

EENG461, LAB2 report

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Objective In this lab we begin exploring interrupts and the concept of task scheduling. We are to have two LEDs are to blink in a pattern, and another LED toggle with a button press, using debouncing.

Introduction Task scheduling is a necessary part of real-time embedded systems that allows for many disparate activities to be completed in the appropriate order and at the appropriate time. The Prof indicated that his requirements are “just get interrupts working”, so we did not implement a general-purpose task scheduler, like in the example code. We did, however, use interrupts to service the different tasks asynchronously.

Narrative

Concluding Remarks

```
#pragma once
//
// Created by Mark Clark on 10/3/23.
//

#ifndef EENG461_LAB_2_MAIN_H
#define EENG461_LAB_2_MAIN_H

int main (void);
void Disable_Interrupts(void);
void Enable_Interrupts(void);

#endif //EENG461_LAB_2_MAIN_H
```

Appendix - main.h

```
//
// Created by Mark Clark on 10/3/23.
//

#include "main.h"
#include "setup.h"
#include "timers.h"
#include <stdint.h>
#include <common/tm4c123gh6pm.h>
```

```

volatile int sec_count;

int main (void) {

    setup();
    configureTimer();

    Enable_Interrupts(); //Enable Global Interrupts

    while (1) {

        switch (sec_count) {
            case 0:
                /*
                 * Time = 0 starts with blue led turning on
                 */
                GPIO_PORTF_DATA_BITS_R[BLUE_LED] = BLUE_LED;
                break;
            case 1:
                /*
                 * After 1 second of blue LED being on, turn on the red LED (leaving
↪ blue LED on)
                 */
                GPIO_PORTF_DATA_BITS_R[RED_LED] = RED_LED;
                break;
            case 3:
                /*
                 * After 2 seconds of red and blue LEDs being on, turn both of them
↪ off
                 */
                GPIO_PORTF_DATA_BITS_R[RED_LED | BLUE_LED] = 0;
                break;
        }

        return (0);
    }

    /*
     * Taken from Lab Assignment
     */
    void Disable_Interrupts(void) {
        __asm (" CPSID I\n");
    }

    void Enable_Interrupts(void) {
        __asm (" CPSIE I\n");
    }
}

```

Appendix - main.c

```

#pragma once
#define GREEN_LED (1 << 3)
#define BLUE_LED (1 << 2)
#define RED_LED (1 << 1)
#define RGB_PINS GREEN_LED | BLUE_LED | RED_LED
#define SW1_PIN (1 << 4)

void setup(void);

```

Appendix - setup.h

```

#include "common/tm4c123gh6pm.h"
#include "setup.h"
#include <stdint.h>

void setup(void) {
    // Enable GPIO clock
    SYSCTL_RCGCGPIO_R |= (1 << 5);
    while(!(SYSCTL_PRGPIO_R & SYSCTL_PRGPIO_R5)) {};

    // Configure pins
    GPIO_PORTF_DEN_R |= RGB_PINS;
    GPIO_PORTF_DR8R_R |= RGB_PINS;

    // Set initial values
    GPIO_PORTF_DATA_R &= ~RGB_PINS; //All off to start

    // Set pin directions
    GPIO_PORTF_DIR_R |= RGB_PINS;

    //SW1 pullup
    GPIO_PORTF_PUR_R |= SW1_PIN;
    GPIO_PORTF_DEN_R |= SW1_PIN;

    //Enable interrupts on value of buttons
    GPIO_PORTF_IS_R &= ~SW1_PIN; //Edge triggered
    GPIO_PORTF_IBE_R |= SW1_PIN; //Both Edges
    GPIO_PORTF_IM_R |= SW1_PIN; //Unmask the pin

    NVIC_PRI7_R = (NVIC_PRI7_R & ~NVIC_PRI7_INT30_M) | (0x7 << NVIC_PRI7_INT30_S);
    ↪ //Set the PORTF interrupt to the lowest priority.

    NVIC_ENO_R |= (1 << 30); // Enable Port F interrupts in nvic
}

