UART

Welcome back to Cypress Academy, PSoC 6 101. In next few videos I will show you the basic building blocks to create our BLE-Controlled robotic arm; this will include a UART terminal interface, PWMs to control the servo motors, EZ-I2C dashboard interface, digital logic-based kill switch, capacitive sensing controls and an advanced technique for debugging RTOS applications. As I go through these videos, I will first create a bare metal implementation so you understand the basics for each peripheral function and then we’ll integrate those functions with an RTOS into the BLE-controlled robotic arm project.

Let’s start with the UART interface to a PC terminal client. The UART interface is great as a rudimentary debug interface when developing an application. It can also be used as a basic communications peripheral for other system ICs.

So, let’s start by adding a new project to our previously used workspace. Let’s call this “BasicUART”.

As with our other projects, let’s drag and drop the UART component on to the schematic. Double click again to edit. Let’s call it “UART”. All the other settings look good, so click okay.

Double click on the pins file under the design wide resources and assign the RX and TX to P5[0] and P5[1].

On the back of the PSoC 6 BLE Pioneer board, you can actually see the silkscreen notes regarding the I/Os. This is a nice quick reference as you build out these projects.

Let’s generate the application.

We’re going to control this with the Cortex-M4, so let’s open the M4 main application file. Start the UART using the API call. For this basic project I just want to echo the characters the PSoC 6 receives back to the terminal client. So, let’s create a character variable called c. Assign c to the value of the received UART character using the generic API call CY\_SCB\_UART\_GET with the macro that PSoC Creator has generated called UART\_HW.

Now I want to check whether the character, c, is printable. To do this, I will use the built-in library function isprint, if it returns true, I’ll echo the character to the screen using the CY\_SCB\_UART\_PUT function. The isprint function is defined in the ctype.h header file, so I will add a #include for that library.

And that’s it, now time to build, program and test it.

First I’m going to do is open Windows’ device manager to see which COM port the KitProg is attached to. You can see which COM port it’s attached to under Ports and labeled KitProg2 USB-UART.

Now open up your favorite terminal client and attach it to the correct COM port at 115200 baud 8-n-1. I know the baud rate and 8-n-1 setting because they are in the component configuration dialog we saw earlier.

Now in the terminal client whatever I type is now echoed back to me on the screen…in this case, PSoC 6 is awesome!

Ok, so now I’m going to create the main project of our BLE-controlled arm application. File->new project just like before and let’s name this “MainController”. Let’s setup the FreeRTOS build settings like we did before in a previous lesson by going to build settings and selecting the checkbox for FreeRTOS. Okay, and back to the blank schematic.

I will drag and drop a UART component from component library just like before; rename it UART. And, setup the pins in the design wide resources folder. P5[0] and P5[1] just like last time.

Now I will open the CM4 main application file.

First I will create the UART task like we did with the blinking LED task before.

I don’t need any arguments so I’ll use void arg like before. Now, let’s start the UART. Then, I like to build a command processor that gets a key and then processes that with a big switch statement. First define a character c. Then read C from the UART. Now setup the switch to process different commands. For now the only command will be ? which will just printout the commands. As we add new commands to the command processor switch I will add more prints to this case as well as additional cases to handle the other commands.

To print just use the PDL Api Cy\_SCB\_UART\_PutString with the macro UART\_HW and the string you want to printout. When the user presses ? for now we will just print “? Prints help”

The last step is to start the task in main… and startup the scheduler.

Build, program.

To test it go to the Terminal again and press ?. OK… good, the help function works and we have a framework to add more commands.

Now we have our first UART interface working. In the next video, I will walk you through adding and configuring the PWM peripherals to control the servos in the robotic arm.

You can post your comments and questions in our PSoC 6 community or as always you are welcome to email me at alan\_hawse@cypress.com or tweet me at @askioexpert with your comments, suggestions, criticisms and questions.