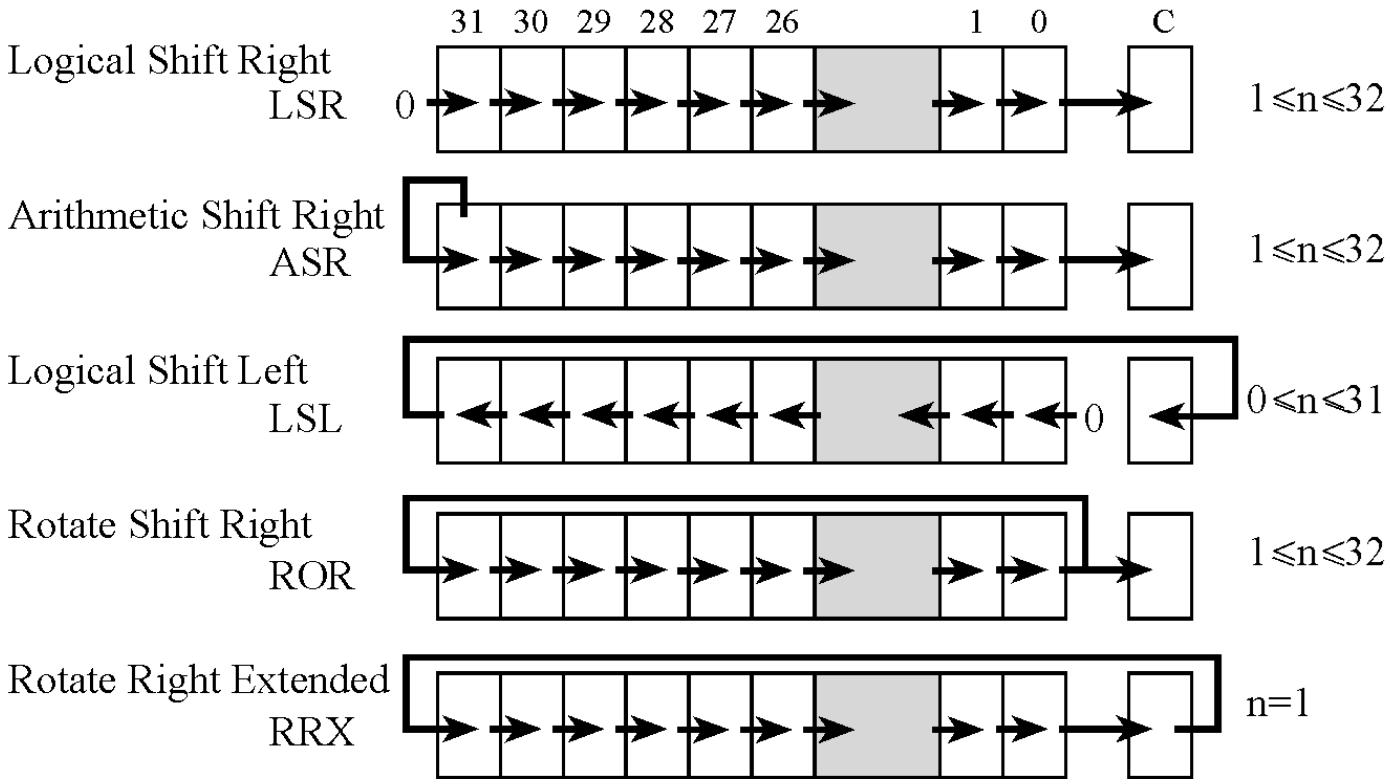
```
X ^= 0x80;
```

Assembly:

```
LDR   R0,=X
LDR   R1,[R0]        ; read port D
EOR   R1,R1,#0x80    ; toggle bit 7
STR   R1,[R0]        ; update
```

b_7	b_6	b_5	b_4	b_3	b_2	b_1	b_0	value of R1
1	0	0	0	0	0	0	0	0x80 constant
$\sim b_7$	b_6	b_5	b_4	b_3	b_2	b_1	b_0	result of the EOR

Shift Operations



Shift Example

High and **Low** are unsigned 4-bit components, which will be combined into a single unsigned 8-bit **Result**.

```
Result = (High<<4)|Low;
```

Assembly:

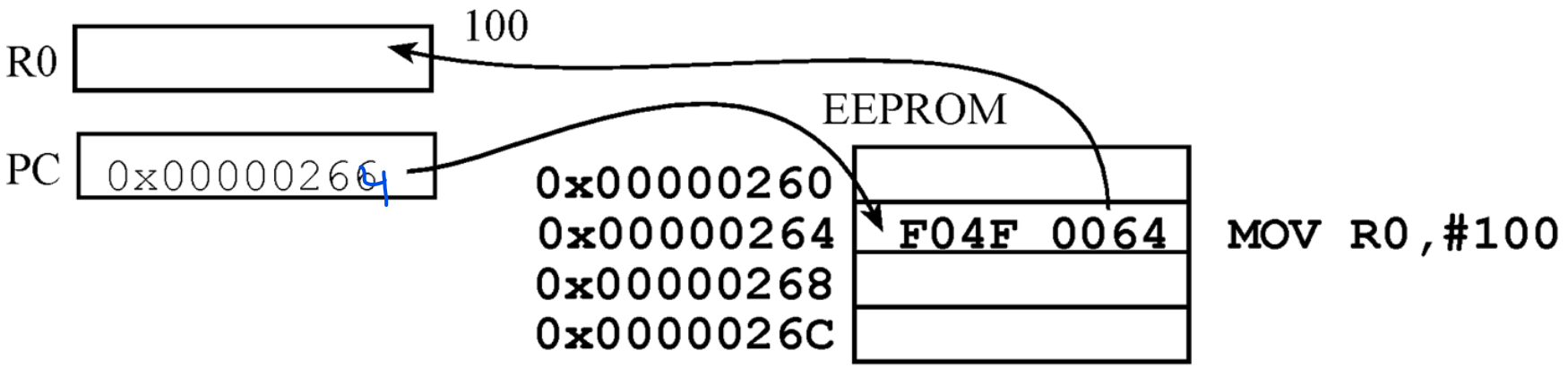
```
LDR   R0,=High
LDR   R1,[R0]          ; read value of High
LSL   R1,R1,#4         ; shift into position
LDR   R0,=Low
LDR   R2,[R0]          ; read value of Low
ORR   R1,R1,R2         ; combine the two parts
LDR   R0,=Result
STR   R1,[R0]          ; save the answer
```

0 0 0 0 h_3 h_2 h_1 h_0	value of **High** in **R1**
h_3 h_2 h_1 h_0 0 0 0 0	after last **LSL**
0 0 0 0 l_3 l_2 l_1 l_0	value of **Low** in **R2**
h_3 h_2 h_1 h_0 l_3 l_2 l_1 l_0	result of the **ORR** instruction

Addressing Modes

- Immediate addressing
  - Data is contained in the instruction

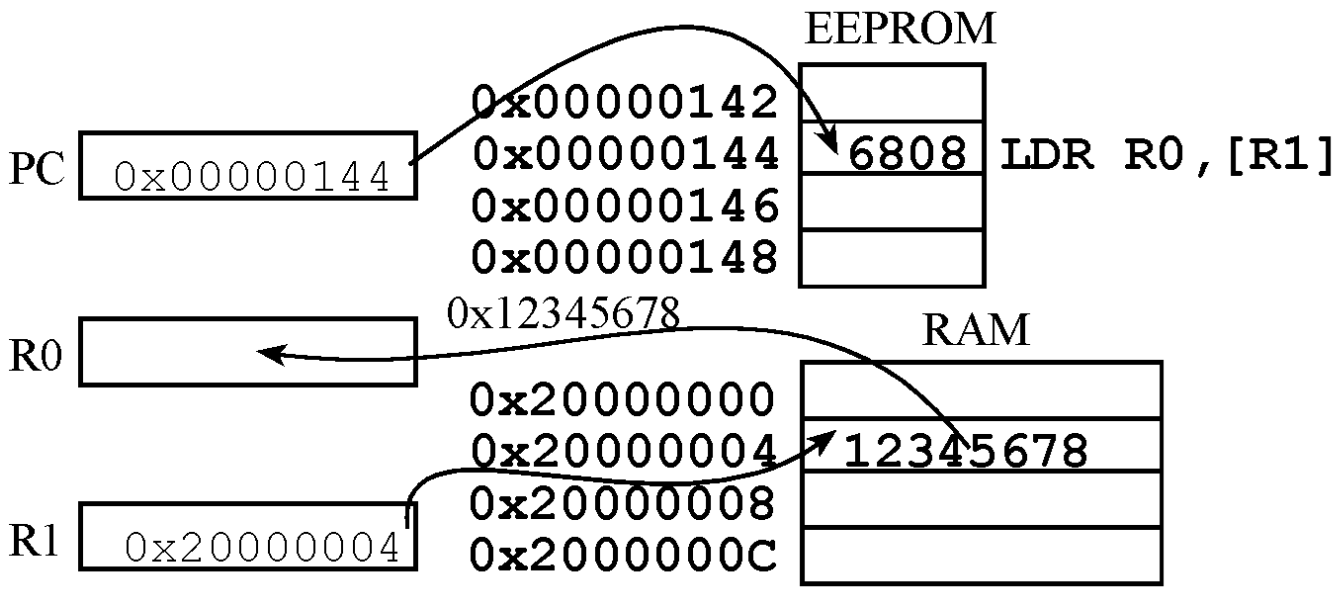
```
MOV   R0,#100        ; R0=100, immediate addressing
```



Addressing Modes

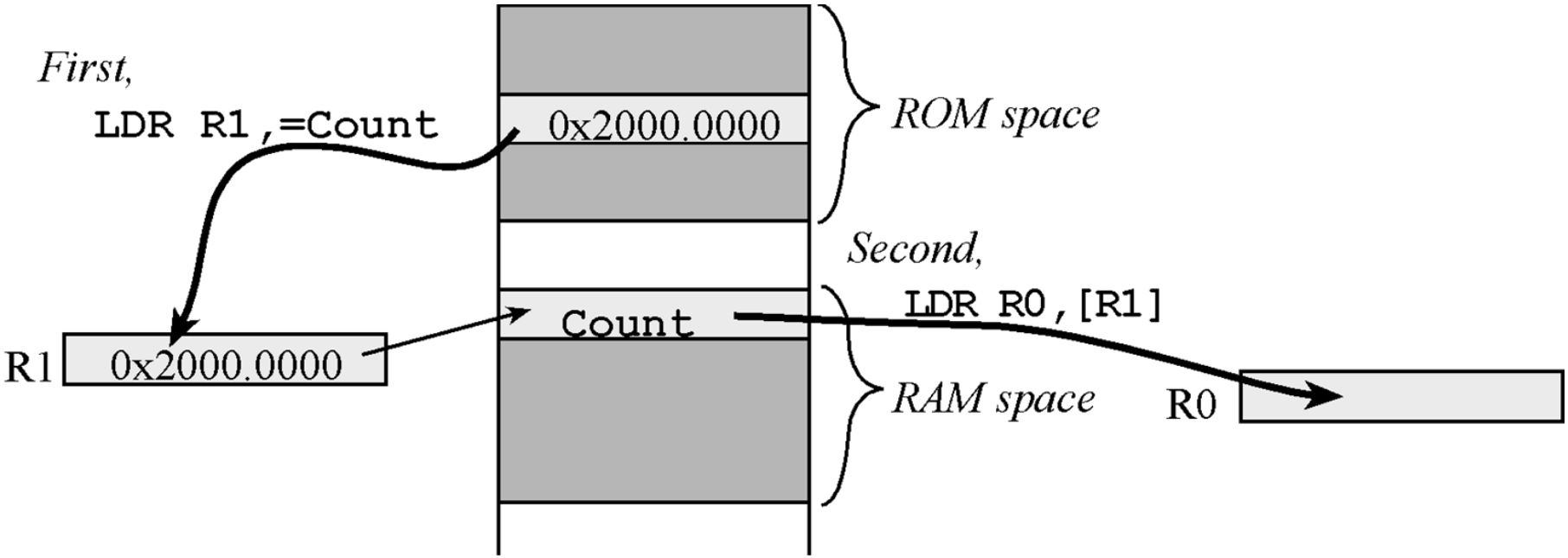
- Indexed Addressing
  - Address of the data in memory is in a register

```
LDR    R0,[R1]        ; R0= value pointed to by R1
```



Addressing Modes

- PC Relative Addressing
  - Address of data in **EEPROM** is indexed based upon the Program Counter



Memory Access Instructions

- Loading a register with a constant, address, or data
  - `LDR Rd, =number`
  - `LDR Rd, =label`
- **`LDR`** and **`STR`** used to load/store RAM using register-indexed addressing
  - **`Register [R0]`**
  - **`Base address plus offset [R0,#16]`**

Load/Store Instructions

- General load/store instruction format

```
LDR{type} Rd,[Rn]      ;load memory at [Rn] to Rd
STR{type} Rt,[Rn]      ;store Rt to memory at [Rn]
LDR{type} Rd,[Rn, #n]  ;load memory at [Rn+n] to Rd
STR{type} Rt,[Rn, #n]  ;store Rt to memory [Rn+n]
LDR{type} Rd,[Rn,Rm,LSL #n]  ;load [Rn+Rm<<n] to Rd
STR{type} Rt,[Rn,Rm,LSL #n]  ;store Rt to [Rn+Rm<<n]
```

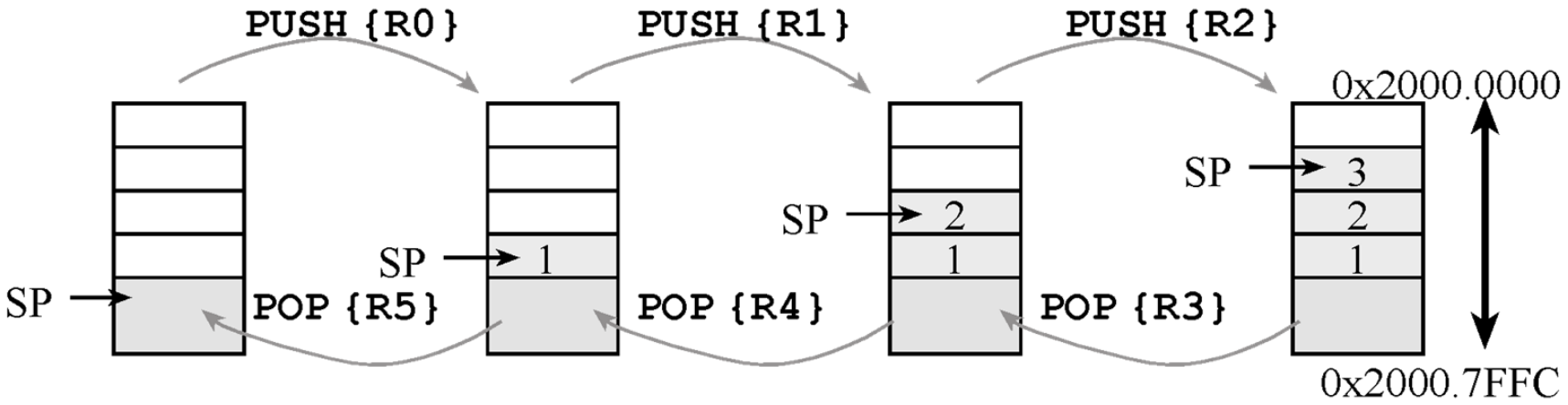
{type}	*Data type*	*Meaning*
	32-bit word	0 to 4,294,967,295 or -2,147,483,648 to +2,147,483,647
B	Unsigned 8-bit byte	0 to 255, Zero pad to 32 bits on load
SB	Signed 8-bit byte	-128 to +127, Sign extend to 32 bits on load
H	Unsigned 16-bit halfword	0 to 65535, Zero pad to 32 bits on load
SH	Signed 16-bit halfword	-32768 to +32767, Sign extend to 32 bits on load
D	64-bit data	Uses two registers

The Stack

- Stack is last-in-first-out (LIFO) storage
  - 32-bit data
- Stack pointer, SP or R13, points to top element of stack
- Stack pointer *decremented* as data placed on stack
- **`PUSH`** and **`POP`** instructions used to load and retrieve data