```

Appendix - setup.c

```
#pragma once
void PORTF_int_handler(void);
```

Appendix - sw1_int.h

```
#include "sw1_int.h"

#include <stdbool.h>
#include <stdint.h>

#include "common/tm4c123gh6pm.h"
#include "setup.h"
#include "timers.h"

#define MIN_CLOCKS_DEBOUNCE (int32_t)((int32_t)CYCLES_PER_SEC/100)

#define TIMER_ISR_IS_PENDING (TIMER0_MIS_R & TIMER_ICR_TATOCINT)

static void sw1_debounce(void);

void PORTF_int_handler(void){
    // ASSUMPTION: ONLY SW1 ON PORTF is toggled.
    // If more pins were being toggled, then we would need to dispatch a different
    ↪ handler for each.
    // Such code might look like this.

    if(GPIO_PORTF_MIS_R & SW1_PIN) {
        GPIO_PORTF_IM_R &= ~SW1_PIN; //Disable interrupt
        GPIO_PORTF_ICR_R |= SW1_PIN; //Clear interrupt
        sw1_debounce();
        GPIO_PORTF_IM_R |= SW1_PIN; //Re-enable interrupt
    }
}

//Performs debounce by disallowing further input after the first edge transition
↪ until MIN_CLOCKS_DEBOUNCE has passed.
static void sw1_debounce(void){
    static int32_t uptime_last = 0;
    static int32_t cycles_last = 0;
    static enum { RELEASED, PRESSED } button_state = RELEASED;

    const enum { FALLING, RISING } edge_type = (GPIO_PORTF_DATA_BITS_R[SW1_PIN] ==
    ↪ SW1_PIN);

    int32_t uptime_now;
    int32_t cycles_now;

    // Early exit for don't-care state combinations
    if( ((button_state == PRESSED) && (edge_type == FALLING )) ||
```

```

        ((button_state == RELEASED) && (edge_type == RISING)) ) {
            return;
        }

        //Critical Section: read of the current time
        __asm("CPSID I\n"); //Disable interrupt handling
        do {
            if(TIMER_ISR_IS_PENDING) timerISR();

            uptime_now = uptime_seconds;
            cycles_now = CYCLES_PER_SEC-TIMERO_TAR_R;

            // If the counter overflowed during this code block, then our reads of uptime
            ↪ and cycles are invalid. Re-do them.
        } while (TIMER_ISR_IS_PENDING);
        __asm("CPSIE I\n"); //Re-enable interrupt handling

        int32_t seconds_passed = (uptime_now - uptime_last);
        if(seconds_passed > 2) seconds_passed = 2; // Prevent overflow
        int32_t cycles_passed = (cycles_now - cycles_last) +
            ↪ seconds_passed*CYCLES_PER_SEC;

        if(cycles_passed > MIN_CLOCKS_DEBOUNCE) {
            uptime_last = uptime_now;
            cycles_last = cycles_now;

            switch(button_state) {
                case PRESSED:
                    button_state = RELEASED;
                    break;

                case RELEASED:
                    button_state = PRESSED;
                    GPIO_PORTF_DATA_BITS_R[GREEN_LED] ^= GREEN_LED;
            }
        }
    }
}

```

Appendix - sw1_int.c

```

//
// Created by Mark Clark on 10/3/23.
//
#include "stdint.h"

#ifndef EENG461_LAB_2_TIMERS_H
#define EENG461_LAB_2_TIMERS_H

extern volatile int sec_count;
extern volatile int32_t uptime_seconds;

```

```

#define CYCLES_PER_SEC 16000000

void configureTimer (void);
void timerISR (void);

#endif //EENG461_LAB_2_TIMERS_H

```

Appendix - timers.h

```

//
// Created by Mark Clark on 10/3/23.
//

#include <stdint.h>
#include "timers.h"
#include "main.h"
#include "setup.h"
#include "common/tm4c123gh6pm.h"

volatile int32_t uptime_seconds;

void configureTimer (void) {

    SYSCTL_RCGCTIMER_R |= SYSCTL_RCGCTIMER_R0; //Enable Run Mode Clock Gating
    ↪ Control for Timer 0

    while (!(SYSCTL_PRTIMER_R & SYSCTL_RCGCTIMER_R0)) {}

    TIMER0_CTL_R &= ~TIMER_CTL_TAEN; //Disable Timer
    TIMER0_CFG_R = TIMER_CFG_32_BIT_TIMER;
    TIMER0_TAMR_R |= TIMER_TAMR_TAMR_PERIOD; //Set Timer to count down periodically
    TIMER0_TAILR_R = CYCLES_PER_SEC - 1;
    TIMER0_TAPR_R = 0;
    TIMER0_ICR_R |= TIMER_ICR_TATOCINT; //Clear Interrupt
    TIMER0_IMR_R |= TIMER_IMR_TATOIM; //Enable Interrupt as Timeout
    NVIC_ENO_R = 1 << (INT_TIMER0A - 16);
    TIMER0_CTL_R |= TIMER_CTL_TAEN; //Enable Timer

}

void timerISR (void) {

    TIMER0_IMR_R &= ~TIMER_IMR_TATOIM; //Disable Interrupt
    TIMER0_ICR_R |= TIMER_ICR_TATOCINT; //Clear Interrupt

    if (sec_count < 4) {
        sec_count++; //Increment second counter
    } else {
        sec_count = 0;
    }
}

