

TahakomAVRLib

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Chapter 1

Namespace Index

1.1 Namespace List

Here is a list of all namespaces with brief descriptions:

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Chapter 2

Hierarchical Index

2.1 Class Hierarchy

This inheritance list is sorted roughly, but not completely, alphabetically:

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component::Buzzer	34
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Class Index

3.1 Class List

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Header file of the WatchdogTimer class	316

Chapter 5

Namespace Documentation

5.1 component Namespace Reference

Classes

- class [Buzzer](#)
- class [DCMotor](#)
- class [Led](#)
- class [PushButton](#)
- class [ServoMotor](#)
- class [StepperMotor](#)

Enumerations

- enum [mode](#) : uint8_t { [mode::fullStep](#) =0, [mode::halfStep](#) }

5.1.1 Enumeration Type Documentation

5.1.1.1 mode

```
enum component::mode : uint8_t [strong]
```

Enumerator

fullStep	
halfStep	

Definition at line 70 of file [StepperMotor.h](#).

```
00070      : uint8_t {  
00071      fullStep=0,  
00072      halfStep,  
00073  };
```

5.2 core Namespace Reference

Classes

- class [ADConverter](#)
- class [AnalogComparator](#)
- class [ExternInterrupt](#)
- class [MCU](#)
- class [TimerCounter](#)
- class [TimerCounter0](#)
- class [TimerCounter1](#)
- class [TimerCounter2](#)
- class [WatchdogTimer](#)

Enumerations

- enum [resolution](#) : uint8_t {
[resolution::res_8bit](#) =0, [resolution::res_9bit](#), [resolution::res_10bit](#), [resolution::res_11bit](#),
[resolution::res_12bit](#), [resolution::res_13bit](#), [resolution::res_14bit](#), [resolution::res_15bit](#),
[resolution::res_16bit](#) }
- enum [referenceVoltage](#) : uint8_t { [referenceVoltage::AREF](#) =0, [referenceVoltage::AVCC](#), [referenceVoltage::internal](#) }
- enum [clockPrescaler](#) : uint8_t {
[clockPrescaler::PS_2](#) = 1, [clockPrescaler::PS_4](#), [clockPrescaler::PS_8](#), [clockPrescaler::PS_16](#),
[clockPrescaler::PS_32](#), [clockPrescaler::PS_64](#), [clockPrescaler::PS_128](#) }
- enum [autoTriggerSource](#) : uint8_t {
[autoTriggerSource::freeRunning](#), [autoTriggerSource::analogComparator](#), [autoTriggerSource::extInterrupt](#),
[autoTriggerSource::timer0Compare](#),
[autoTriggerSource::timer0Overflow](#), [autoTriggerSource::timer1CompareB](#), [autoTriggerSource::timer1Overflow](#),
[autoTriggerSource::timer1Capture](#) }
- enum [senseControl](#) : uint8_t { [senseControl::lowLevel](#) =0, [senseControl::logicalChange](#), [senseControl::fallingEdge](#),
[senseControl::risingEdge](#) }
- enum [pinChangePort](#) : uint8_t { [pinChangePort::PCINTB](#) =0, [pinChangePort::PCINTC](#), [pinChangePort::PCINTD](#) }
- enum [BODMode](#) : uint8_t { [BODMode::enabled](#) =0, [BODMode::disabled](#) }
- enum [sleepMode](#) : uint8_t {
[sleepMode::Idle](#) =0, [sleepMode::ADC_NoiseReduction](#), [sleepMode::powerDown](#), [sleepMode::powerSave](#),
[sleepMode::standby](#) =6, [sleepMode::extendedStandby](#) }
- enum [channel](#) : uint8_t { [channel::A](#) =0, [channel::B](#) }
- enum [compareOutputMode](#) : uint8_t { [compareOutputMode::normal](#) =0, [compareOutputMode::toggle](#),
[compareOutputMode::clear](#), [compareOutputMode::set](#) }
- enum [operationMode](#) : uint8_t {
[operationMode::normal](#) =0, [operationMode::PWM_PC](#), [operationMode::PWM_PC_8bit](#), [operationMode::PWM_PC_9bit](#),
[operationMode::PWM_PC_10bit](#), [operationMode::PWM_PFC_ICR](#), [operationMode::PWM_PFC_OCR](#),
[operationMode::PWM_PC_ICR](#),
[operationMode::PWM_PC_OCR](#), [operationMode::fast_PWM](#), [operationMode::fast_PWM_8bit](#), [operationMode::fast_PWM_9bit](#),
[operationMode::fast_PWM_10bit](#), [operationMode::fast_PWM_ICR](#), [operationMode::fast_PWM_OCR](#),
[operationMode::CTC_OCR](#),
[operationMode::CTC_ICR](#), [operationMode::interrupt](#) =1, [operationMode::reset](#), [operationMode::interrupt_reset](#)
}
- enum [clockSource](#) : uint16_t {
[clockSource::noClock](#) =0, [clockSource::PS_1](#), [clockSource::PS_8](#), [clockSource::PS_32](#),
[clockSource::PS_64](#), [clockSource::PS_128](#), [clockSource::PS_256](#), [clockSource::PS_1024](#),
[clockSource::extern_Clock_T0_Falling_Edge](#), [clockSource::extern_Clock_T0_Rising_Edge](#) }