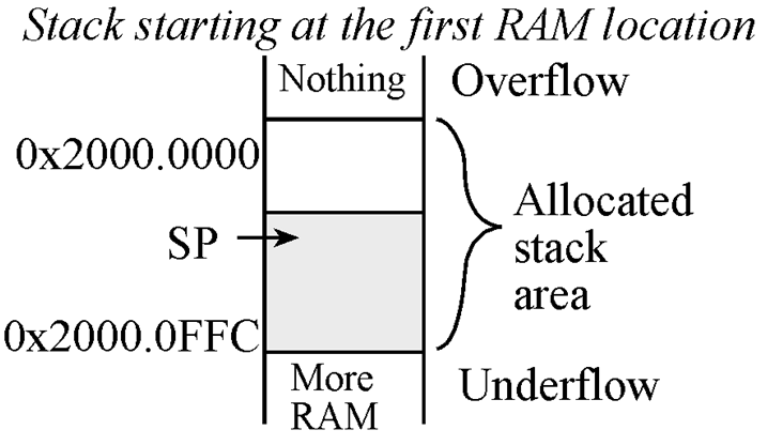
The Stack

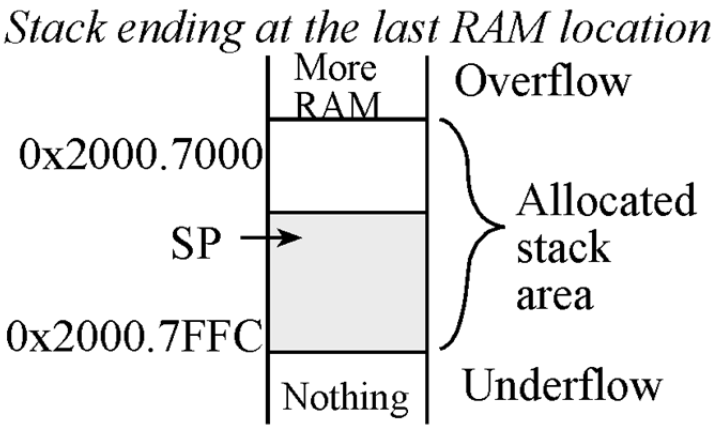
- Stack is last-in-first-out (LIFO) storage
  - 32-bit data
- Stack pointer, SP or R13, points to top element of stack
- Stack pointer *decremented* as data placed on stack (*incremented* when data is removed)
- **`PUSH`** and **`POP`** instructions used to load and retrieve data



Stack Usage

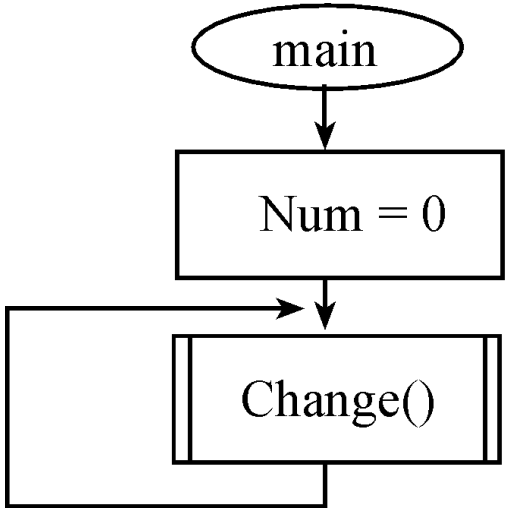
- Stack memory allocation

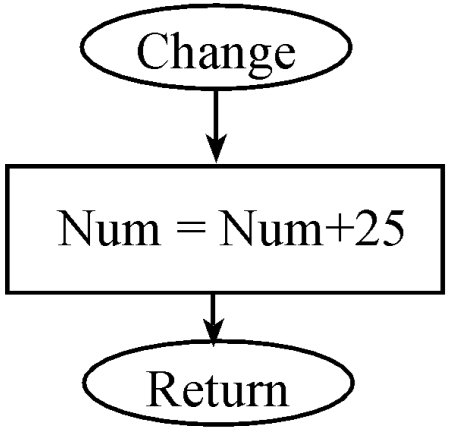




- Rules for stack use
  - Stack should always be balanced, i.e. functions should have an equal number of pushes and pops
  - Stack accesses (push or pop) should not be performed outside the allocated area

Functions






```
Change  LDR   R1,=Num    ; 5) R1 = &Num
        LDR   R0,[R1]    ; 6) R0 = Num
        ADD   R0,R0,#25  ; 7) R0 = Num+25
        STR   R0,[R1]    ; 8) Num = Num+25
        BX    LR         ; 9) return
main    LDR   R1,=Num    ; 1) R1 = &Num
        MOV   R0,#0      ; 2) R0 = 0
        STR   R0,[R1]    ; 3) Num = 0
loop    BL    Change     ; 4) function call
        B     loop       ; 10) repeat
```

```
unsigned long Num;
void Change(void){
  Num = Num+25;
}
void main(void){
  Num = 0;
  while(1){
    Change();
  }
}
```

Variables

- Type
  - int32_t
  - uint32_t
  - int16_t
  - uint16_t
  - int8_t
  - uint8_t
  - char
- Scope
  - Global -> everywhere
  - Local -> within {}
- Allocation
  - Global -> ROM or RAM
  - Local -> registers or stack

- 32-bit access
  - LDR
  - STR
- 16-bit access
  - LDRH LDRSH
  - STRH
- 8-bit access
  - LDRB LDRSB
  - STRB

Call by value versus reference

```
void noChange(uint32_t val){
    val = 5;
}
void Change(uint32_t *val){
   *val = 5;
}
uint32_t a;
int main(void){
  a = 55;
  noChange(a);
  Change(&a);
}
```

```
noChange
    MOV R0,#5
   BX LR
Change
   MOV R1,# 5
   STR R1,[R0]
   BX LR
main
   LDR R0,=a
   MOV R1,#55
   STR  R1,[R0]
   LDR R0,=a
   LDR R0,[R0]
   BL   noChange
   LDR R0,=a
   BL   Change
   BX LR
```

Pointers

```
void swap(uint32_t *a,uint32_t *b){
    uint32_t t;
    t = *a;
   *a = *b;
   *b = t;
}
uint32_t a,b;
int main(void){
  a = 3; b=4;
  swap(&a,&b);
}
```

```
AREA    DATA, ALIGN=2
a       SPACE 4
b       SPACE 4
```

```
main
    LDR R0,=a
    MOV R1,#3
    STR  R1,[R0]
    LDR R0,=b
    MOV R1,#5
    STR  R1,[R0]
    LDR R0,=a
    LDR R1,=b
    BL   swap

    BX LR
```

```
swap
    LDR R3,[R0] ;t=*a
    LDR R4,[R1] ;*b
    STR R4,[R0] ;*a =*b
    STR R3,[R1]
    BX LR
```

Array example

- Address calculation

32-bit	base+4*index
16-bit	base+2*index
8-bit	base+index

- Access

```
for(int i=0; i< 5;i++){
    aa[i] = i;
    bb[i] = 5;
}
```

```
    AREA   DATA, ALIGN=2
aa  SPACE 4*10
bb  SPACE 4*10
i RN 4
main MOV i,#0  ;i=0
    MOV R3,#5
forloop2
    CMP i,#5  ;is i<5
    BGE forDone2
    LDR R0,=aa  ;aa[i] = aa+4*i
    ASL R2,i,#2 ;R2=i*4
    STR i,[R0,R2]
    LDR R6,=bb
    STR R3,[R6,R2] ;bb+i*4
   ADD i,i,#1
   B  forloop2
forDone2
```

Array parameters

- Parameter is pass by reference

```
int32_t dot(int32_t a[], int32_t b[], int32_t l){
  int32_t s=0;
  for(int32_t i=0;i<l;i++){
        s += a[i]*b[i];
  }
  return s;
}
```

- Invocation pass by reference

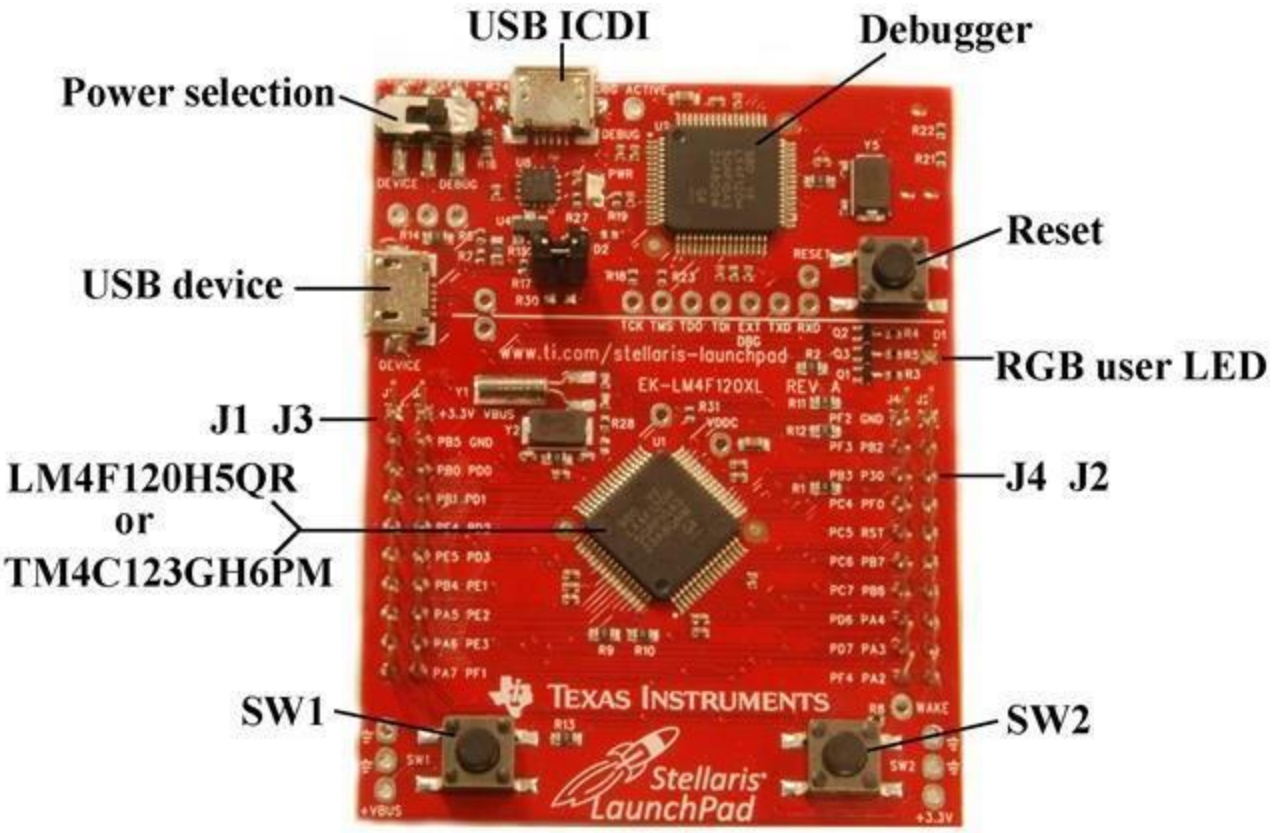
```
int main(void){
  int32_t result;
  result = dot(aa,bb,5);
  while(1){
  }
}
```

```
s RN 4
i  RN 5
dot MOV s,#0  ;s=0
    MOV i,#0  ;i=0
forloop3
    CMP i,R2  ;is i<l
    BGE forDone3
    ASL R6,i,#2 ;i*4
    LDR  R7,[R0,R6]
    LDR  R8,[R1,R6]
    MUL R7,R7,R8
   ADD s,s,R7
    ADD i,i,#1
   B  forloop3
forDone3
   MOV R0,s
   BX  LR
```

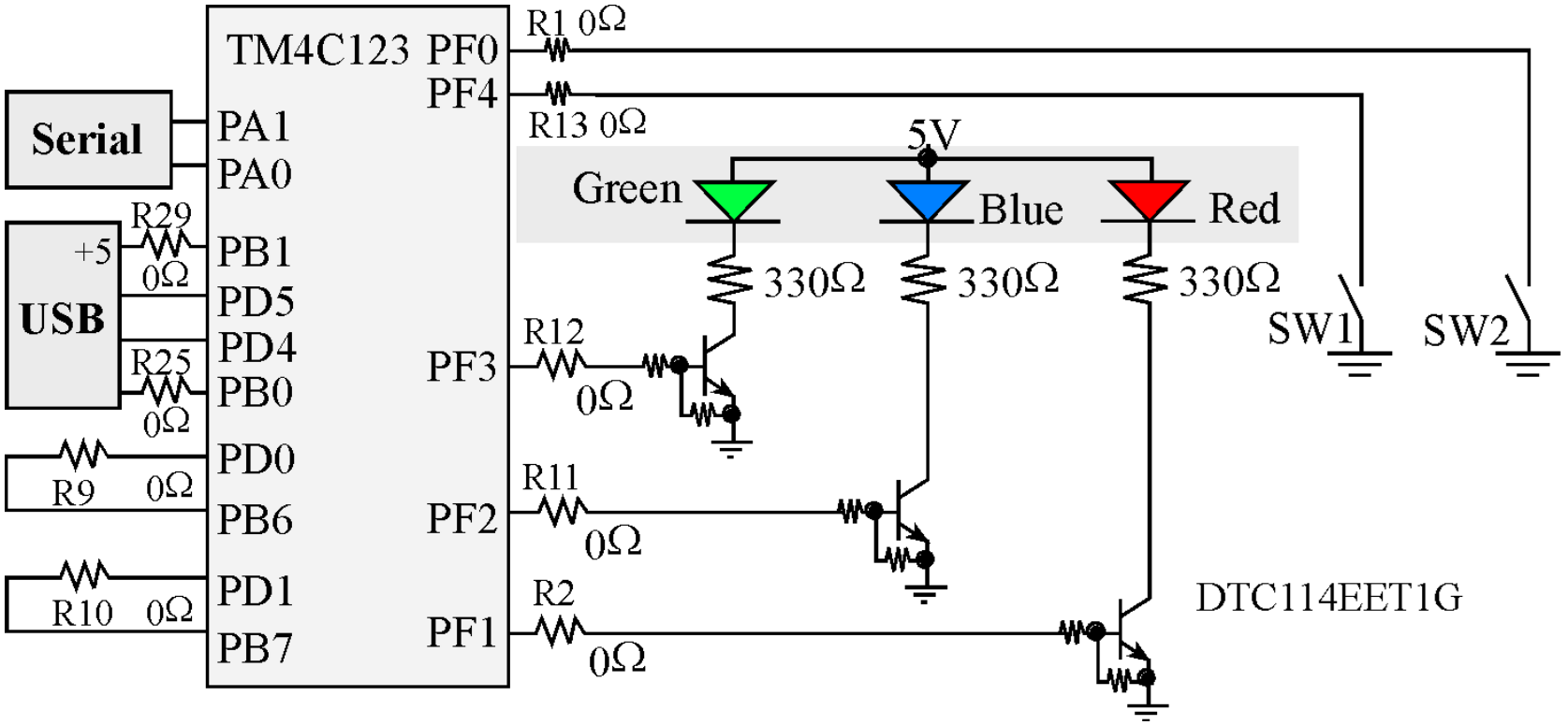
Call by value vs call by reference

```
void swap(int32_t aa, int32_t bb){ int32_t tmp;
    tmp = aa;
    aa = bb;
    bb = tmp;
}
void swap2(int32_t *aa, int32_t *bb){ int32_t tmp;
    tmp = *aa;
    *aa = *bb;
    *bb = tmp;
}
int32_t a=33;
int32_t b=44;
int main(void){

  swap(a,b);
  printf("swap a=%d, b=%d\n",a,b);
  swap2(&a,&b);
  printf("swap2 a=%d, b=%d\n",a,b);
  while(1){};
}
```