```

```

    }
    uptime_seconds++;

    TIMERO_IMR_R |= TIMER_IMR_TATOIM; //Enable Interrupt
}

```

Appendix - timers.h

```

CC      = arm-none-eabi-gcc
LD      = arm-none-eabi-ld
AR      = arm-none-eabi-ar
AS      = arm-none-eabi-as
OBJSIZE = arm-none-eabi-size
OBJDUMP = arm-none-eabi-objdump
OBJCOPY = arm-none-eabi-objcopy
CPU     = -mcpu=cortex-m4
FPU     = -mfpu=fpv4-sp-d16 -mfloat-abi=softfp

AFLAGS  = -mthumb ${CPU} ${FPU} -MD

CFLAGS  = -mthumb ${CPU} ${FPU} -Og -ffunction-sections -fno-builtin -fdata-sections
↳ -MD -std=c17 -Wall -Wextra -pedantic -c -Dgcc -g -I driver -I src -I sys

CFLAGS += -DPART_TM4C123GH6PM -DTARGET_IS_BLIZZARD_RA1

LDFLAGS=--gc-sections
#-L /usr/lib/arm-none-eabi/newlib -lc

AFLAGS+=${patsubst %, -I%, ${subst :, , ${IPATH}}}}
CFLAGS+=${patsubst %, -I%, ${subst :, , ${IPATH}}}}

export CC LD AR AS OBJCOPY
export CFLAGS AFLAGS LDFLAGS

BUILD_DIR := objs
SRCS      := $(wildcard src/*.c) $(wildcard sys/*.c)
HEADERS    := $(wildcard src/*.h) $(wildcard sys/*.h) Makefile
OBJECTS    := $(addprefix $(BUILD_DIR)/, $(subst .c, .o, $(SRCS)))
TARGET     := lab2binary

all: credir $(BUILD_DIR)/$(TARGET).axf

# Compile
$(BUILD_DIR)/%.o: %.c $(HEADERS)
    $(CC) $(CFLAGS) -o $(@) -MD -MF $(addprefix $(BUILD_DIR)/, $(subst .c, .d, $<))
↳ $(firstword $~)

# Linking
$(BUILD_DIR)/$(TARGET).axf: $(OBJECTS)

```

```

$(LD) $(OBJECTS) -T sys/tm4c123.ld --entry ResetISR $(LDFLAGS) -o $(@)
↪ -Map=$(BUILD_DIR)/$(TARGET).map
$(OBJCOPY) -O binary ${@} ${@:.axf=.bin}
$(OBJDUMP) -Sd -W $(@) > ${BUILD_DIR}/$(TARGET).lss
$(OBJSIZE) ${@}

# Load binary to device
flash:
    sudo lm4flash $(BUILD_DIR)/$(TARGET).bin

clean:
    rm -rf $(BUILD_DIR)/*
    rm lab2_report.pdf

credir:
    mkdir -p $(BUILD_DIR)
    mkdir -p $(BUILD_DIR)/src
    mkdir -p $(BUILD_DIR)/sys

app_info: $(BUILD_DIR)/${TARGET}.axf
    arm-none-eabi-readelf -a $(^)

%.pdf: docs/src/%.md Makefile
    pandoc $< -o $@ --highlight-style tango --pdf-engine=xelatex

report: lab2_report.pdf

.PHONY: all clean flash compiling app_info report

```

Appendix - Makefile

```

#!/bin/bash
sudo echo ""
sudo openocd -f ti_ek-tm4c123gx1.cfg &> /dev/null &
openocd_pid=$!

gdb-multiarch -ex "file objs/lab2binary.axf" -ex "target extended-remote
↪ localhost:3333" -ex "b main" -ex "layout split" -ex "mon reset halt" -ex "ni"
↪ -tui

kill $openocd_pid

```

Appendix - debug.sh

```

source [find interface/ti-icdi.cfg]

transport select hla_jtag

set WORKAREASIZE 0x8000

```



```
set CHIPNAME tm4c123gh6pm  
source [find target/stellaris.cfg]
```

Appendix - debug.sh