- enum `timeOut` : `uint8_t` {
`timeOut::to_16ms` =0, `timeOut::to_32ms`, `timeOut::to_64ms`, `timeOut::to_125ms`,
`timeOut::to_250ms`, `timeOut::to_500ms`, `timeOut::to_1s`, `timeOut::to_2s`,
`timeOut::to_4s`, `timeOut::to_8s` }
- enum `operationMode` : `uint8_t` {
`operationMode::normal` =0, `operationMode::PWM_PC`, `operationMode::PWM_PC_8bit`, `operationMode::PWM_PC_9bit`,
`operationMode::PWM_PC_10bit`, `operationMode::PWM_PFC_ICR`, `operationMode::PWM_PFC_OCR`,
`operationMode::PWM_PC_ICR`,
`operationMode::PWM_PC_OCR`, `operationMode::fast_PWM`, `operationMode::fast_PWM_8bit`, `operationMode::fast_PWM_9bit`,
`operationMode::fast_PWM_10bit`, `operationMode::fast_PWM_ICR`, `operationMode::fast_PWM_OCR`,
`operationMode::CTC_OCR`,
`operationMode::CTC_ICR`, `operationMode::interrupt` =1, `operationMode::reset`, `operationMode::interrupt_reset`
}

5.2.1 Enumeration Type Documentation

5.2.1.1 autoTriggerSource

```
enum core::autoTriggerSource : uint8_t [strong]
```

Enumerator

<code>freeRunning</code>	
<code>analogComparator</code>	
<code>extInterrupt</code>	
<code>timer0Compare</code>	
<code>timer0Overflow</code>	
<code>timer1CompareB</code>	
<code>timer1Overflow</code>	
<code>timer1Capture</code>	

Definition at line 118 of file [ADC.h](#).

```
00118                                     : uint8_t {
00119     freeRunning,
00120     analogComparator,
00121     extInterrupt,
00122     timer0Compare,
00123     timer0Overflow,
00124     timer1CompareB,
00125     timer1Overflow,
00126     timer1Capture
00127 };
```

5.2.1.2 BODMode

```
enum core::BODMode : uint8_t [strong]
```

Enumerator

<code>enabled</code>	
<code>disabled</code>	

Definition at line 77 of file [MCU.h](#).

```
00077             : uint8_t {
00078     enabled=0,
00079     disabled,
00080 };
```

5.2.1.3 channel

```
enum core::channel : uint8_t [strong]
```

Enumerator

A	
B	

Definition at line 470 of file [TimerCounter.h](#).

```
00470             : uint8_t {
00471     A=0,
00472     B,
00473 };
```

5.2.1.4 clockPrescaler

```
enum core::clockPrescaler : uint8_t [strong]
```

Enumerator

PS_2	
PS_4	
PS_8	
PS_16	
PS_32	
PS_64	
PS_128	

Definition at line 108 of file [ADC.h](#).

```
00108             : uint8_t {
00109     PS_2 = 1,
00110     PS_4,
00111     PS_8,
00112     PS_16,
00113     PS_32,
00114     PS_64,
00115     PS_128
00116 };
```

5.2.1.5 clockSource

```
enum core::clockSource : uint16_t [strong]
```

Enumerator

noClock	
PS_1	
PS_8	
PS_32	
PS_64	
PS_128	
PS_256	
PS_1024	
extern_Clock_T0_Falling_Edge	
extern_Clock_T0_Rising_Edge	

Definition at line 504 of file [TimerCounter.h](#).

```
00504                                     : uint16_t {
00505     noClock=0,
00506     PS_1,
00507     PS_8,
00508     PS_32,
00509     PS_64,
00510     PS_128,
00511     PS_256,
00512     PS_1024,
00513     extern_Clock_T0_Falling_Edge,
00514     extern_Clock_T0_Rising_Edge,
00515 };
```

5.2.1.6 compareOutputMode

```
enum core::compareOutputMode : uint8_t [strong]
```

Enumerator

normal	
toggle	
clear	
set	

Definition at line 476 of file [TimerCounter.h](#).

```
00476                                     : uint8_t {
00477     normal=0,
00478     toggle,
00479     clear,
00480     set,
00481 };
```

5.2.1.7 operationMode [1/2]

```
enum core::operationMode : uint8_t [strong]
```

Enumerator

normal	
--------	--

Enumerator

PWM_PC	
PWM_PC_8bit	
PWM_PC_9bit	
PWM_PC_10bit	
PWM_PFC_ICR	
PWM_PFC_OCR	
PWM_PC_ICR	
PWM_PC_OCR	
fast_PWM	
fast_PWM_8bit	
fast_PWM_9bit	
fast_PWM_10bit	
fast_PWM_ICR	
fast_PWM_OCR	
CTC_OCR	
CTC_ICR	
interrupt	
reset	
interrupt_reset	

Definition at line 78 of file [WatchdogTimer.h](#).

```

00078                                     : uint8_t {
00079     interrupt=1,
00080     reset,
00081     interrupt_reset,
00082 };

```

5.2.1.8 operationMode [2/2]

```
enum core::operationMode : uint8_t [strong]
```

Enumerator

normal	
PWM_PC	
PWM_PC_8bit	
PWM_PC_9bit	
PWM_PC_10bit	
PWM_PFC_ICR	
PWM_PFC_OCR	
PWM_PC_ICR	
PWM_PC_OCR	
fast_PWM	
fast_PWM_8bit	
fast_PWM_9bit	
fast_PWM_10bit	
fast_PWM_ICR	
fast_PWM_OCR	

Enumerator

CTC_OCR	
CTC_ICR	
interrupt	
reset	
interrupt_reset	

Definition at line 485 of file [TimerCounter.h](#).

```
00485                                     : uint8_t {
00486     normal=0,
00487     PWM_PC,
00488     PWM_PC_8bit,
00489     PWM_PC_9bit,
00490     PWM_PC_10bit,
00491     PWM_PFC_ICR,
00492     PWM_PFC_OCR,
00493     PWM_PC_ICR,
00494     PWM_PC_OCR,
00495     fast_PWM,
00496     fast_PWM_8bit,
00497     fast_PWM_9bit,
00498     fast_PWM_10bit,
00499     fast_PWM_ICR,
00500     fast_PWM_OCR,
00501     CTC_OCR,
00502     CTC_ICR,
00503 };
```