Tiva C Board

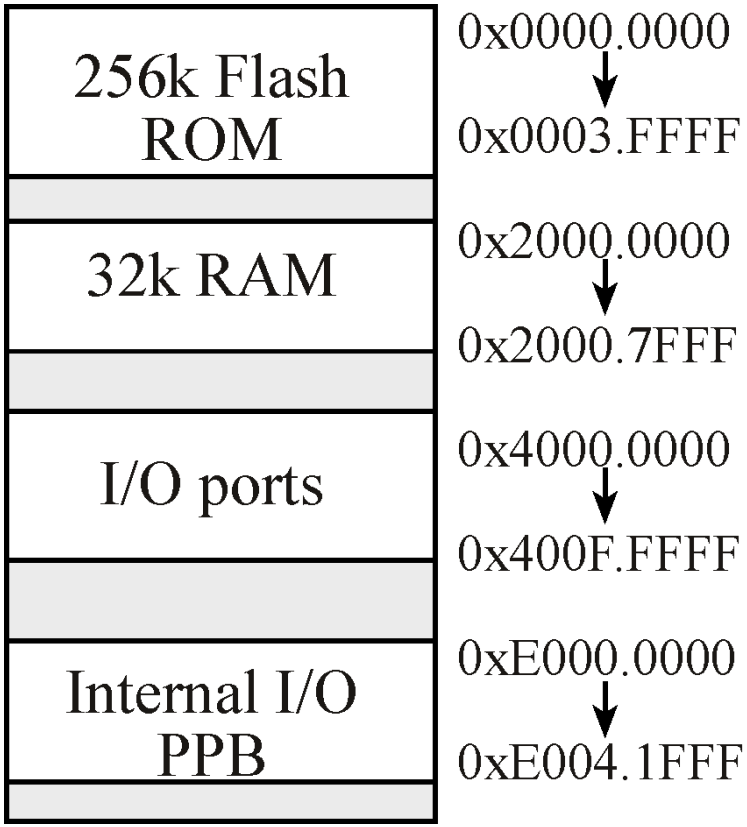

USB ICDI
Debugger
Power selection
Reset
USB device
RGB user LED
J1 J3
J4 J2
LM4F120H5QR
or
TM4C123GH6PM
SW1
SW2
www.ti.com/stellaris-launchpad
EK-LM4F120XL
REV A
TEXAS INSTRUMENTS
Stellaris
LaunchPad

LaunchPad Switches and LEDs



- **The switches on the LaunchPad**
  - **Negative logic**
  - **Require internal pull-up (set bits in PUR)**
- **The PF3-1 LEDs are positive logic**

ARM Memory-map

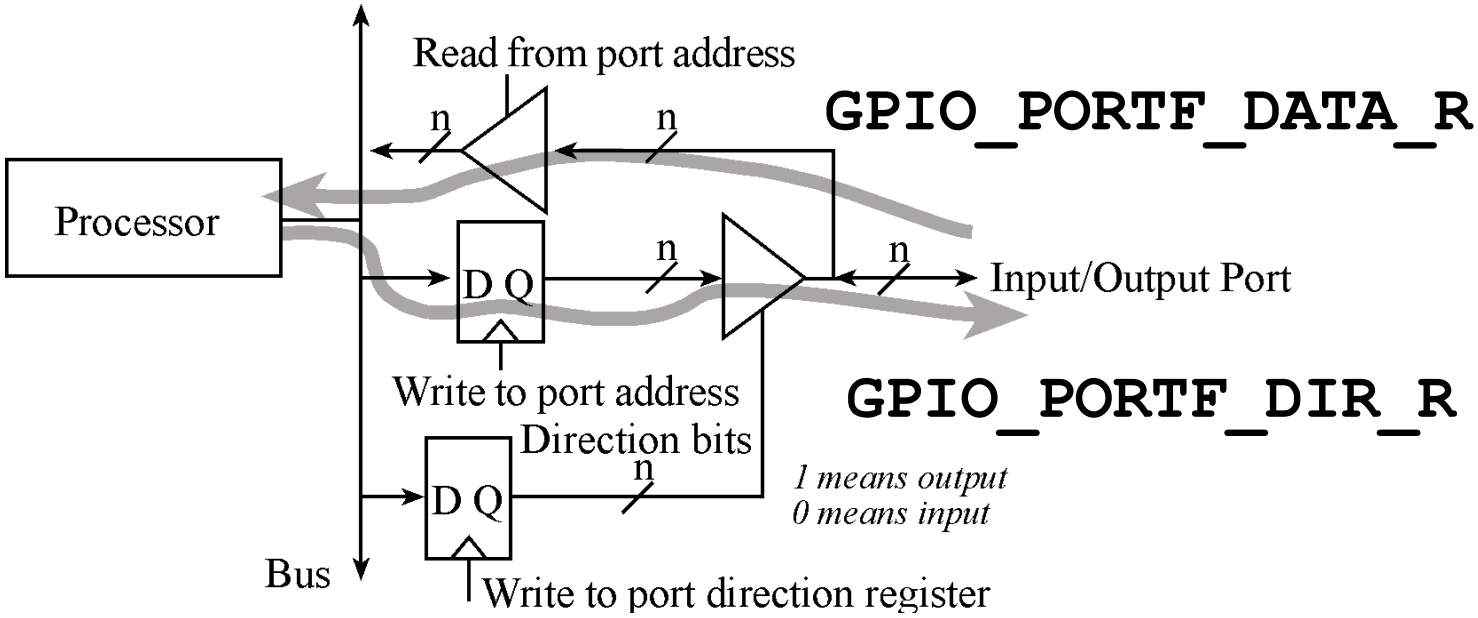


TI TM4C123
Microcontroller

I/O Programming

Address	7	6	5	4	3	2	1	0	Name
$400F.E108	--	--	GPIOF	GPIOE	GPIOD	GPIOC	GPIOB	GPIOA	SYSCTL_RCGC2_R
$4000.43FC	DATA	DATA	DATA	DATA	DATA	DATA	DATA	DATA	GPIO_PORTA_DATA_R
$4000.4400	DIR	DIR	DIR	DIR	DIR	DIR	DIR	DIR	GPIO_PORTA_DIR_R
$4000.4420	SEL	SEL	SEL	SEL	SEL	SEL	SEL	SEL	GPIO_PORTA_AFSEL_R
$4000.4510	PUE	PUE	PUE	PUE	PUE	PUE	PUE	PUE	GPIO_PORTA_PUR_R
$4000.451C	DEN	DEN	DEN	DEN	DEN	DEN	DEN	DEN	GPIO_PORTA_DEN_R
$4000.4524	1	1	1	1	1	1	1	1	GPIO_PORTA_CR_R
$4000.4528	0	0	0	0	0	0	0	0	GPIO_PORTA_AMSEL_R
$4000.53FC	DATA	DATA	DATA	DATA	DATA	DATA	DATA	DATA	GPIO_PORTB_DATA_R
$4000.5400	DIR	DIR	DIR	DIR	DIR	DIR	DIR	DIR	GPIO_PORTB_DIR_R
$4000.5420	SEL	SEL	SEL	SEL	SEL	SEL	SEL	SEL	GPIO_PORTB_AFSEL_R
$4000.5510	PUE	PUE	PUE	PUE	PUE	PUE	PUE	PUE	GPIO_PORTB_PUR_R
$4000.551C	DEN	DEN	DEN	DEN	DEN	DEN	DEN	DEN	GPIO_PORTB_DEN_R
$4000.5524	1	1	1	1	1	1	1	1	GPIO_PORTB_CR_R
$4000.5528	0	0	AMSEL	AMSEL	0	0	0	0	GPIO_PORTB_AMSEL_R
$4000.63FC	DATA	DATA	DATA	DATA	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_DATA_R
$4000.6400	DIR	DIR	DIR	DIR	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_DIR_R
$4000.6420	SEL	SEL	SEL	SEL	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_AFSEL_R
$4000.6510	PUE	PUE	PUE	PUE	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_PUR_R
$4000.651C	DEN	DEN	DEN	DEN	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_DEN_R
$4000.6524	1	1	1	1	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_CR_R
$4000.6528	AMSEL	AMSEL	AMSEL	AMSEL	JTAG	JTAG	JTAG	JTAG	GPIO_PORTC_AMSEL_R
$4000.73FC	DATA	DATA	DATA	DATA	DATA	DATA	DATA	DATA	GPIO_PORTD_DATA_R
$4000.7400	DIR	DIR	DIR	DIR	DIR	DIR	DIR	DIR	GPIO_PORTD_DIR_R

I/O Ports and Control Registers



The input/output direction of a bidirectional port is specified by its direction register.

GPIO_PORTF_DIR_R , specify if corresponding pin is input or output:

- 0 means input
- 1 means output

PORTA

```
GPIO_PORTA_DATA_R       EQU   0x400043FC
GPIO_PORTA_DIR_R        EQU   0x40004400
```

GPIO Control

IO	Ain	0	1	2	3	4	5	6	7	8	9	14
PA0		*Port*	*U0Rx*							CAN1Rx		
PA1		*Port*	*U0Tx*							CAN1Tx		
PA2		Port		SSI0Clk								
PA3		Port		SSI0Fss								
PA4		Port		SSI0Rx								
PA5		Port		SSI0Tx								
PA6		Port			I_2C1SCL		M1PWM2					
PA7		Port			I_2C1SDA		M1PWM3					
PB0		Port	U1Rx						T2CCP0			
PB1		Port	U1Tx						T2CCP1			
PB2		Port			I_2C0SCL				T3CCP0			

I/O Programming & Direction Register

GPIO_PORTF_DIR_R	**Which pins are input or output.**
GPIO_PORTF_AFSEL_R	**Activate the alternate functions**
GPIO_PORTF_DEN_R:	**Digital port**
GPIO_PORTF_DATA_R	**Perform input/output on the port.**

Set Port Direction & Port Type

```
LDR     R1,= GPIO_PORTF_DIR_R
MOV     R0,#0x0E
STR     R0,[R1]

LDR     R1,=GPIO_PORTF_DEN_R
MOV     R0,#0xFF
STR     R0,[R1]
```

Set Port Direction & Port Type

```
GPIO_PORTF_DIR_R = 0x0E;          // PF4,PF0 in, PF3-1 out
GPIO_PORTF_AFSEL_R = 0x00;        // disable alt funct on PF7-0
GPIO_PORTF_DEN_R = 0x1F;          // enable digital I/O on PF4-0
```

I/O Ports and Control Registers

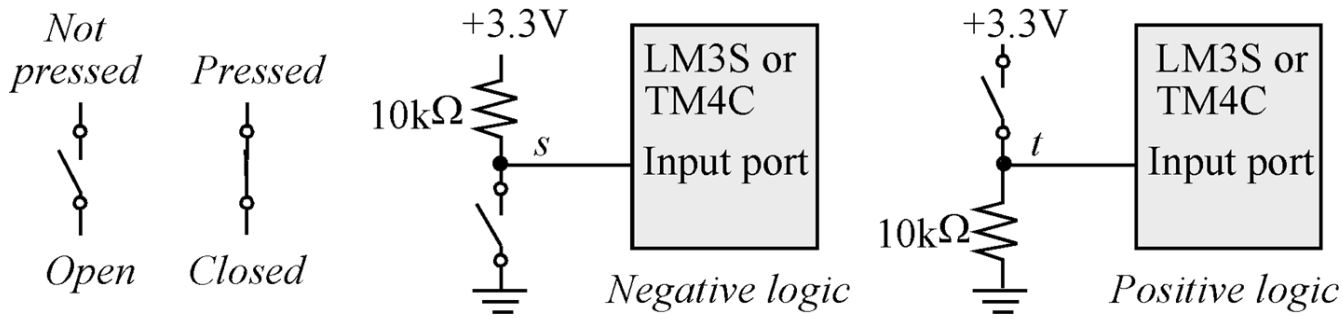
Address	7	6	5	4	3	2	1	0	Name
400F.E608	-	-	**GPIOF**	GPIOE	GPIOD	GPIOC	GPIOB	GPIOA	SYSCTL_RCGCGPIO_R
4002.53FC	-	-	-	DATA	DATA	DATA	DATA	DATA	GPIO_PORTF_DATA_R
4002.5400	-	-	-	DIR	DIR	DIR	DIR	DIR	GPIO_PORTF_DIR_R
4002.551C	-	-	-	DEN	DEN	DEN	DEN	DEN	GPIO_PORTF_DEN_R

- **Initialization (executed once at beginning)**
  1. Write *DIR* bit, 1 for output or 0 for input
  2. Set *DEN* bits to 1 to enable data pins
- **Input/output from pin**
  Input: Read from **`GPIO_PORTF_DATA_R`**
  Output: Write **`GPIO_PORTF_DATA_R`**

Port F LED Programming

```
DR R1, =GPIO_PORTF_DIR_R        ; R1 -> GPIO_PORTE_DIR_R
MOV R0, #0X0E                     ;PF0 , PF4 in and PF3-1 out
STR R0, [R1]                    ; set direction register

LDR R1, =GPIO_PORTF_DEN_R       ; R1 -> GPIO_PORTE_DEN_R
MOV R0, R0, #0xFF               ; enable digital port
STR R0, [R1]                    ; set digital enable register

LDR R1, =GPIO_PORTF_DATA_R
MOV R0,#0x02
STR R0,[R1]
```

Switch Interfacing



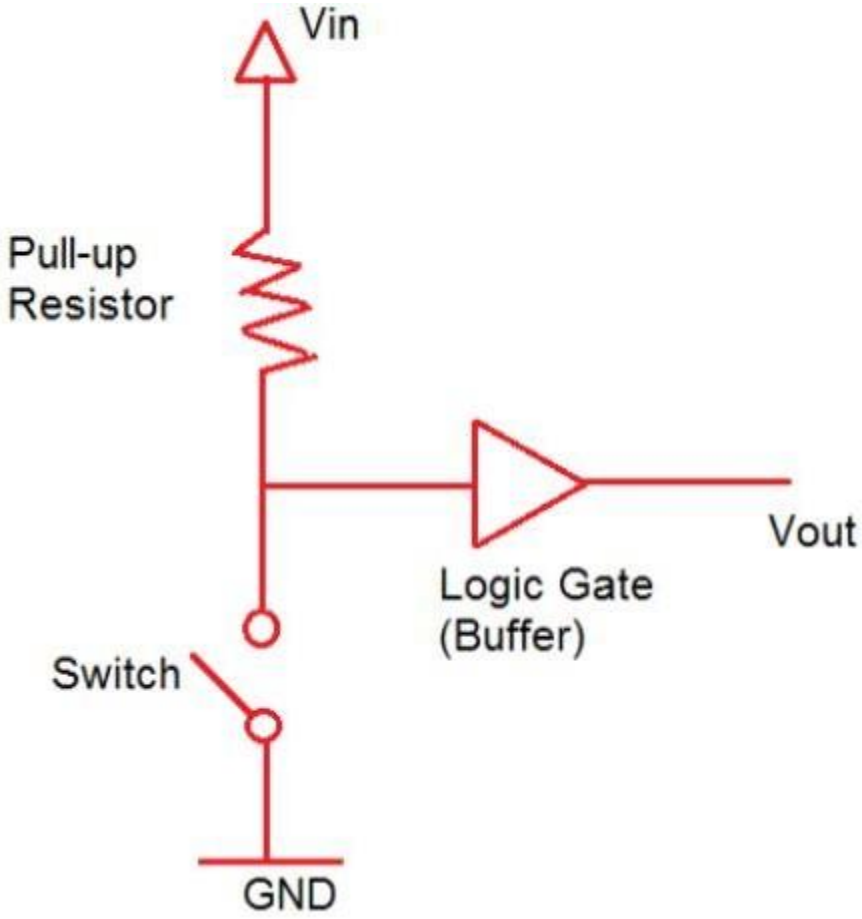
Assembly:

```
LDR   R1,=GPIO_PORTF_DATA_R
LDR   R0,[R1]        ; read port F
AND   R0,R0,#0x11    ; PF4-PF0
```

