BLE CapSense Remote Control

Welcome back to Cypress Academy, PSoC 6 101. So far, we’ve created a BLE-controlled robotic arm, and added a second PSoC 6 BLE Pioneer Kit to the system to act as a remote control. We are now going to add CapSense capacitive-sensing to our BLE Remote Control for our robotic arm.

Add the capsense component

Change the name to capsense

Add linear slider and two buttons

Make the buttons mutual cap

Go to the advanced tab -> widget details… change the Button1\_tx to be button0\_tx

Assign the pins the linear slider to pin P8[3] -> P8[7], The Button0 RX to P8[1] and Button 1 to P8[2] … then the Button Tx to P1[0] … then you assign the capacitors to their default location… see they are labled in green when you do the pulldown menu

Now… because I am into code reuse Ill copy the capsenseTask.h and .c from the MainController project… lets see I need to set the includes to be project.h freertos.h task.h and

Now we have a BLE remote control with CapSense and a BLE-controlled robotic arm. Next step, lets add in some sensors. For the next few videos, we’ll be implementing the motion sensor and the E-ink Display to the BLE remote controller!

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.