5.2.1.9 pinChangePort

```
enum core::pinChangePort : uint8_t [strong]
```

Enumerator

PCINTB	
PCINTC	
PCINTD	

Definition at line 156 of file [ExternInterrupt.h](#).

```
00156                                     : uint8_t {
00157     PCINTB=0,
00158     PCINTC,
00159     PCINTD,
00160 };
```

5.2.1.10 referenceVoltage

```
enum core::referenceVoltage : uint8_t [strong]
```

Enumerator

AREF	external AREF pin voltage reference, internal 1.1V voltage reference turned off
AVCC	AVCC voltage reference with external capacitor at AREF pin.
internal	internal 1.1V voltage reference with external capacitor at AREF pin

Definition at line 100 of file [ADC.h](#).

```
00100                                     : uint8_t {
00101     AREF=0,
00102     AVCC,
00103     internal
00104 };
```

5.2.1.11 resolution

```
enum core::resolution : uint8_t [strong]
```

Enumerator

res_8bit	
res_9bit	
res_10bit	
res_11bit	
res_12bit	
res_13bit	
res_14bit	
res_15bit	
res_16bit	

Definition at line 87 of file [ADC.h](#).

```
00087                                     : uint8_t {
00088     res_8bit=0,
00089     res_9bit,
00090     res_10bit,
00091     res_11bit,
00092     res_12bit,
00093     res_13bit,
00094     res_14bit,
00095     res_15bit,
00096     res_16bit
00097 };
```

5.2.1.12 senseControl

```
enum core::senseControl : uint8_t [strong]
```

Enumerator

lowLevel	
logicalChange	
fallingEdge	
risingEdge	

Definition at line 149 of file [ExternInterrupt.h](#).

```
00149                                     : uint8_t {
00150     lowLevel=0,
00151     logicalChange,
00152     fallingEdge,
00153     risingEdge
```



```
00154 };
```

5.2.1.13 sleepMode

```
enum core::sleepMode : uint8_t [strong]
```

Enumerator

Idle	
ADC_NoiseReduction	
powerDown	
powerSave	
standby	
extendedStandby	

Definition at line 82 of file [MCU.h](#).

```
00082             : uint8_t {  
00083     Idle=0,  
00084     ADC_NoiseReduction,  
00085     powerDown,  
00086     powerSave,  
00087     standby=6,  
00088     extendedStandby,  
00089 };
```

5.2.1.14 timeOut

```
enum core::timeOut : uint8_t [strong]
```

Enumerator

to_16ms	
to_32ms	
to_64ms	
to_125ms	
to_250ms	
to_500ms	
to_1s	
to_2s	
to_4s	
to_8s	

Definition at line 65 of file [WatchdogTimer.h](#).

```
00065             : uint8_t {  
00066     to_16ms=0,  
00067     to_32ms,  
00068     to_64ms,  
00069     to_125ms,  
00070     to_250ms,  
00071     to_500ms,  
00072     to_1s,
```

```

00073         to_2s,
00074         to_4s,
00075         to_8s,
00076     };

```

5.3 io Namespace Reference

Classes

- class [Pin](#)
- struct [Port](#)
Structure.
- class [SPI](#)
- class [USART0](#)

Enumerations

- enum [operationMode](#) : [uint8_t](#) { [operationMode::master](#) =0, [operationMode::slave](#), [operationMode::submaster](#), [operationMode::disable](#) }
- enum [clockPrescaler](#) : [uint8_t](#) { [clockPrescaler::PS_4](#) = 0, [clockPrescaler::PS_16](#), [clockPrescaler::PS_64](#), [clockPrescaler::PS_128](#), [clockPrescaler::PS_2](#), [clockPrescaler::PS_8](#), [clockPrescaler::PS_32](#) }
- enum [dataMode](#) : [uint8_t](#) { [dataMode::mode_0](#) = 0, [dataMode::mode_1](#), [dataMode::mode_2](#), [dataMode::mode_3](#) }
- enum [dataOrder](#) : [uint8_t](#) { [dataOrder::first_MSB](#) = 0, [dataOrder::first_LSB](#) }
- enum [transmissionMode](#) : [uint8_t](#) { [transmissionMode::async](#) =0, [transmissionMode::sync](#), [transmissionMode::masterSPI](#) }
- enum [communicationMode](#) : [uint8_t](#) { [communicationMode::duplex](#) =0, [communicationMode::transmit](#), [communicationMode::receive](#) }
- enum [parityMode](#) : [uint8_t](#) { [parityMode::noParity](#) =0, [parityMode::evenParity](#), [parityMode::oddParity](#) }
- enum [frameSize](#) : [uint8_t](#) { [frameSize::eightBits](#) =0, [frameSize::fiveBits](#), [frameSize::sixBits](#), [frameSize::sevenBits](#), [frameSize::neineBits](#) }
- enum [stopBit](#) : [uint8_t](#) { [stopBit::oneStopBit](#) =0, [stopBit::twoStopBits](#) }

Variables

- static [io::Port PortB](#) = { &DDRB, &PORTB, &PINB }
global static [Port](#) B object
- static [io::Port PortC](#) = { &DDRC, &PORTC, &PINC }
global static [Port](#) C object
- static [io::Port PortD](#) = { &DDRD, &PORTD, &PIND }
global static [Port](#) D object

5.3.1 Enumeration Type Documentation

5.3.1.1 clockPrescaler

```
enum io::clockPrescaler : uint8\_t [strong]
```

Enumerator

PS_4	
PS_16	
PS_64	
PS_128	
PS_2	
PS_8	
PS_32	

Definition at line 63 of file [SPI.h](#).

```

00063                                     : uint8_t {
00064     PS_4 = 0,
00065     PS_16,
00066     PS_64,
00067     PS_128,
00068     PS_2,
00069     PS_8,
00070     PS_32
00071 };

```

5.3.1.2 communicationMode

```
enum io::communicationMode : uint8_t [strong]
```

Enumerator

duplex	full duplex mode
transmit	transmit mode
receive	receive mode

Definition at line 85 of file [USART0.h](#).

```

00085                                     : uint8_t {
00086     duplex=0,
00087     transmit,
00088     receive,
00090 };