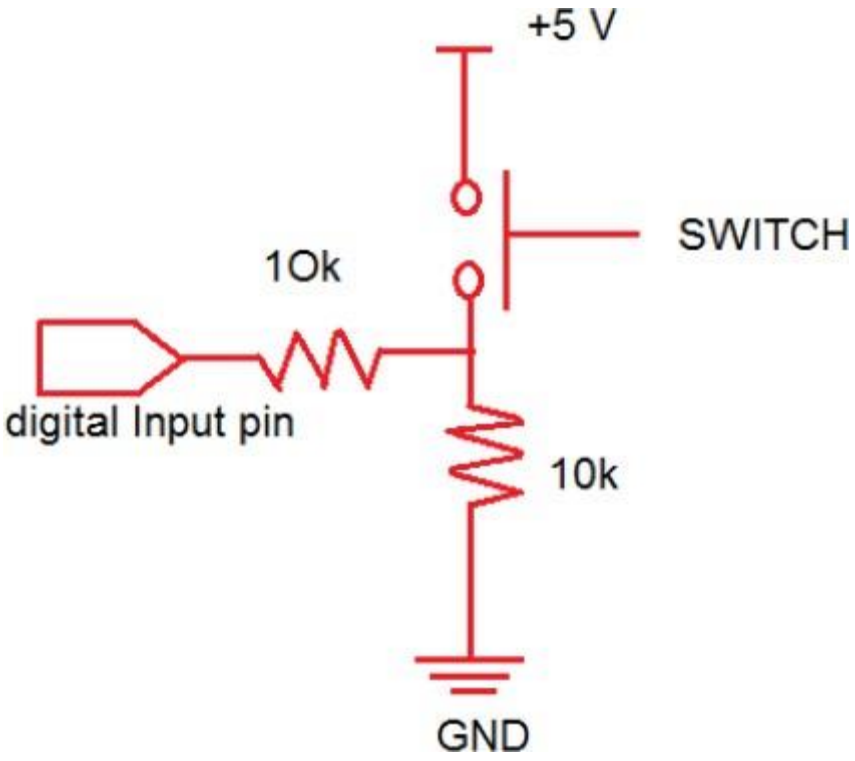
I/O Programming ARM

```
PortF_Init
        LDR R1, =SYSCTL_RCGCGPIO_R ; activate Port F
        LDR R0, [R1]
        ORR R0, R0, #0x20 ; set bit 5 to activate Port F
        STR R0, [R1]
        NOP
        NOP ; allow time for Port F activation
        LDR R1, =GPIO_PORTF_CR_R ; allow change to Port F
        MOV R0, #0xFF ; 1 means allow access
        STR R0, [R1]
        LDR R1, =GPIO_PORTF_DIR_R ; 5) set direction register
        MOV R0, #0x0E ; PF0 and PF7-4 input, PF3-1 output
        STR R0, [R1]
```

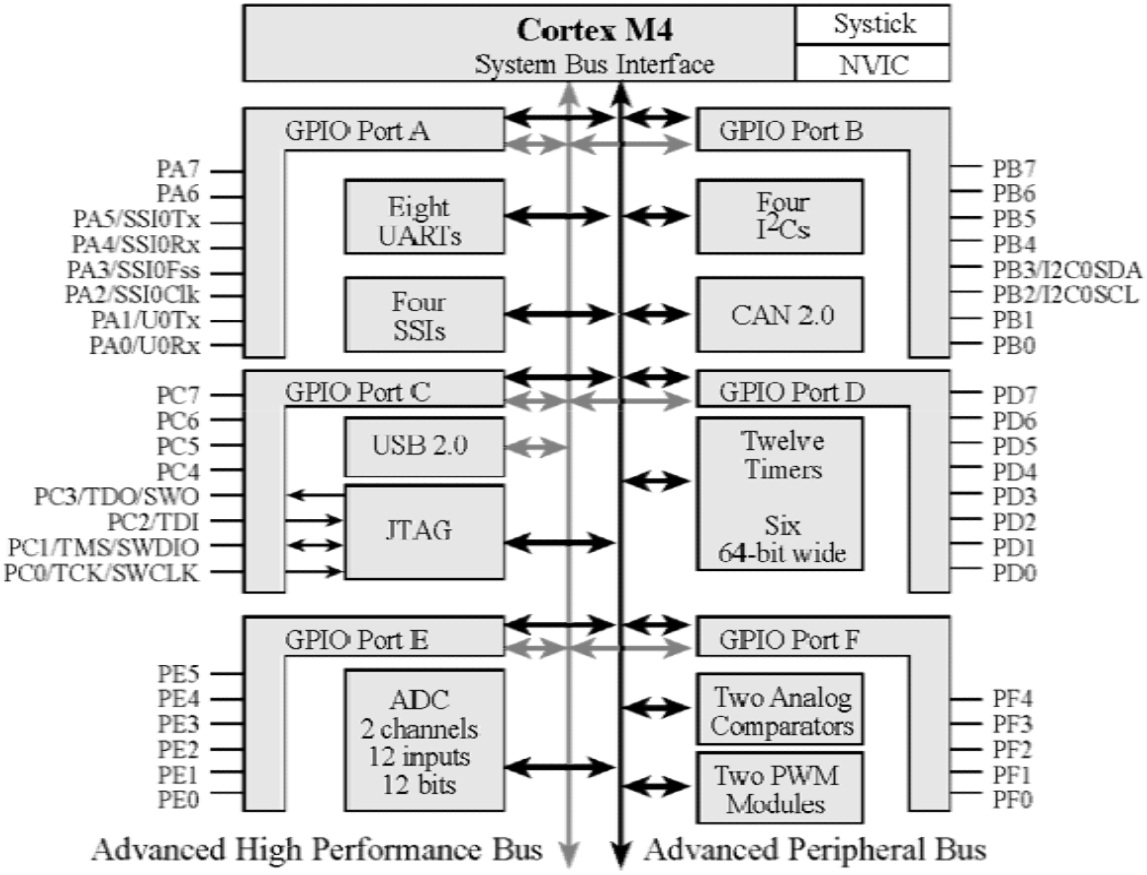
Pull-up resistor



Pull-down resistor



Texas Instruments TM4C123



SYSCTL_PRGPIO_R

Address	7	6	5	4	3	2	1	0	Name
$400F.E608	-	-	GPIOF	GPIOE	GPIOD	GPIOC	GPIOB	GPIOA	SYSCTL_RCGCGPIO_R
$400F.EA08	-	-	GPIOF	GPIOE	GPIOD	GPIOC	GPIOB	GPIOA	SYSCTL_PRGPIO_R
4000.43FC	DATA	DATA	DATA	DATA	DATA	DATA	DATA	DATA	GPIO_PORTA_DATA_R
		DIR	DIR	DIR	DIR	DIR	DIR	DIR	GPIO_PORTA_DIR_R

I/O Programming ARM

```
    LDR R1, =GPIO_PORTF_PUR_R ; pull-up resistors for PF4,PF0
    MOV R0, #0x11 ; enable pull-up on PF0 and PF4
    STR R0, [R1]
    LDR R1, =GPIO_PORTF_DEN_R ; enable Port F digital
    MOV R0, #0xFF ; 1 means enable digital I/O
    STR R0, [R1]
    BX LR
PortF_Input
    LDR R1, =GPIO_PORTF_DATA_R ; pointer to Port F data
    LDR R0, [R1] ; read all of Port F
    AND R0,R0,#0x11 ; just the input pins, bits 4,0
    BX LR ; return R0 with inputs
Port F_Output
    LDR R1, =GPIO_PORTF_DATA_R ; pointer to Port Fdata
    STR R0, [R1] ; write to PF3-1
    BX LR
```

I/O Programming

```
#define GPIO_PORTF_DATA_R (*((volatile unsigned long *) 0x400253FC))

#define GPIO_PORTF_DEN_R (*((volatile unsigned long *) 0x4002551C))
```

I/O Programming C

```
#include "inc/tm4c123gh6pm.h"
void PortF_Init(void){
    SYSCTL_RCGCGPIO_R |= 0x00000020; // activate Port F
    while((SYSCTL_PRGPIO_R&0x00000020) == 0){};
    GPIO_PORTF_CR_R = 0x1F; // allow changes to PF4-0
    GPIO_PORTF_DIR_R = 0x0E; // PF4,PF0 in, PF3-1 out
    GPIO_PORTF_PUR_R = 0x11; // pull-up on PF0 and PF4
    GPIO_PORTF_DEN_R = 0x1F; // digital I/O on PF4-0
}
uint32_t PortF_Input(void){
    return (GPIO_PORTF_DATA_R&0x11); // read PF4,PF0
    inputs
}
void PortF_Output(uint32_t data){ // write PF3-PF1 outputs
    GPIO_PORTF_DATA_R = data;
}
```

For Loops for time delay

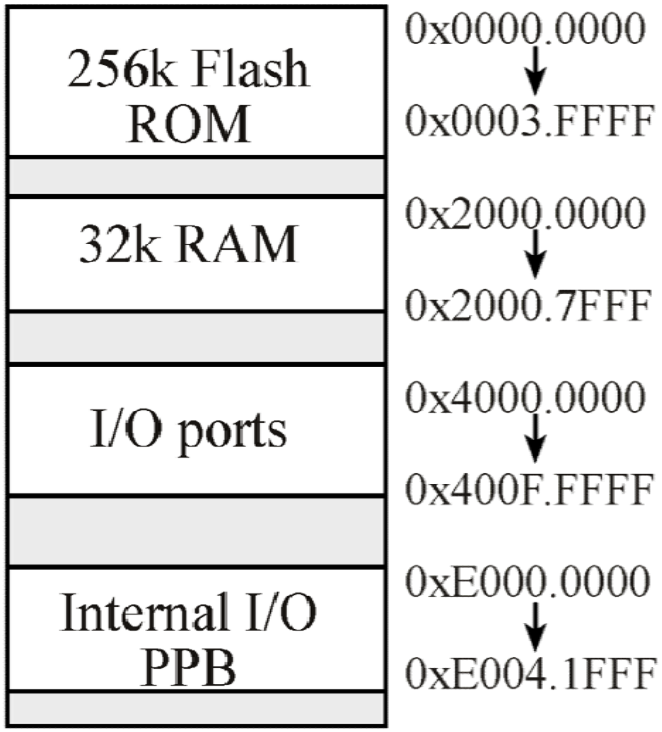
```
Delay SUBS R0,R0,#1
      BNE  Delay
      BX   LR

Main  BL   LED_Init
Loop  MOV  R0,#1
      BL   LED_Out
      LDR  R0,=250000
      BL   Delay
      MOV  R0,#0
      BL   LED_Out
      LDR  R0,=250000
      BL   Delay
      B    Loop
```

```
void Delay(uint32_t time){
  while(time){
    time--;
   }
}
int main(void){
  LED_Init();
  while(1){
    LED_Out(1);
    Delay(2500000);
    LED_Out(0);
    Delay(2500000);
  }
}
```

SysTick Timer

- Timer/Counter operation
  - 24-bit counter *decrements* at bus clock frequency
    - With 80 MHz bus clock, decrements every 12.5 ns
  - Counting is from *n* → 0

ARM Memory-map



TI TM4C123
Microcontroller

SysTick Timer

Address	31-24	23-17	16	15-3	2	1	0	Name
$E000E010	0	0	COUNT	0	CLK_SRC	INTEN	ENABLE	NVIC_ST_CTRL_R
$E000E014	0	24-bit RELOAD value						NVIC_ST_RELOAD_R
$E000E018	0	24-bit CURRENT value of SysTick counter						NVIC_ST_CURRENT_R

- Initialization (4 steps)
  - Step1: Clear ENABLE to stop counter
  - Step2: Specify the RELOAD value
  - Step3: Clear the counter via NVIC_ST_CURRENT_R
  - Step4: Set NVIC_ST_CTRL_R
    - CLK_SRC = 1 (bus clock is the only option)
    - INTEN = 0 for no interrupts
    - ENABLE = 1 to enable

SysTick Timer Registers

```
#define NVIC_ST_CTRL_R(*((volatile uint32_t *)0xE000E010))

#define NVIC_ST_RELOAD_R(*((volatile uint32_t *)0xE000E014))

#define NVIC_ST_CURRENT_R(*((volatile uint32_t *)0xE000E018))
```

SysTick Timer Example

```
void SysTick_Init(void){
 NVIC_ST_CTRL_R = 0; // 1) disable SysTick during setup
 NVIC_ST_RELOAD_R = 0x00FFFFFF; // 2) maximum reload value
 NVIC_ST_CURRENT_R = 0; // 3) any write to CURRENT clears it
 NVIC_ST_CTRL_R = 0x00000005; // 4) enable SysTick with core clock
}

// The delay parameter is in units of the 80 MHz core clock(12.5 ns)
void SysTick_Wait(uint32_t delay){
  NVIC_ST_RELOAD_R = delay-1;  // number of counts
  NVIC_ST_CURRENT_R = 0;       // any value written to CURRENT clears
  while((NVIC_ST_CTRL_R&0x00010000)==0){ // wait for flag
  }
}
// Call this routine to wait for delay*10ms
void SysTick_Wait10ms(uint32_t delay){
unsigned long i;
 for(i=0; i<delay; i++){
   SysTick_Wait(800000); // wait 10ms
}
```

SysTick Timer

24-bit Countdown Timer

```
SysTick_Init
; disable SysTick during setup
    LDR R1, =NVIC_ST_CTRL_R
    MOV R0, #0              ; Clear Enable
    STR R0, [R1]
; set reload to maximum reload value
    LDR R1, =NVIC_ST_RELOAD_R
    LDR R0, =0x00FFFFFF;    ; Specify RELOAD value
    STR R0, [R1]            ; reload at maximum
; writing any value to CURRENT clears it
    LDR  R1,  =NVIC_ST_CURRENT_R
    MOV  R0,  #0
    STR  R0,  [R1]                ; clear    counter
;  enable SysTick with core clock
    LDR R1, =NVIC_ST_CTRL_R
    MOV R0, #0x0005       ; Enable but     no interrupts (later)
    STR R0, [R1]          ; ENABLE and     CLK_SRC bits set
    BX  LR
```

SysTick Timer

```
;_____________SysTick_Wait_____________
; Time delay using busy wait.
; Input: R0  delay parameter in units of the core clock
;        80 MHz(12.5 nsec each tick)
; Output: none
; Modifies: R1
SysTick_Wait
    SUB  R0, R0, #1    ; delay-1
    LDR  R1, =NVIC_ST_RELOAD_R
    STR  R0, [R1]      ; time to wait
    LDR  R1, =NVIC_ST_CURRENT_R
    STR  R0, [R1]      ; any value written to CURRENT clears
    LDR  R1, =NVIC_ST_CTRL_R
SysTick_Wait_loop
    LDR  R0, [R1]      ; read status
    ANDS R0, R0, #0x00010000 ; bit 16 is COUNT flag
    BEQ  SysTick_Wait_loop   ; repeat until flag set
    BX   LR
```

SysTick Timer

```
;_____SysTick_Wait10ms_____
; Call this routine to wait for R0*10 ms
; Time delay using busy wait. This assumes 80 MHz clock
; Input: R0  number of times to wait 10 ms before returning
; Output: none
; Modifies: R0
DELAY10MS              EQU 800000   ; clock cycles in 10 ms
SysTick_Wait10ms
    PUSH {R4, LR}                   ; save R4 and LR
    MOVS R4, R0                     ; R4 = R0 = remainingWaits
    BEQ SysTick_Wait10ms_done       ; R4 == 0, done
SysTick_Wait10ms_loop
    LDR R0, =DELAY10MS              ; R0 = DELAY10MS
    BL  SysTick_Wait                ; wait 10 ms
    SUBS R4, R4, #1                 ; remainingWaits--
    BHI SysTick_Wait10ms_loop       ; if(R4>0), wait another 10 ms
SysTick_Wait10ms_done
    POP {R4, PC}
```

SysTick Timer

Address	31-24	23-17	16	15-3	2	1	0	Name
$E000E010	0	0	COUNT	0	CLK_SRC	INTEN	ENABLE	NVIC_ST_CTRL_R
$E000E014	0	24-bit RELOAD value						NVIC_ST_RELOAD_R
$E000E018	0	24-bit CURRENT value of SysTick counter						NVIC_ST_CURRENT_R

- Initialization (4 steps)
  - Step1: Clear ENABLE to stop counter
  - Step2: Specify the RELOAD value
  - Step3: Clear the counter via NVIC_ST_CURRENT_R
  - Step4: Set NVIC_ST_CTRL_R
    - CLK_SRC = 1 (bus clock is the only option)
    - INTEN = 0 for no interrupts
    - ENABLE = 1 to enable

SysTick Timer

24-bit Countdown Timer

```
SysTick_Init
; disable SysTick during setup
    LDR R1, =NVIC_ST_CTRL_R
    MOV R0, #0              ; Clear Enable
    STR R0, [R1]
; set reload to maximum reload value
    LDR R1, =NVIC_ST_RELOAD_R
    LDR R0, =0x00FFFFFF;    ; Specify RELOAD value
    STR R0, [R1]            ; reload at maximum
; writing any value to CURRENT clears it
    LDR  R1,  =NVIC_ST_CURRENT_R
    MOV  R0,  #0
    STR  R0,  [R1]                ; clear    counter
;  enable SysTick with core clock
    LDR R1, =NVIC_ST_CTRL_R
    MOV R0, #0x0005       ; Enable but     no interrupts (later)
    STR R0, [R1]          ; ENABLE and     CLK_SRC bits set
    BX  LR
```

SysTick Timer

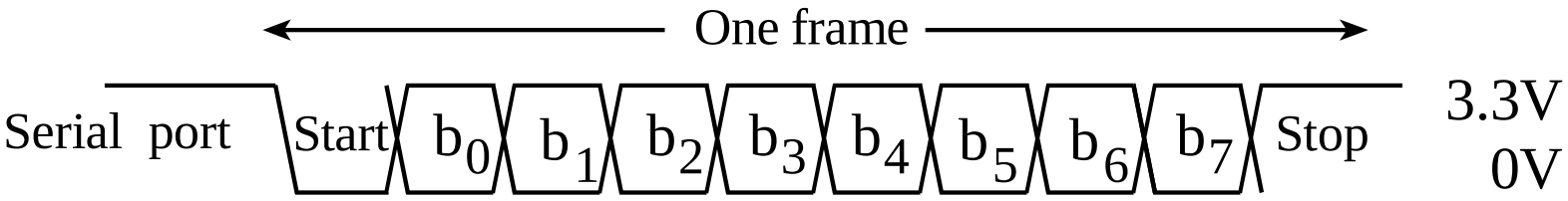
```
;_____________SysTick_Wait_____________
; Time delay using busy wait.
; Input: R0  delay parameter in units of the core clock
;        80 MHz(12.5 nsec each tick)
; Output: none
; Modifies: R1
SysTick_Wait
    SUB  R0, R0, #1    ; delay-1
    LDR  R1, =NVIC_ST_RELOAD_R
    STR  R0, [R1]      ; time to wait
    LDR  R1, =NVIC_ST_CURRENT_R
    STR  R0, [R1]      ; any value written to CURRENT clears
    LDR  R1, =NVIC_ST_CTRL_R
SysTick_Wait_loop
    LDR  R0, [R1]      ; read status
    ANDS R0, R0, #0x00010000 ; bit 16 is COUNT flag
    BEQ  SysTick_Wait_loop   ; repeat until flag set
    BX   LR
```

SysTick Timer

```
;_____SysTick_Wait10ms_____
; Call this routine to wait for R0*10 ms
; Time delay using busy wait. This assumes 80 MHz clock
; Input: R0  number of times to wait 10 ms before returning
; Output: none
; Modifies: R0
DELAY10MS              EQU 800000   ; clock cycles in 10 ms
SysTick_Wait10ms
    PUSH {R4, LR}                   ; save R4 and LR
    MOVS R4, R0                     ; R4 = R0 = remainingWaits
    BEQ SysTick_Wait10ms_done       ; R4 == 0, done
SysTick_Wait10ms_loop
    LDR R0, =DELAY10MS              ; R0 = DELAY10MS
    BL  SysTick_Wait                ; wait 10 ms
    SUBS R4, R4, #1                 ; remainingWaits--
    BHI SysTick_Wait10ms_loop       ; if(R4>0), wait another 10 ms
SysTick_Wait10ms_done
    POP {R4, PC}
```

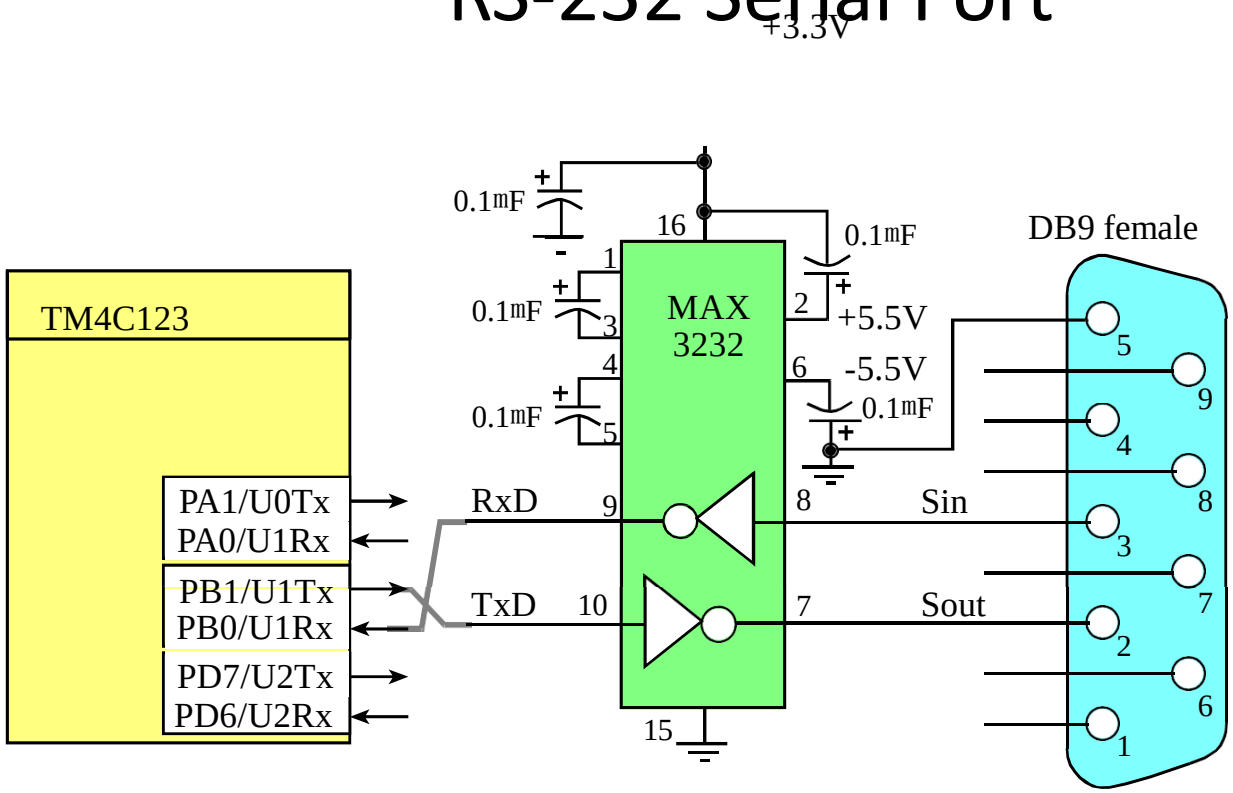
Universal Asynchronous Receiver/Transmitter (UART)

- UART (Serial Port) Interface



  - Send/receive a *frame* of (5-8) data bits with a single (start) bit prefix and a 1 or 2 (stop) bit suffix
  - Baud rate is total number of bits per unit time
    - Baudrate = 1 / bit-time
  - Bandwidth is data per unit time
    - Bandwidth = (data-bits / frame-bits) * baudrate

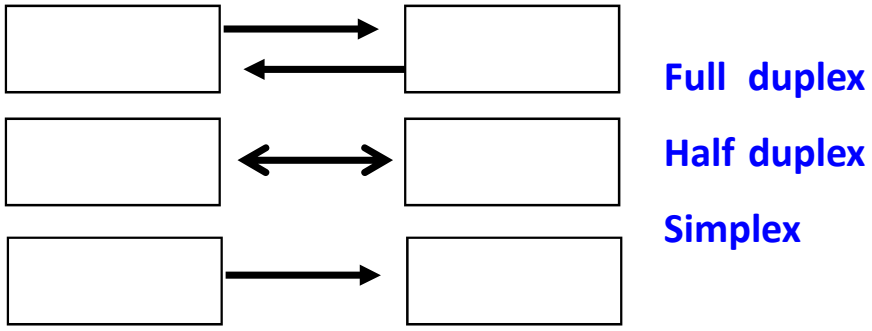
RS-232 Serial Port



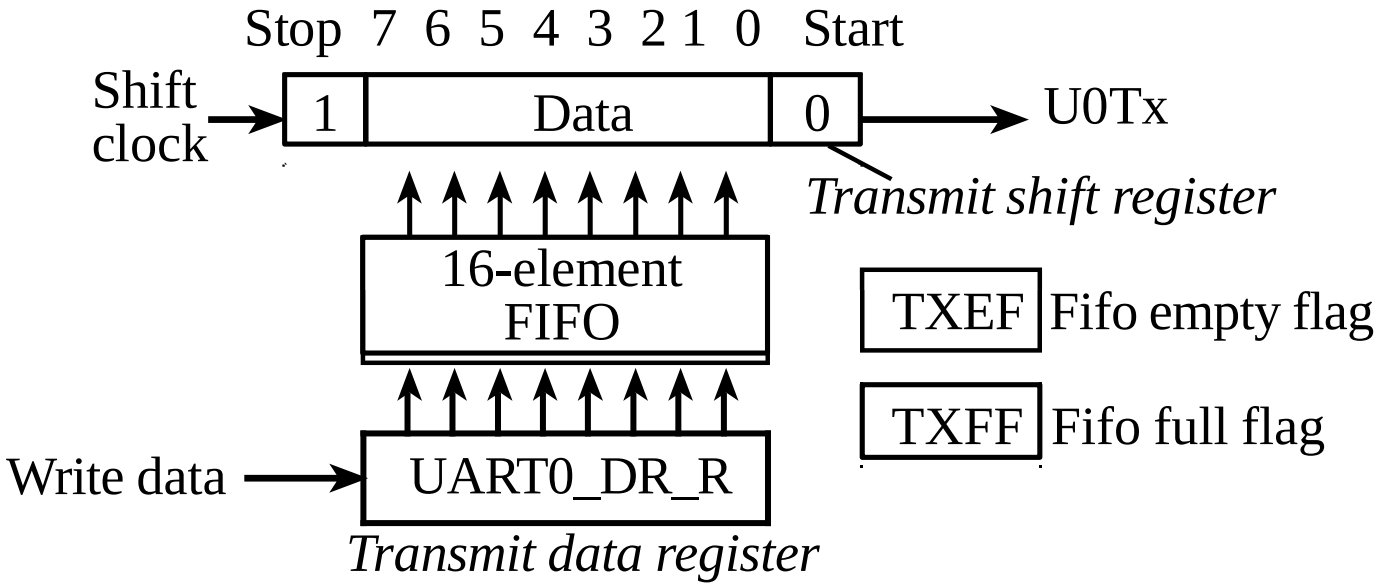
DB25 Pin	RS232 Name	DB9 Pin	EIA-574 Name	Signal	Description	True	DTE	DCE
2	BA	3	103	TxD	Transmit Data	-5.5V	out	in
3	BB	2	104	RxD	Receive Data	-5.5V	in	out
7	AB	5	102	SG	Signal Ground			

Serial I/O

- Serial communication
  - Transmit Data (TxD), Receive Data (RxD), and Signal Ground (SG) implement *duplex* communication link
  - Both communicating devices must operate at the same bit rate



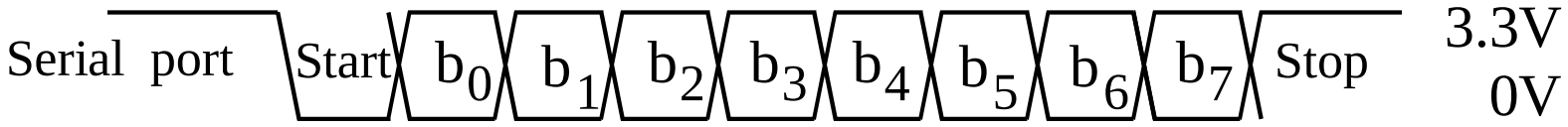
UART - Transmitter



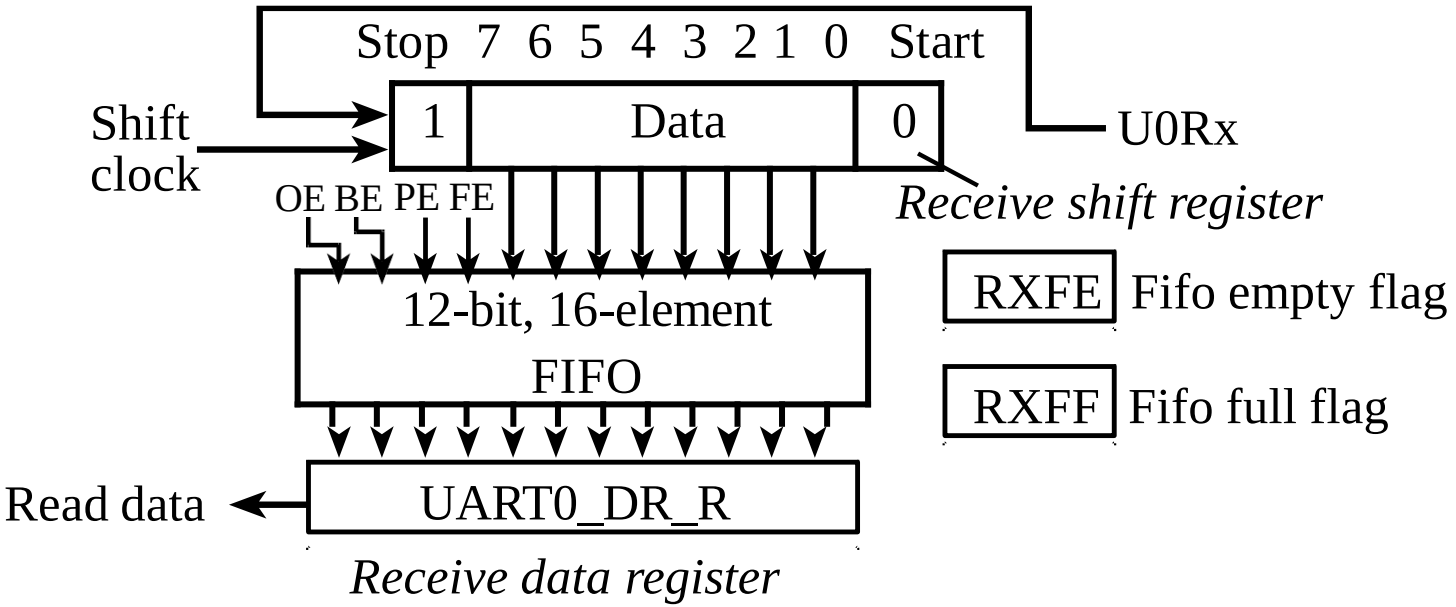
UART - Transmitter

- Tx Operation
  - Data written to UART0_DR_R
    - passes through 16-element FIFO
    - permits small amount of data rate matching between processor and UART
  - Shift clock is generated from 16x clock
    - permits difference 