```

5.3.1.3 dataMode

```
enum io::dataMode : uint8_t [strong]
```

Enumerator

mode↵ _0	
mode↵ _1	
mode↵ _2	
mode↵ _3	

Definition at line 73 of file [SPI.h](#).

```
00073         : uint8_t {
00074     mode_0 = 0,
00075     mode_1,
00076     mode_2,
00077     mode_3,
00078 };
```

5.3.1.4 dataOrder

```
enum io::dataOrder : uint8_t [strong]
```

Enumerator

first_MSB	
first_LSB	

Definition at line 80 of file [SPI.h](#).

```
00080         : uint8_t {
00081     first_MSB = 0,
00082     first_LSB
00083 };
```

5.3.1.5 frameSize

```
enum io::frameSize : uint8_t [strong]
```

Enumerator

eightBits	8 bits frame size
fiveBits	5 bits frame size
sixBits	6 bits frame size
sevenBits	7 bits frame size
neineBits	9 bits frame size

Definition at line 98 of file [USART0.h](#).

```
00098         : uint8_t {
00099     eightBits=0,
00100     fiveBits,
00101     sixBits,
00102     sevenBits,
00103     neineBits
00104 };
```

5.3.1.6 operationMode

```
enum io::operationMode : uint8_t [strong]
```

Enumerator

master	
slave	
submaster	
disable	

Definition at line 56 of file [SPI.h](#).

```
00056                                     : uint8_t {
00057     master=0,
00058     slave,
00059     submaster,
00060     disable,
00061 };
```

5.3.1.7 parityMode

```
enum io::parityMode : uint8_t [strong]
```

Enumerator

noParity	no parity check mode
evenParity	even parity check mode
oddParity	odd parity check mode

Definition at line 92 of file [USART0.h](#).

```
00092                                     : uint8_t {
00093     noParity=0,
00094     evenParity,
00095     oddParity
00096 };
```

5.3.1.8 stopBit

```
enum io::stopBit : uint8_t [strong]
```

Enumerator

oneStopBit	1 stop bit
twoStopBits	2 stop bits

Definition at line 106 of file [USART0.h](#).

```
00106                                     : uint8_t{
00107     oneStopBit=0,
00108     twoStopBits
00109 };
```

5.3.1.9 transmissionMode

```
enum io::transmissionMode : uint8_t [strong]
```

Enumerator

async	asynchronous mode
sync	synchronous mode
masterSPI	masterSPI mode

Definition at line 79 of file [USART0.h](#).

```
00079                                     : uint8_t {
00080     async=0,
00081     sync,
00082     masterSPI
00083 };
```

5.3.2 Variable Documentation

5.3.2.1 PortB

```
io::Port io::PortB = { &DDRB, &PORTB, &PINB } [static]
```

global static [Port](#) B object

Definition at line 72 of file [Pin.h](#).

5.3.2.2 PortC

```
io::Port io::PortC = { &DDRC, &PORTC, &PINC } [static]
```

global static [Port](#) C object

Definition at line 73 of file [Pin.h](#).

5.3.2.3 PortD

```
io::Port io::PortD = { &DDRD, &PORTD, &PIND } [static]
```

global static [Port](#) D object

Definition at line 74 of file [Pin.h](#).

5.4 utils Namespace Reference

Functions

- long [map](#) (long x, long in_min, long in_max, long out_min, long out_max)

5.4.1 Function Documentation

5.4.1.1 [map\(\)](#)

```
long utils::map (  
    long x,  
    long in_min,  
    long in_max,  
    long out_min,  
    long out_max )
```

Definition at line 3 of file [utils_m328p.cpp](#).

```
00004 {  
00005     return (x - in_min) * (out_max - out_min) / (in_max - in_min) + out_min;  
00006 }
```


Chapter 6

Class Documentation

6.1 core::ADConverter Class Reference

```
#include <ADC.h>
```

Public Member Functions

- void [start](#) ()
- void [stop](#) ()
- void [selectReferenceVoltage](#) (const [referenceVoltage](#) &ar_refVoltage)
- void [selectAnalogInput](#) ([io::Pin](#) a_pin)
- void [selectClockPrescaler](#) (const [clockPrescaler](#) &ar_clockPrescaler)
- void [enableConversionCompleteInterrupt](#) (const uint8_t a_enable)
- void [enableAutoTrigger](#) (const uint8_t a_enable)
- void [selectAutoTriggerSource](#) (const [autoTriggerSource](#) &ar_autoTriggerSource)
- uint8_t [conversionComplete](#) ()
- void [getConversionResult](#) (uint16_t *ap_resultData, const [resolution](#) &ar_resolution=[resolution::res_10bit](#))

Static Public Member Functions

- static [ADConverter](#) & [getInstance](#) (const [referenceVoltage](#) &ar_refVoltage=[referenceVoltage::AVCC](#), const [clockPrescaler](#) &ar_clockPrescaler=[clockPrescaler::PS_128](#), const [autoTriggerSource](#) &ar_autoTriggerSource=[autoTriggerSource::freeRunning](#), const [io::Pin](#) &ar_pin=[io::Pin](#)(0, [io::PortC](#)))
- static void [conversionCompleteServiceRoutine](#) () __asm__([STR\(ADC_CONVERSION_COMPLETE_INTERRUPT\)](#))
__attribute__((__signal__

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [ADConverter](#) (const [referenceVoltage](#) &ar_refVoltage, const [clockPrescaler](#) &ar_clockPrescaler, const [autoTriggerSource](#) &ar_autoTriggerSource, const [io::Pin](#) &ar_pin)
- [~ADConverter](#) ()
Destructor.
- [ADConverter](#) (const [ADConverter](#) &)
Overried Copy constructor.
- const [ADConverter](#) & [operator=](#) (const [ADConverter](#) &)
Override assign operator.