Rx clocks to be reconciled

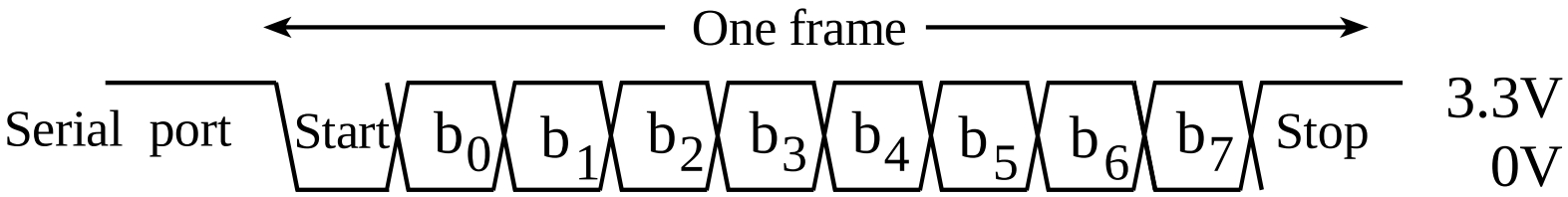


UART - Receiver

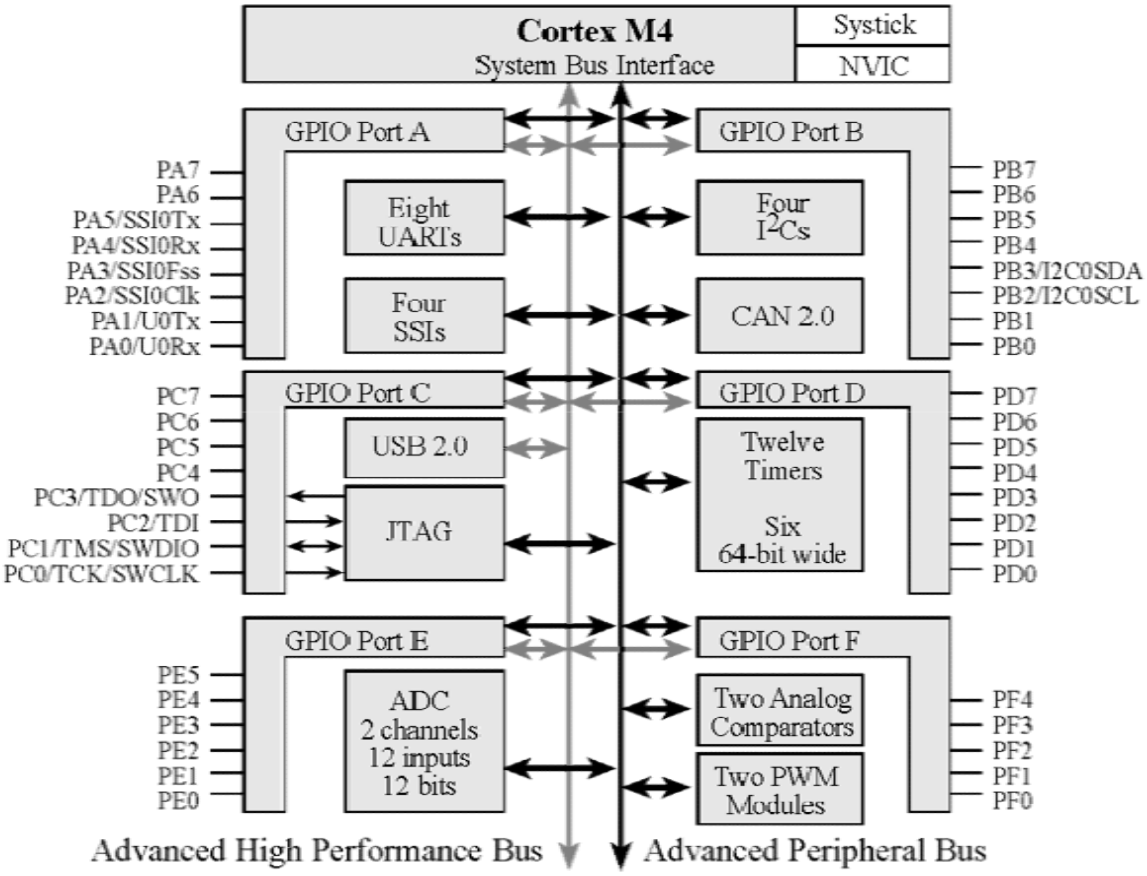


UART - Receiver

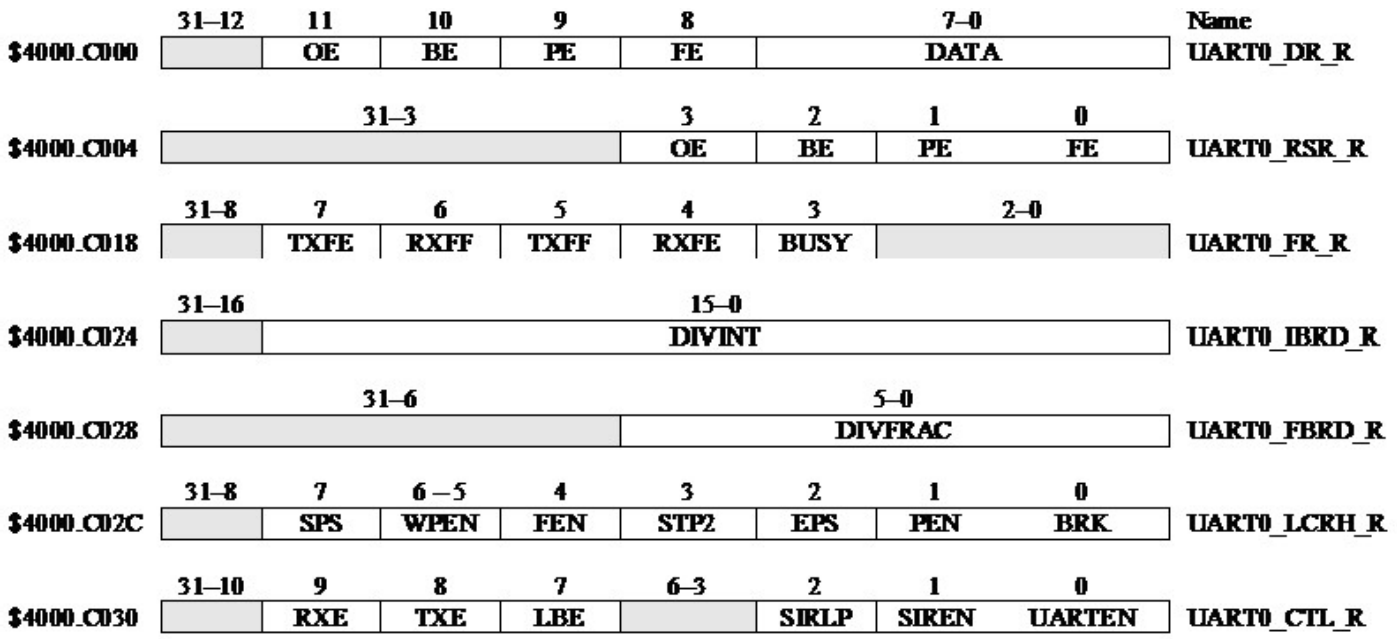
- Rx Operation
  - **RXFE** is 0 when data are available
  - **RXFF** is 1 when FIFO is full
  - FIFO entries have four control bits
    - **BE** set when Tx signal held low for more than one frame (break)
    - **OE** set when FIFO is full and new frame has arrived
    - **PE** set if frame parity error
    - **FE** set if stop bit timing error



Texas Instruments TM4C123



TM4C UART0 – Registers



GPIOPCTL Register

IO	Ain	0	1	2	3	4	5	6	7	8	9	14
PA2		Port		SSI0Clk								
PA3		Port		SSI0Fss								
PA4		Port		SSI0Rx								
PA5		Port		SSI0Tx								
PA6		Port			I_2C1SCL		M1PWM2					
PA7		Port			I_2C1SDA		M1PWM3					
PB0		Port	U1Rx						T2CCP0			
PB1		Port	U1Tx						T2CCP1			
PB2		Port			I_2C0SCL				T3CCP0			
PB3		Port			I_2C0SDA				T3CCP1			
PB4	Ain10	Port		SSI2Clk		M0PWM2			T1CCP0	CAN0Rx		
PB5	Ain11	Port		SSI2Fss		M0PWM3			T1CCP1	CAN0Tx		
PB6		Port		SSI2Rx		M0PWM0			T0CCP0			
PB7		Port		SSI2Tx		M0PWM1			T0CCP1			
PC4	C1-	Port	U4Rx	U1Rx		M0PWM6		IDX1	WT0CCP0	U1RTS		
PC5	C1+	Port	U4Tx	U1Tx		M0PWM7		PhA1	WT0CCP1	U1CTS		
PC6	C0+	Port	U3Rx					PhB1	WT1CCP0	USB0epen		
PC7	C0-	Port	U3Tx						WT1CCP1	USB0pflt		
PD0	Ain7	Port	SSI3Clk	SSI1Clk	I_2C3SCL	M0PWM6	M1PWM0		WT2CCP0			
PD1	Ain6	Port	SSI3Fss	SSI1Fss	I_2C3SDA	M0PWM7	M1PWM1		WT2CCP1			
PD2	Ain5	Port	SSI3Rx	SSI1Rx		M0Fault0			WT3CCP0	USB0epen		
PD3	Ain4	Port	SSI3Tx	SSI1Tx				IDX0	WT3CCP1	USB0pflt		
PD6		Port	U2Rx			M0Fault0		PhA0	WT5CCP0			
PD7		Port	U2Tx					PhB0	WT5CCP1	NMI		
PE0	Ain3	Port	U7Rx									
PE1	Ain2	Port	U7Tx									
PE2	Ain1	Port										
PE3	Ain0	Port										
PE4	Ain9	Port	U5Rx		I_2C2SCL	M0PWM4	M1PWM2			CAN0Rx		
PE5	Ain8	Port	U5Tx		I_2C2SDA	M0PWM5	M1PWM3			CAN0Tx		
PF0		Port	U1RTS	SSI1Rx	CAN0Rx		M1PWM4	PhA0	T0CCP0	NMI	C0o	
PF1		Port	U1CTS	SSI1Tx			M1PWM5	PhB0	T0CCP1		C1o	TRD1
PF2		Port		SSI1Clk		M0Fault0	M1PWM6		T1CCP0			TRD0
PF3		Port		SSI1Fss	CAN0Tx		M1PWM7		T1CCP1			TRCLK
PF4							M1Fault0	IDX0	T2CCP0	USB0epen		

TM4C UART Setup

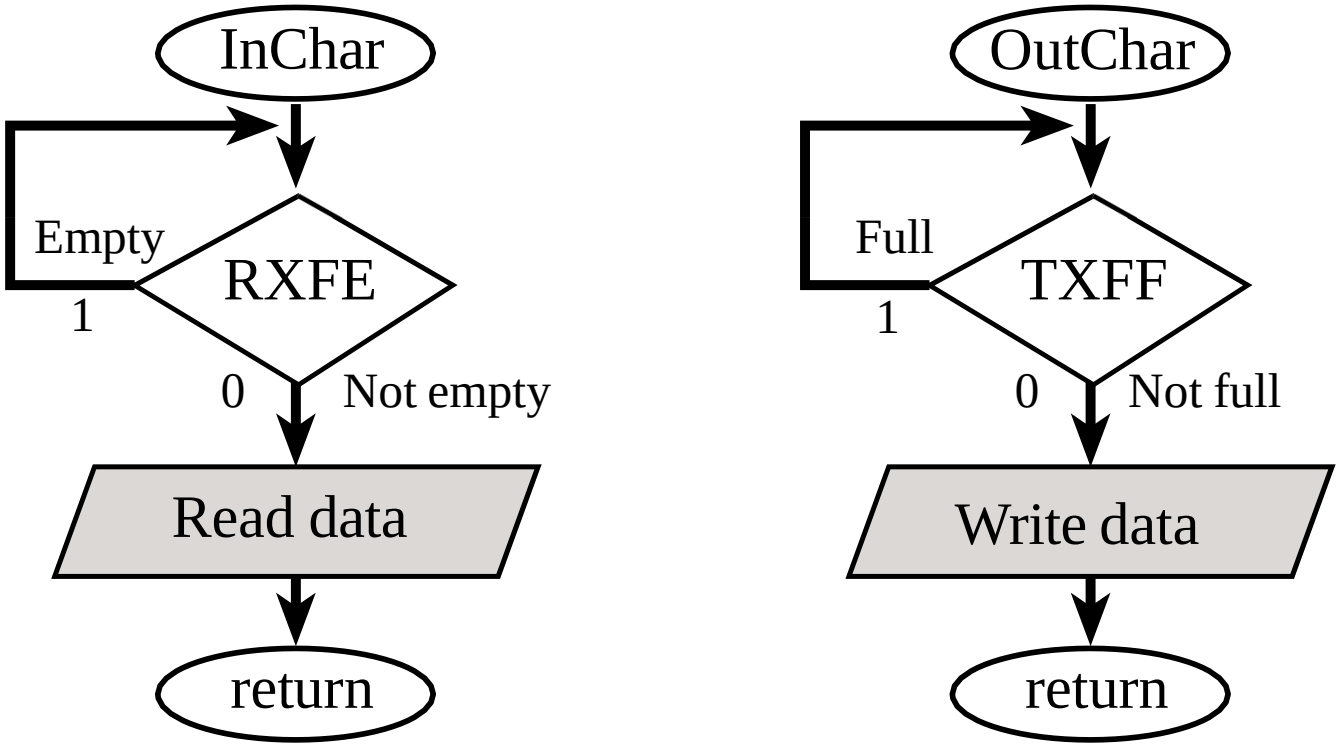
- UART0 operation
  - UART clock started in **SYSCTL_RCGCUART_R**
  - Digital port clock started in **SYSCTL_RCGCGPIO_R**
  - **UART0_CTL_R** contains UART enable (UARTEN), Tx (TXE), and Rx enable (RXE)
    - set each to 1 to enable
    - **UART disabled during initialization**
  - **UART1_IBRD_R** and **UART1_FBRD_R** specify baud rate
    - bit rate = (bus clock frequency)/(16*divider)
    - ex: want 19.2 kb/s and bus clock is 80 MHz
    - 80 MHz/(16*19.2 k) = 26.04167 = 11010.000011_2
    - Tx and Rx clock rates must be within 5% to avoid errors
  - **GPIO_PORTC_AFSEL_R** to choose alternate function
  - **GPIO_PORTC_DEN_R** Enable digital I/O on pins 1-0
  - **GPIO_PORTC_AMSEL_R** no Analog I/O on pins 1-0
  - **write to UART0_LCRH_R to activate**

TM4C UART Programming

```
// Assumes a 80 MHz bus clock, creates 115200 baud rate
void UART_Init(void){              // should be called only once
  SYSCTL_RCGCUART_R |= 0x00000002;  // activate UART1
  SYSCTL_RCGCGPIO_R |= 0x00000004;  // activate port C
  UART1_CTL_R &= ~0x00000001;     // disable UART
  UART1_IBRD_R = 43;      // IBRD = int(80,000,000/(16*115,200)) = int(43.40278)
  UART1_FBRD_R = 26;      // FBRD = round(0.40278 * 64) = 26
  UART1_LCRH_R = 0x00000070;  // 8 bit, no parity bits, one stop, FIFOs
  UART1_CTL_R |= 0x00000001;      // enable UART
  GPIO_PORTC_AFSEL_R |= 0x30;     // enable alt funct on PC5-4
  GPIO_PORTC_DEN_R |= 0x30;       // configure PC5-4 as UART1
  GPIO_PORTC_PCTL_R = (GPIO_PORTC_PCTL_R&0xFF00FFFF)+0x00220000;
  GPIO_PORTC_AMSEL_R &= ~0x30;    // disable analog on PC5-4
}
```

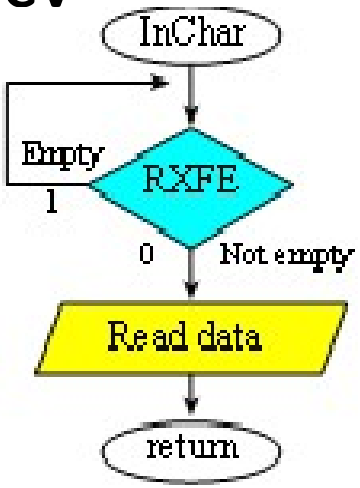
UART Synchronization

- Busy-wait operation

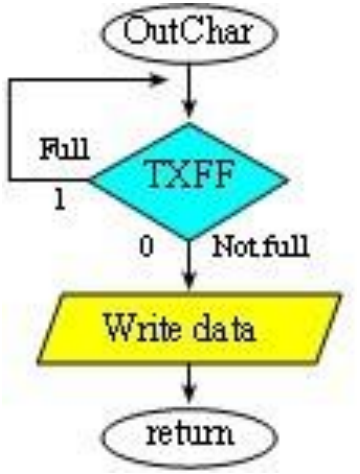


UART Busy-Wait Send/Recv

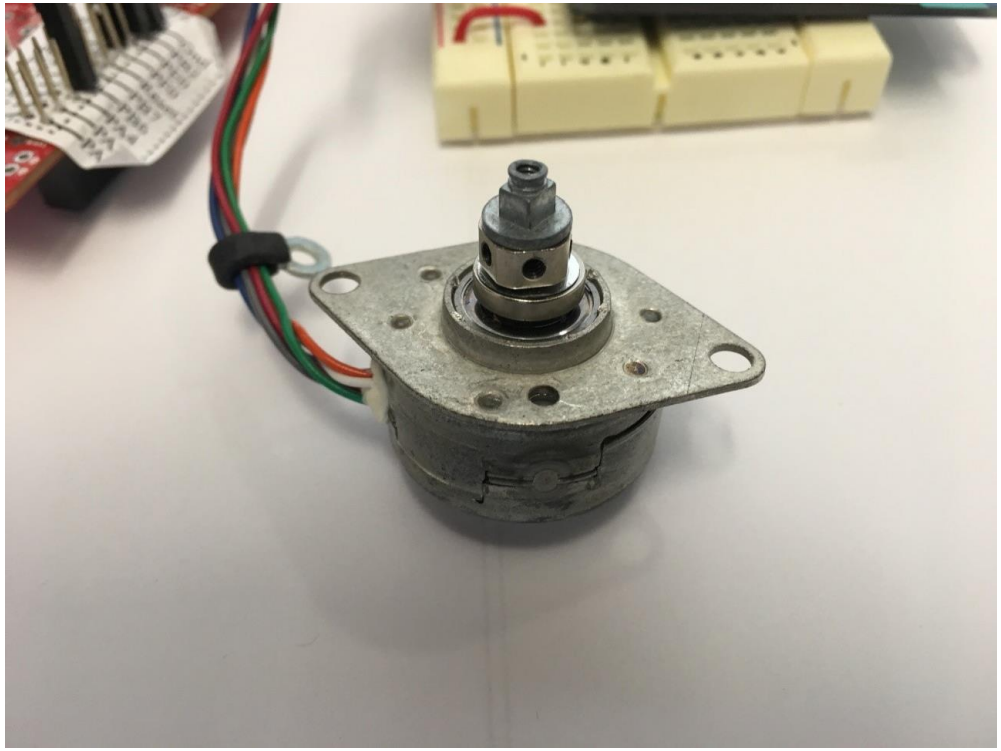
```
// Wait for new input,
// then return ASCII code
uint8_t UART_InChar(void) {
  while((UART1_FR_R&0x0010) != 0);
  // wait until RXFE is 0
  return((uint8_t)(UART1_DR_R&0xFF));
}
```