Static Private Attributes

- static volatile uint16_t * [mp_conversionResult](#) = nullptr
pointer to receiver buffer
- static uint8_t [m_resolution](#) = 10
pointer to receiver buffer
- static volatile uint8_t [m_conversionComplete](#) = 0
ready to receive flag

6.1.1 Detailed Description

Definition at line 129 of file [ADC.h](#).

6.1.2 Constructor & Destructor Documentation

6.1.2.1 ADConverter() [1/2]

```
core::ADConverter::ADConverter (
    const referenceVoltage & ar_refVoltage,
    const clockPrescaler & ar_clockPrescaler,
    const autoTriggerSource & ar_autoTriggerSource,
    const io::Pin & ar_pin ) [private]
```

Definition at line 23 of file [ADC.cpp](#).

```
00027 {
00028     core::MCU::enableADC(1);
00029     selectAnalogInput(ar_pin);
00030     selectReferenceVoltage(ar_refVoltage);
00031     selectClockPrescaler(ar_clockPrescaler);
00032     enableAutoTrigger(1);
00033     selectAutoTriggerSource(ar_autoTriggerSource);
00034     sei();
00035     enableConversionCompleteInterrupt(1);
00036
00037 }
00038 }
```

References [core::MCU::enableADC\(\)](#).

6.1.2.2 ~ADConverter()

```
core::ADConverter::~~ADConverter ( ) [private]
```

Destructor.

Definition at line 41 of file [ADC.cpp](#).

```
00042 {
00043
00044 }
```

6.1.2.3 ADConverter() [2/2]

```
core::ADConverter::ADConverter (
    const ADConverter & ) [private]
```

Overried Copy constructor.

6.1.3 Member Function Documentation

6.1.3.1 conversionComplete()

```
uint8_t core::ADConverter::conversionComplete ( )
```

Definition at line 255 of file [ADC.cpp](#).

```
00256 {
00257     return m_conversionComplete;
00258
00259 }
```

6.1.3.2 conversionCompleteServiceRoutine()

```
void core::ADConverter::conversionCompleteServiceRoutine ( ) [static]
```

Definition at line 109 of file [ADC.cpp](#).

```
00110 {
00111
00112     static uint32_t l_resultData = 0;
00113     static uint16_t l_resultDataIndex = 0;
00114
00115     m_conversionComplete = 0;
00116     switch (m_resolution)
00117     {
00118     case 8:
00119     {
00120         *mp_conversionResult = ADC >> 8;
00121         m_conversionComplete = 1;
00122         break;
00123     }
00124     case 9:
00125     {
00126         *mp_conversionResult = ADC >> 7;
00127         m_conversionComplete = 1;
```

```
00128         break;
00129     }
00130     case 10:
00131     {
00132         *mp_conversionResult = ADC;
00133         m_conversionComplete = 1;
00134         break;
00135     }
00136     case 11:
00137     {
00138
00139         if (l_resultDataIndex < 4)
00140         {
00141             l_resultData += ADC;
00142             l_resultDataIndex++;
00143         }
00144         else
00145         {
00146             *mp_conversionResult = l_resultData > 1;
00147             l_resultData = 0;
00148             l_resultDataIndex = 0;
00149             m_conversionComplete = 1;
00150         }
00151     }
00152     break;
00153 }
00154 case 12:
00155 {
00156     if (l_resultDataIndex < 16)
00157     {
00158         l_resultData += ADC;
00159         l_resultDataIndex++;
00160     }
00161     else
00162     {
00163         *mp_conversionResult = l_resultData > 2;
00164         l_resultData = 0;
00165         l_resultDataIndex = 0;
00166         m_conversionComplete = 1;
00167     }
00168     break;
00169 }
00170 case 13:
00171 {
00172     if (l_resultDataIndex < 64)
00173     {
00174         l_resultData += ADC;
00175         l_resultDataIndex++;
00176     }
00177     else
00178     {
00179         *mp_conversionResult = l_resultData > 3;
00180         l_resultData = 0;
00181         l_resultDataIndex = 0;
00182         m_conversionComplete = 1;
00183     }
00184     break;
00185 }
00186 case 14:
00187 {
00188     if (l_resultDataIndex < 256)
00189     {
00190         l_resultData += ADC;
00191         l_resultDataIndex++;
00192     }
00193     else
00194     {
00195         *mp_conversionResult = l_resultData > 4;
00196         l_resultData = 0;
00197         l_resultDataIndex = 0;
00198         m_conversionComplete = 1;
00199     }
00200     break;
00201 }
00202 case 15:
00203 {
00204     if (l_resultDataIndex < 1024)
00205     {
00206         l_resultData += ADC;
```

```

00215         l_resultDataIndex++;
00216     }
00217 }
00218 else
00219 {
00220     *mp_conversionResult = l_resultData >> 5;
00221     l_resultData = 0;
00222     l_resultDataIndex = 0;
00223     m_conversionComplete = 1;
00224 }
00225 }
00226 break;
00227 }
00228 case 16:
00229 {
00230     if (l_resultDataIndex < 4096)
00231     {
00232         l_resultData += ADC;
00233         l_resultDataIndex++;
00234     }
00235     else
00236     {
00237         *mp_conversionResult = l_resultData >> 6;
00238         l_resultData = 0;
00239         l_resultDataIndex = 0;
00240         m_conversionComplete = 1;
00241     }
00242     break;
00243 }
00244 }
00245 }
00246 }
00247 }
00248 }
00249 }
00250 }
00251 }
00252 }
00253 }

```

6.1.3.3 enableAutoTrigger()

```

void core::ADConverter::enableAutoTrigger (
    const uint8_t a_enable )

```

Definition at line 73 of file [ADC.cpp](#).

```

00074 {
00075     if (a_enable) {
00076         ADC_ENABLE_AUTOTRIGGER;
00077     } else {
00078         ADC_DISABLE_AUTOTRIGGER;
00079     }
00080 }
00081 }
00082 }

```

References [ADC_DISABLE_AUTOTRIGGER](#), and [ADC_ENABLE_AUTOTRIGGER](#).

6.1.3.4 enableConversionCompleteInterrupt()

```

void core::ADConverter::enableConversionCompleteInterrupt (
    const uint8_t a_enable )

```

Definition at line 84 of file [ADC.cpp](#).

```

00085 {
00086     if (a_enable) {
00087         ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT;
00088     }

```

```

00089     } else {
00090         ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT;
00091     }
00092 }
00093 }

```

References [ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT](#), and [ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT](#).

6.1.3.5 getConversionResult()

```

void core::ADConverter::getConversionResult (
    uint16_t * ap_resultData,
    const resolution & ar_resolution = resolution::res_10bit )

```

Definition at line 262 of file [ADC.cpp](#).

```

00263 {
00264     mp_conversionResult = ap_resultData;
00265
00266     switch (ar_resolution)
00267     {
00268         case core::resolution::res_8bit:
00269         {
00270             ADC_ADJUST_RESULT_LEFT;
00271             m_resolution = 8;
00272             break;
00273         }
00274         case core::resolution::res_9bit:
00275         {
00276             ADC_ADJUST_RESULT_LEFT;
00277             m_resolution = 9;
00278             break;
00279         }
00280         case core::resolution::res_10bit:
00281         {
00282             ADC_ADJUST_RESULT_RIGHT;
00283             m_resolution = 10;
00284             break;
00285         }
00286         case core::resolution::res_11bit:
00287         {
00288
00289             m_resolution = 11;
00290             break;
00291         }
00292         case core::resolution::res_12bit:
00293         {
00294             m_resolution = 12;
00295             break;
00296         }
00297         case core::resolution::res_13bit:
00298         {
00299             m_resolution = 13;
00300             break;
00301         }
00302         case core::resolution::res_14bit:
00303         {
00304             m_resolution = 14;
00305             break;
00306         }
00307         case core::resolution::res_15bit:
00308         {
00309             m_resolution = 15;
00310             break;
00311         }
00312         case core::resolution::res_16bit:
00313         {
00314             m_resolution = 16;
00315             break;
00316         }
00317     }
00318
00319 }
00320 }

```

References [ADC_ADJUST_RESULT_LEFT](#), [ADC_ADJUST_RESULT_RIGHT](#), [core::res_10bit](#), [core::res_11bit](#), [core::res_12bit](#), [core::res_13bit](#), [core::res_14bit](#), [core::res_15bit](#), [core::res_16bit](#), [core::res_8bit](#), and [core::res_9bit](#).

6.1.3.6 getInstance()

```
core::ADConverter & core::ADConverter::getInstance (
    const referenceVoltage & ar_refVoltage = referenceVoltage::AVCC,
    const clockPrescaler & ar_clockPrescaler = clockPrescaler::PS_128,
    const autoTriggerSource & ar_autoTriggerSource = autoTriggerSource::freeRunning,
    const io::Pin & ar_pin = io::Pin(0,io::PortC) ) [static]
```

Definition at line 9 of file [ADC.cpp](#).

```
00013 {
00014
00015     static ADConverter l_instance(ar_refVoltage,
00016                                   ar_clockPrescaler,
00017                                   ar_autoTriggerSource,
00018                                   ar_pin);
00019
00020     return l_instance;
00021 }
```

6.1.3.7 operator=()

```
const ADConverter& core::ADConverter::operator= (
    const ADConverter & ) [private]
```

Override assign operator.

6.1.3.8 selectAnalogInput()

```
void core::ADConverter::selectAnalogInput (
    io::Pin a_pin )
```

Definition at line 53 of file [ADC.cpp](#).

```
00054 {
00055     a_pin.toInput(0);
00056     ADC_SELECT_ANALOG_INPUT(a_pin.getPinNumber());
00057     ADC_DISABLE_DIGITAL_INPUT_REGISTER(a_pin.getPinNumber());
00058
00059 }
```

References [ADC_DISABLE_DIGITAL_INPUT_REGISTER](#), [ADC_SELECT_ANALOG_INPUT](#), [io::Pin::getPinNumber\(\)](#), and [io::Pin::toInput\(\)](#).

6.1.3.9 selectAutoTriggerSource()

```
void core::ADConverter::selectAutoTriggerSource (
    const autoTriggerSource & ar_autoTriggerSource )
```

Definition at line 102 of file [ADC.cpp](#).

```
00103 {
00104     ADC_SELECT_AUTO_TRIGGER_SOURCE(static_cast<uint8_t>(ar_autoTriggerSource));
00105
00106
00107 }
```

References [ADC_SELECT_AUTO_TRIGGER_SOURCE](#).

6.1.3.10 selectClockPrescaler()

```
void core::ADConverter::selectClockPrescaler (
    const clockPrescaler & ar_clockPrescaler )
```

Definition at line 95 of file [ADC.cpp](#).

```
00096 {
00097     ADC_SELECT_CLOCK_PRESCALER(static_cast<uint8_t>(ar_clockPrescaler));
00098
00099 }
```

References [ADC_SELECT_CLOCK_PRESCALER](#).

6.1.3.11 selectReferenceVoltage()

```
void core::ADConverter::selectReferenceVoltage (
    const referenceVoltage & ar_refVoltage )
```

Definition at line 47 of file [ADC.cpp](#).

```
00048 {
00049     ADC_SELECT_REF_VOLTAGE(static_cast<uint8_t>(ar_refVoltage));
00050
00051 }
```

References [ADC_SELECT_REF_VOLTAGE](#).

6.1.3.12 start()

```
void core::ADConverter::start ( )
```

Definition at line 61 of file [ADC.cpp](#).

```
00062 {
00063     ADC_ENABLE;
00064     ADC_START_CONVERSION;
00065 }
```

References [ADC_ENABLE](#), and [ADC_START_CONVERSION](#).