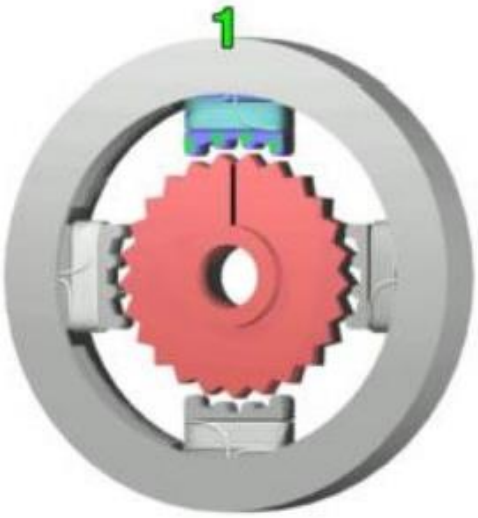

```
// Wait for buffer to be not full,
// then output
void UART_OutChar(uint8_t data) {
  while((UART1_FR_R&0x0020) != 0);
  // wait until TXFF is 0
  UART1_DR_R = data;
}
```



Stepper Motor

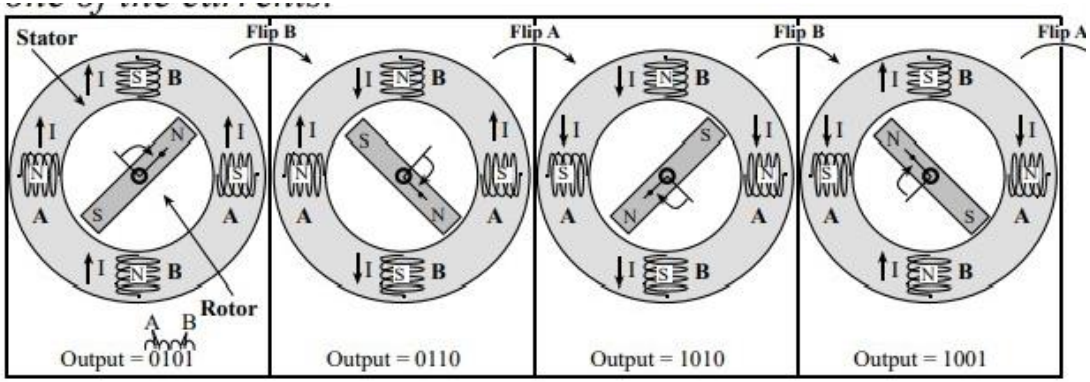


Stepper Motor

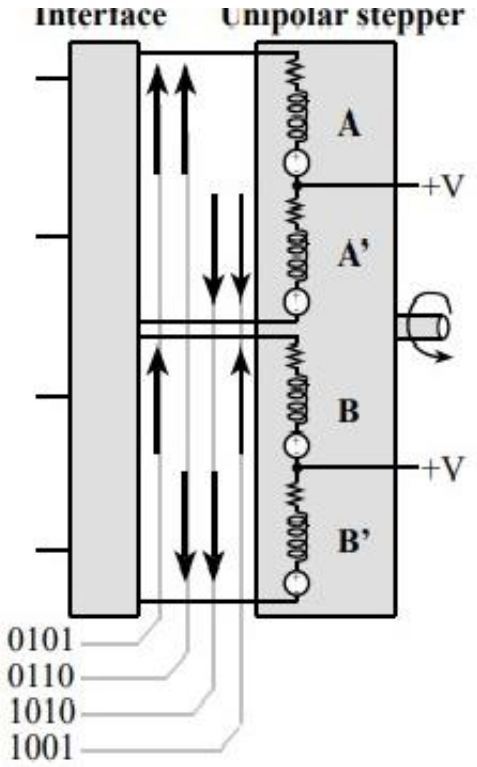


Steps / rev

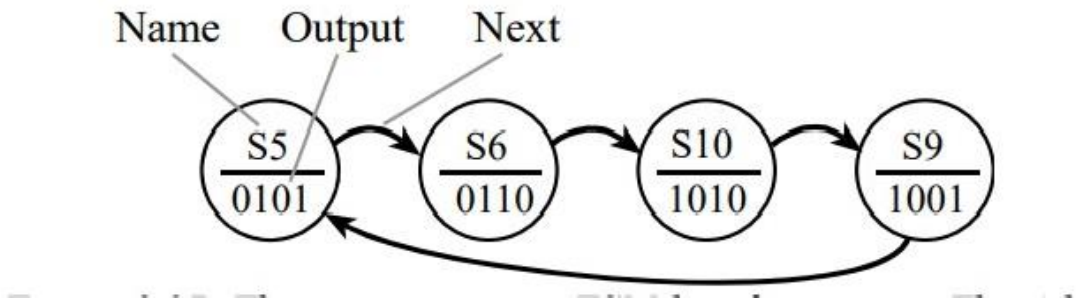
Stepper Motor



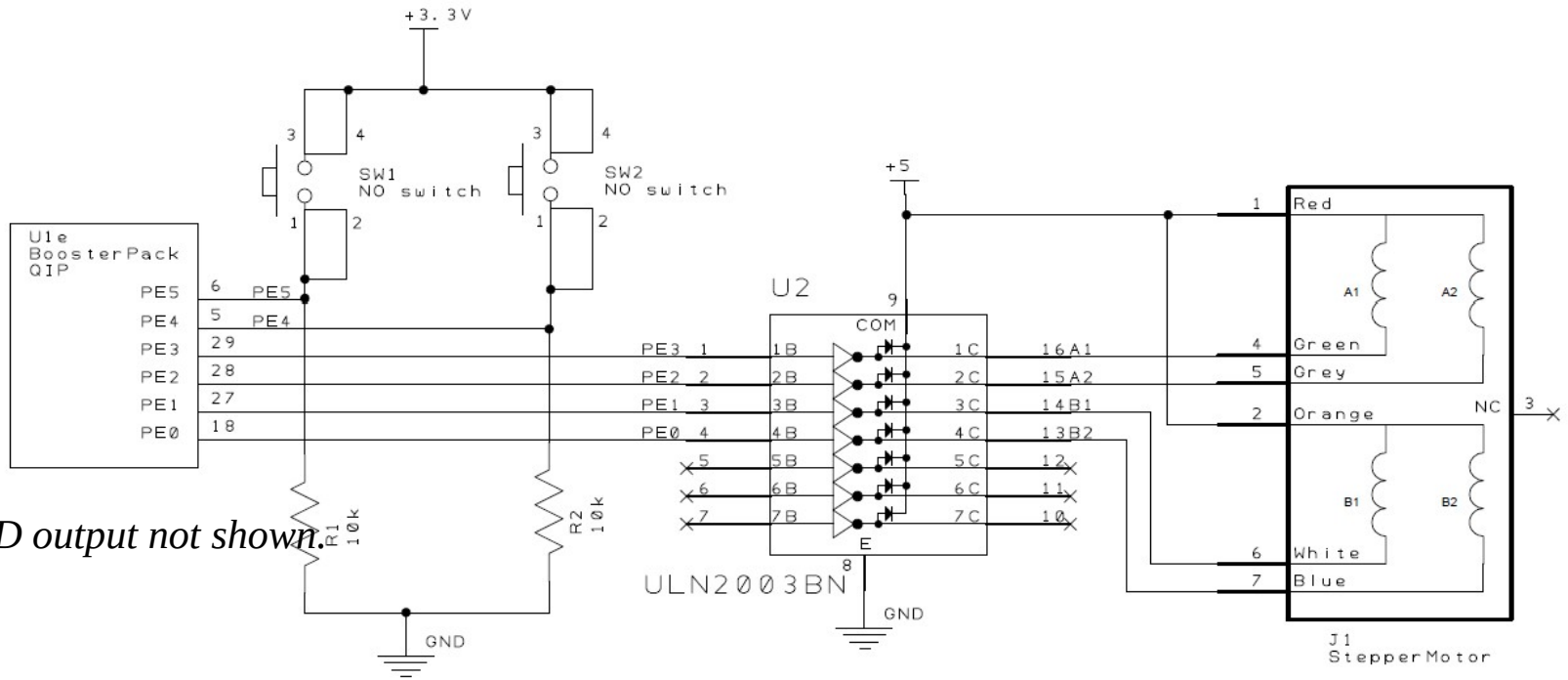
Stepper Motor



Stepper Motor FSM

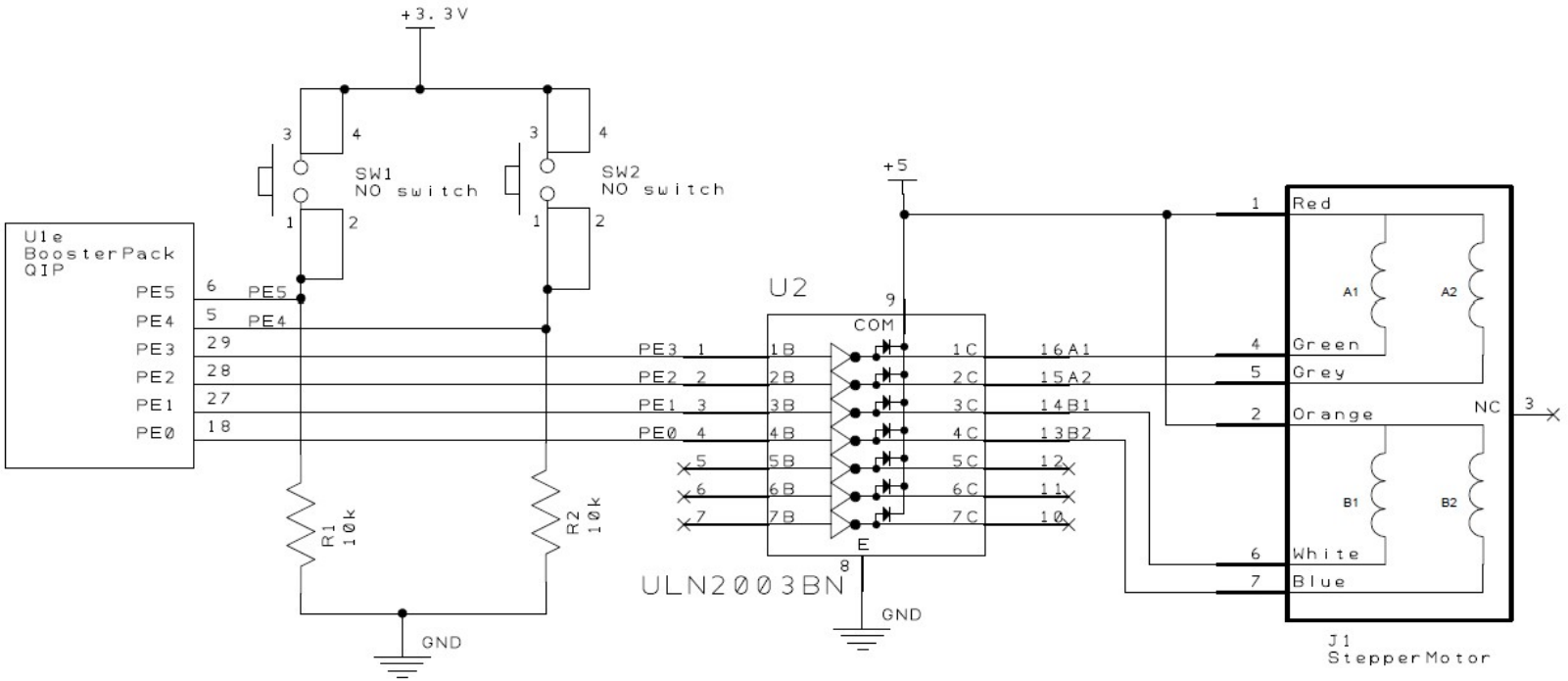


Stepper Motor Interface



LED output not shown.

Stepper Motor Interface



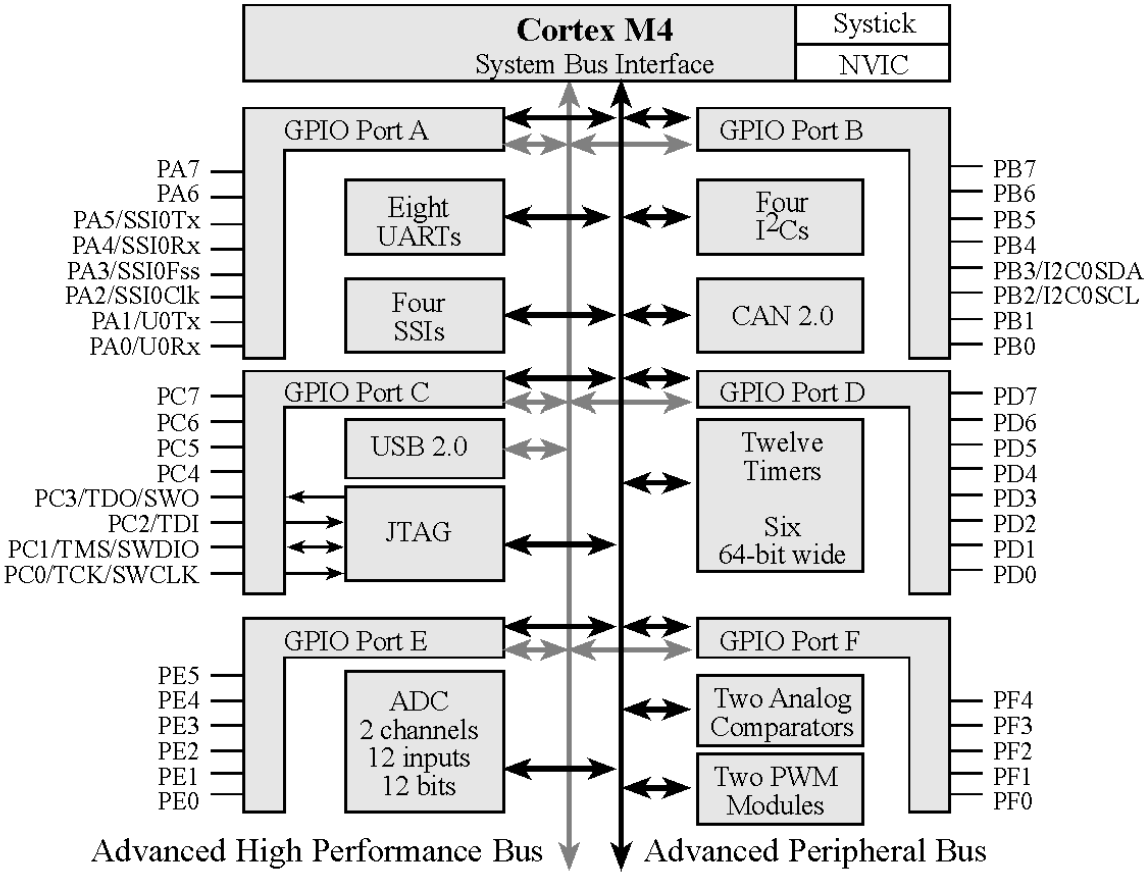
Clockwise 5,6,10,9,5,6,10,9,5,6,10,9,5,6,10,9,5,6,10,9,5,6,10,9,5,6,10,9,…