6.1.3.13 stop()

```
void core::ADConverter::stop ( )
```

Definition at line 67 of file [ADC.cpp](#).

```
00068 {
00069     ADC_STOP_CONVERSION;
00070     ADC_DISABLE;
00071 }
```

References [ADC_DISABLE](#), and [ADC_STOP_CONVERSION](#).

6.1.4 Member Data Documentation

6.1.4.1 `__externally_visible__`

```
void core::ADConverter::__externally_visible__
```

Definition at line 160 of file [ADC.h](#).

6.1.4.2 `__used__`

```
void core::ADConverter::__used__
```

Definition at line 160 of file [ADC.h](#).

6.1.4.3 `m_conversionComplete`

```
volatile uint8_t core::ADConverter::m_conversionComplete = 0 [static], [private]
```

ready to receive flag

Definition at line 192 of file [ADC.h](#).

6.1.4.4 `m_resolution`

```
uint8_t core::ADConverter::m_resolution = 10 [static], [private]
```

pointer to receiver buffer

Definition at line 190 of file [ADC.h](#).

6.1.4.5 `mp_conversionResult`

```
volatile uint16_t * core::ADConverter::mp_conversionResult = nullptr [static], [private]
```

pointer to receiver buffer

Definition at line 187 of file [ADC.h](#).

6.2 core::AnalogComparator Class Reference

```
#include <AnalogComparator.h>
```

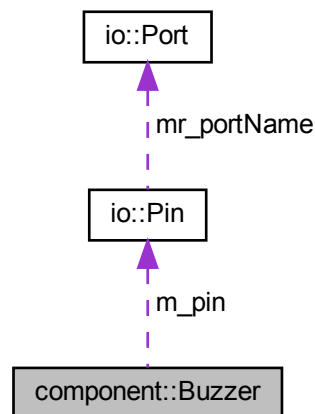
6.2.1 Detailed Description

Definition at line 24 of file [AnalogComparator.h](#).

6.3 component::Buzzer Class Reference

```
#include <Buzzer.h>
```

Collaboration diagram for component::Buzzer:



Public Member Functions

- [Buzzer](#) (const [io::Pin](#) &ar_pin)
- [~Buzzer](#) ()
- void [buzz](#) (const uint16_t &ar_period_us, const uint16_t &ar_duration_ms)
- template<typename TC >
void [buzz](#) (TC &ar_timerCounter, const uint16_t &ar_period_us, uint16_t &ar_duration_ms, const [core::channel](#) &ar_channel=[core::channel::A](#), const [core::clockSource](#) &ar_clockSource=[core::clockSource::PS_64](#))

Private Attributes

- [io::Pin](#) `m_pin`
pin object

6.3.1 Detailed Description

Definition at line 69 of file [Buzzer.h](#).

6.3.2 Constructor & Destructor Documentation

6.3.2.1 Buzzer()

```
component::Buzzer::Buzzer (
    const io::Pin & ar_pin )
```

Definition at line 4 of file [Buzzer.cpp](#).

```
00005         : m_pin(ar_pin)
00006 {
00007     m_pin.toOutput();
00008
00009 }
```

References [m_pin](#), and [io::Pin::toOutput\(\)](#).

6.3.2.2 ~Buzzer()

```
component::Buzzer::~Buzzer ( )
```

Definition at line 11 of file [Buzzer.cpp](#).

```
00012 {
00013
00014 }
```

6.3.3 Member Function Documentation

6.3.3.1 buzz() [1/2]

```
void component::Buzzer::buzz (
    const uint16_t & ar_period_us,
    const uint16_t & ar_duration_ms )
```

Definition at line 18 of file [Buzzer.cpp](#).

```
00019 {
00020     uint32_t l_duration_us = ar_duration_ms*1000UL;
00021
00022     for (uint32_t i = 0; i < l_duration_us; i += ar_period_us)
00023     {
00024         /* For loop with variable delay selects the pitch */
00025         // _delay_us() needs a constant defined at compile time
00026         for (uint16_t j = 0; j < ar_period_us; j++)
00027         {
00028             _delay_us(1);
00029         }
00030         m_pin.toggle();
00031     }
00032     m_pin.setLow();
00033
00034 }
```

6.3.3.2 buzz() [2/2]

```
template<typename TC >
void component::Buzzer::buzz (
    TC & ar_timerCounter,
    const uint16_t & ar_period_us,
    uint16_t & ar_duration_ms,
    const core::channel & ar_channel = core::channel::A,
    const core::clockSource & ar_clockSource = core::clockSource::PS_64 ) [inline]
```

Definition at line 81 of file [Buzzer.h](#).

```
00087 {
00088     ar_timerCounter.selectOperationMode(core::operationMode::CTC_OCR);
00089     ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::toggle);
00090     ar_timerCounter.setCounter(0);
00091     ar_timerCounter.setOutputCompareRegister(ar_channel, ar_period_us);
00092     // start timer
00093     ar_timerCounter.start();
00094     // wait for the pitch duration
00095     while (ar_duration_ms) {
00096         _delay_ms(1);
00097         ar_duration_ms--;
00098     }
00099     // no buzz
00100     ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::normal);
00101     ar_timerCounter.stop();
00102 }
```

References [core::CTC_OCR](#), [core::normal](#), and [core::toggle](#).

6.3.4 Member Data Documentation

6.3.4.1 m_pin

```
io::Pin component::Buzzer::m_pin [private]
```

pin object

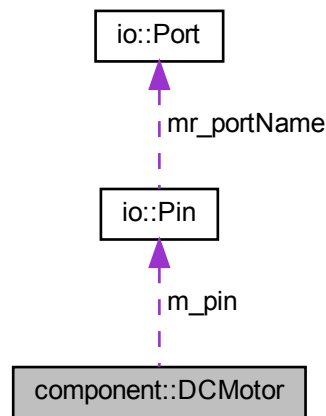
Definition at line 109 of file [Buzzer.h](#).