36 steps/revolution means each step changes angle by 10 degrees

Analog Watch Example

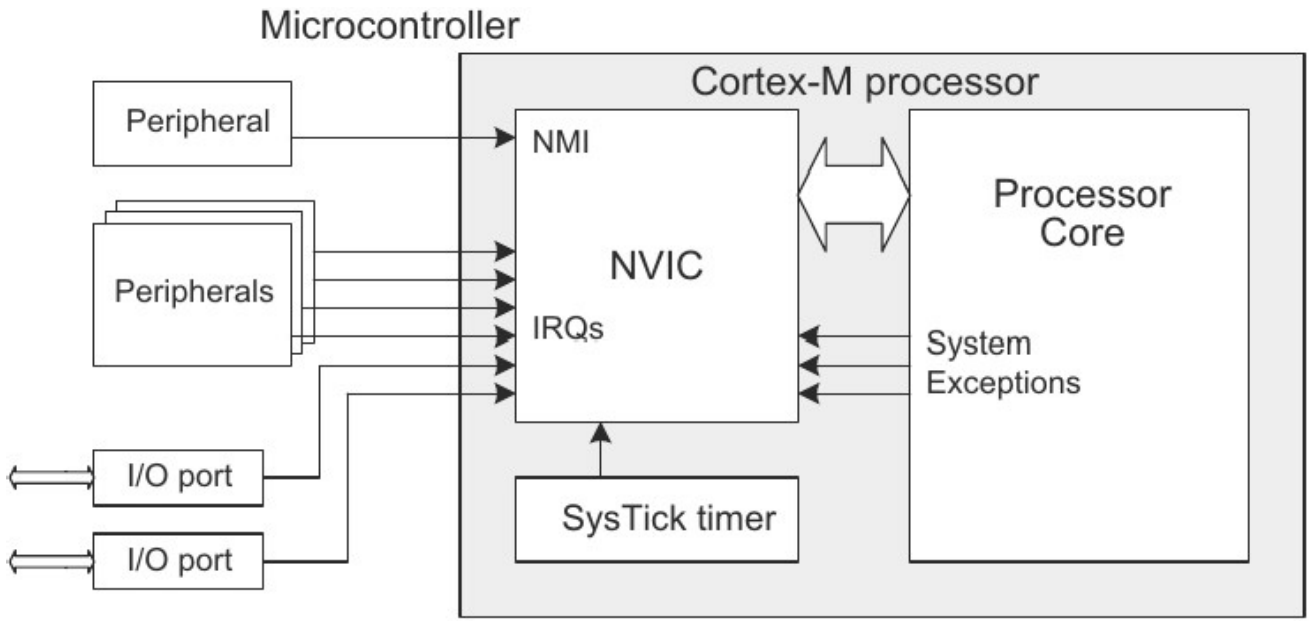
```
void SysTick_Wait(uint32_t delay){
        NVIC_ST_RELOAD_R = delay -1;
        NVIC_ST_CURRENT_R =0;
        while ((NVIC_ST_CTRL_R & 0x00010000) ==0){}
}
void SysTick_wait10ms(uint32_t delay){
                uint32_t i;
                for(i=0; i<delay;i++){ SysTick_Wait(800000);}
};
#define STEPPER (*((volatile unit32_t *) 0x4000703C))
        int main(void)
{
                int i,j;
                SYSCTL_RCGCGPIO_R |=0x08;
                GPIO_PORTD_DIR_R |=0xF;
                GPIO_PORTD_DEN_R |=0xF;
                while(1){
                                STEPPER = 10;
                                SysTick_wait10ms(5);
                                STEPPER = 9;
                                SysTick_wait10ms(5);
                                STEPPER = 5;
                                SysTick_wait10ms(5);
                                 STEPPER = 6;
                                 SysTick_wait10ms(5);}
}
```

Texas Instruments TM4C123



ARM Cortex-M4
+ 256K Flash
+ 32K RAM
+ JTAG
+ 43 Ports
+ SysTick
+ ADC
+ UART

ARM Cortex-M Interrupts



ARM Cortex-M Interrupts

- Each interrupt source has a separate **arm** bit
  - Set for those devices from which it wishes to accept interrupts,

```
GPIO_PORTF_IM_R |= 0x10;      // arm interrupt on PF4
```

  - Deactivate in those devices from which interrupts are not allowed
- Each interrupt source has a separate **flag** bit
  - hardware sets the flag when it wishes to request an interrupt

```
GPIO_PORTF_ICR_R = 0x10;      // acknowledge flag4
```

  - software clears the flag in ISR to signify it is processing the request
- Interrupt **enable** conditions in processor
  - Global interrupt enable bit, I, in PRIMASK register

```
EnableInterrupts();
```

Interrupt Processing

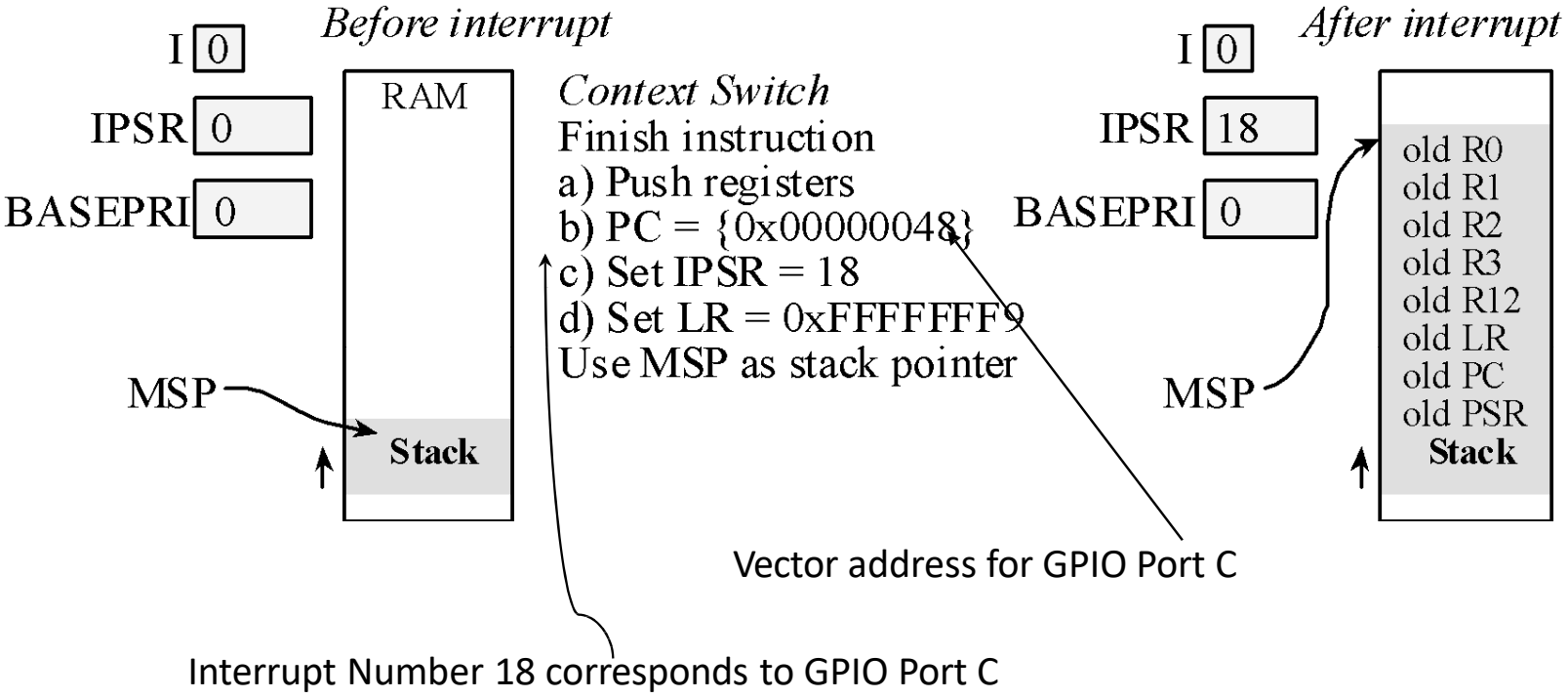
1. The execution of the main program is suspended
    1. the current instruction is finished,
    2. suspend execution and push 8 registers (R0-R3, R12, LR, PC, PSR) on the stack
    3. IPSR set to interrupt number
    4. sets PC to ISR address
2. The interrupt service routine (ISR) is executed
    - ❖ clears the flag that requested the interrupt
    - ❖ performs necessary operations
    - ❖ communicates using global variables
3. The main program is resumed when ISR executes **BX LR**
    - ❖ pulls the 8 registers from the stack

Interrupt Program Status Register (ISPR)

Bits	Description
Bits 31:9	Reserved
Bits 8:0	**ISR_NUMBER:** This is the number of the current exception: 0: Thread mode 1: Reserved 2: NMI 3: Hard fault 4: Memory management fault 5: Bus fault 6: Usage fault 7: Reserved .... 10: Reserved 11: SVCall 12: Reserved for Debug 13: Reserved 14: PendSV 15: SysTick 16: IRQ0(1) ....

Figure 2-3, The IPSR Register.

Interrupt Context Switch



Interrupt Vectors

Vector address	Number	IRQ	ISR name in **Startup.s**	NVIC	Priority bits
0x00000038	14	-2	PendSV_Handler	NVIC_SYS_PRI3_R	23 – 21
0x0000003C	15	-1	SysTick_Handler	NVIC_SYS_PRI3_R	31 – 29
0x00000040	16	0	GPIOPortA_Handler	NVIC_PRI0_R	7 – 5
0x00000044	17	1	GPIOPortB_Handler	NVIC_PRI0_R	15 – 13
0x00000048	18	2	GPIOPortC_Handler	NVIC_PRI0_R	23 – 21
0x0000004C	19	3	GPIOPortD_Handler	NVIC_PRI0_R	31 – 29
0x00000050	20	4	GPIOPortE_Handler	NVIC_PRI1_R	7 – 5
0x00000054	21	5	UART0_Handler	NVIC_PRI1_R	15 – 13
0x00000058	22	6	UART1_Handler	NVIC_PRI1_R	23 – 21
0x0000005C	23	7	SSI0_Handler	NVIC_PRI1_R	31 – 29
0x00000060	24	8	I2C0_Handler	NVIC_PRI2_R	7 – 5
0x00000064	25	9	PWM0Fault_Handler	NVIC_PRI2_R	15 – 13
0x00000068	26	10	PWM0_Handler	NVIC_PRI2_R	23 – 21
0x0000006C	27	11	PWM1_Handler	NVIC_PRI2_R	31 – 29
0x00000070	28	12	PWM2_Handler	NVIC_PRI3_R	7 – 5
0x00000074	29	13	Quadrature0_Handler	NVIC_PRI3_R	15 – 13
0x00000078	30	14	ADC0_Handler	NVIC_PRI3_R	23 – 21
0x0000007C	31	15	ADC1_Handler	NVIC_PRI3_R	31 – 29
0x00000080	32	16	ADC2_Handler	NVIC_PRI4_R	7 – 5
0x00000084	33	17	ADC3_Handler	NVIC_PRI4_R	15 – 13
0x00000088	34	18	WDT_Handler	NVIC_PRI4_R	23 – 21
0x0000008C	35	19	Timer0A_Handler	NVIC_PRI4_R	31 – 29
0x00000090	36	20	Timer0B_Handler	NVIC_PRI5_R	7 – 5
0x00000094	37	21	Timer1A_Handler	NVIC_PRI5_R	15 – 13
0x00000098	38	22	Timer1B_Handler	NVIC_PRI5_R	23 – 21
0x0000009C	39	23	Timer2A_Handler	NVIC_PRI5_R	31 – 29
0x000000A0	40	24	Timer2B_Handler	NVIC_PRI6_R	7 – 5
0x000000A4	41	25	Comp0_Handler	NVIC_PRI6_R	15 – 13
0x000000A8	42	26	Comp1_Handler	NVIC_PRI6_R	23 – 21
0x000000AC	43	27	Comp2_Handler	NVIC_PRI6_R	31 – 29
0x000000B0	44	28	SysCtl_Handler	NVIC_PRI7_R	7 – 5
0x000000B4	45	29	FlashCtl_Handler	NVIC_PRI7_R	15 – 13

Interrupt Vectors

Vector address	Number	IRQ	ISR	NVIC	Prority bit
0x000000B8	46	30	GPIOPortFHandler	NVIC_PRI7_R	23-21

Priority registers on the NVIC

Address	31 – 29	23 – 21	15 – 13	7 – 5	Name
0xE000E400	GPIO Port D	GPIO Port C	GPIO Port B	GPIO Port A	NVIC_PRI0_R
0xE000E404	SSI0, Rx Tx	UART1, Rx Tx	UART0, Rx Tx	GPIO Port E	NVIC_PRI1_R
0xE000E408	PWM Gen 1	PWM Gen 0	PWM Fault	I2C0	NVIC_PRI2_R
0xE000E40C	ADC Seq 1	ADC Seq 0	Quad Encoder	PWM Gen 2	NVIC_PRI3_R
0xE000E410	Timer 0A	Watchdog	ADC Seq 3	ADC Seq 2	NVIC_PRI4_R
0xE000E414	Timer 2A	Timer 1B	Timer 1A	Timer 0B	NVIC_PRI5_R
0xE000E418	Comp 2	Comp 1	Comp 0	Timer 2B	NVIC_PRI6_R
0xE000E41C	GPIO Port G	GPIO Port F	Flash Control	System Control	NVIC_PRI7_R
0xE000E420	Timer 3A	SSI1, Rx Tx	UART2, Rx Tx	GPIO Port H	NVIC_PRI8_R
0xE000E424	CAN0	Quad Encoder 1	I2C1	Timer 3B	NVIC_PRI9_R
0xE000E428	Hibernate	Ethernet	CAN2	CAN1	NVIC_PRI10_R
0xE000E42C	uDMA Error	uDMA Soft Tfr	PWM Gen 3	USB0	NVIC_PRI11_R
0xE000ED20	SysTick	PendSV	--	Debug	NVIC_SYS_PRI3_R

NVIC enable registers

Address	31	30	29-7	6	5	4	3	2	1	0	Name
0xE000E100	G	F	…	UART1	UART0	E	D	C	B	A	NVIC_EN0_R
0xE000E104			…						UART2	H	NVIC_EN1_R

PortF Interrupt Initialization

```
void EdgeCounter_Init(void){
  SYSCTL_RCGCGPIO_R |= 0x00000020; // activate port F
  FallingEdges = 0;
  GPIO_PORTF_DIR_R &= ~0x10;    //  make PF4 in (built-in button)
  GPIO_PORTF_DEN_R |= 0x10;     //     enable digital I/O on PF4
  GPIO_PORTF_PUR_R |= 0x10;     //     enable weak pull-up on PF4
  GPIO_PORTF_IS_R &= ~0x10;     //  PF4 is edge-sensitive
  GPIO_PORTF_IBE_R &= ~0x10;    //     PF4 is not both edges
  GPIO_PORTF_IEV_R &= ~0x10;    //     PF4 falling edge event
  GPIO_PORTF_ICR_R = 0x10;      // clear flag4
  GPIO_PORTF_IM_R |= 0x10;      //  arm interrupt on PF4
  NVIC_PRI7_R = (NVIC_PRI7_R&0xFF00FFFF)|0x00A00000; // priority 5
  NVIC_EN0_R = 0x40000000;      // enable interrupt 30 in NVIC
  EnableInterrupts();           // Enable global Interrupt flag (I)
}
```

PortF Handler

```
void GPIOPortF_Handler(void){

   GPIO_PORTF_ICR_R = 0x10;      // acknowledge flag4

   FallingEdges = FallingEdges + 1;

}
```