Referenced by [Buzzer\(\)](#).

6.4 component::DCMotor Class Reference

```
#include <DCMotor.h>
```

Collaboration diagram for component::DCMotor:



Public Member Functions

- [DCMotor](#) (const [io::Pin](#) &ar_pin)
- [~DCMotor](#) ()
- void [on](#) ()
Turn servo motor On.
- void [off](#) ()
Turn servo motor Off.
- void [toggle](#) ()
Toggle servo motor state.
- template<typename TC >
void [spin](#) (TC &ar_timerCounter, const uint16_t &ar_speed, const [core::channel](#) &ar_channel=[core::channel::A](#))
- template<typename TC >
void [stop](#) (TC &ar_timerCounter)
- template<typename TC >
void [connect](#) (TC &ar_timerCounter, const [core::channel](#) &ar_channel=[core::channel::A](#))
- template<typename TC >
void [disconnect](#) (TC &ar_timerCounter, const [core::channel](#) &ar_channel=[core::channel::A](#))

Private Attributes

- [io::Pin m_pin](#)
pin object

6.4.1 Detailed Description

Definition at line 126 of file [DCMotor.h](#).

6.4.2 Constructor & Destructor Documentation

6.4.2.1 DCMotor()

```
component::DCMotor::DCMotor (
    const io::Pin & ar_pin )
```

Definition at line 3 of file [DCMotor.cpp](#).

```
00004         : m_pin(ar_pin)
00005 {
00006     m_pin.toOutput();
00007
00008 }
```

References [m_pin](#), and [io::Pin::toOutput\(\)](#).

6.4.2.2 ~DCMotor()

```
component::DCMotor::~DCMotor ( )
```

Definition at line 11 of file [DCMotor.cpp](#).

```
00012 {
00013
00014 }
```

6.4.3 Member Function Documentation

6.4.3.1 connect()

```
template<typename TC >
void component::DCMotor::connect (
    TC & ar_timerCounter,
    const core::channel & ar_channel = core::channel::A ) [inline]
```

Definition at line 164 of file [DCMotor.h](#).

```
00166     {
00167         ar_timerCounter.selectOperationMode(core::operationMode::fast_PWM);
00168         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::clear);
00169         ar_timerCounter.setCounter(0);
00170
00171     }
```

References [core::clear](#), and [core::fast_PWM](#).

6.4.3.2 disconnect()

```
template<typename TC >
void component::DCMotor::disconnect (
    TC & ar_timerCounter,
    const core::channel & ar_channel = core::channel::A ) [inline]
```

Definition at line 174 of file [DCMotor.h](#).

```
00176     {
00177         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::normal);
00178         ar_timerCounter.stop();
00179     }
```

References [core::normal](#).

6.4.3.3 off()

```
void component::DCMotor::off ( )
```

Turn servo motor Off.

Definition at line 21 of file [DCMotor.cpp](#).

```
00022 {
00023     m_pin.setLow();
00024 }
```

6.4.3.4 on()

```
void component::DCMotor::on ( )
```

Turn servo motor On.

Definition at line 16 of file [DCMotor.cpp](#).

```
00017 {
00018     m_pin.setHigh();
00019 }
```

6.4.3.5 spin()

```
template<typename TC >
void component::DCMotor::spin (
    TC & ar_timerCounter,
    const uint16_t & ar_speed,
    const core::channel & ar_channel = core::channel::A ) [inline]
```

Definition at line 144 of file [DCMotor.h](#).

```
00148     {
00149
00150         ar_timerCounter.setOutputCompareRegister(ar_channel, ar_speed);
00151         ar_timerCounter.start();
00152
00153
00154     }
```

6.4.3.6 stop()

```
template<typename TC >
void component::DCMotor::stop (
    TC & ar_timerCounter ) [inline]
```

Definition at line 156 of file [DCMotor.h](#).

```
00157     {
00158         ar_timerCounter.stop();
00159     }
00160
00161 }
```

6.4.3.7 toggle()

```
void component::DCMotor::toggle ( )
```

Toggle servo motor state.

Definition at line 26 of file [DCMotor.cpp](#).

```
00027 {
00028     m_pin.toggle();
00029 }
00030 }
```

6.4.4 Member Data Documentation

6.4.4.1 m_pin

```
io::Pin component::DCMotor::m_pin [private]
```

pin object

Definition at line 185 of file [DCMotor.h](#).

Referenced by [DCMotor\(\)](#).

6.5 core::ExternInterrupt Class Reference

```
#include <ExternInterrupt.h>
```

Public Member Functions

- void [setInt0SenseControl](#) (const [senseControl](#) &ar_senseControl)
- void [setInt1SenseControl](#) (const [senseControl](#) &ar_senseControl)
- void [enableInt0](#) (const uint8_t a_enable)
- void [enableInt1](#) (const uint8_t a_enable)
- void [enablePinChange](#) (const [pinChangePort](#) &ar_pinChangePort, const uint8_t a_enable)
- void [enablePinChangeMaskPortB](#) (const uint8_t a_pinNumber, const uint8_t a_enable)
- void [enablePinChangeMaskPortC](#) (const uint8_t a_pinNumber, const uint8_t a_enable)
- void [enablePinChangeMaskPortD](#) (const uint8_t a_pinNumber, const uint8_t a_enable)

Static Public Member Functions

- static [ExternInterrupt](#) & [getInstance](#) ()
- static void [Int0ServiceRoutine](#) () __asm__(STR(EXT_INT_INT0_INTERRUPT)) __attribute__((__signal__
- static void [Int1ServiceRoutine](#) () __asm__(STR(EXT_INT_INT1_INTERRUPT)) __attribute__((__signal__
- static void [pinChangePortBServiceRoutine](#) () __asm__(STR(EXT_INT_PIN_CHANGE_PORTB_INTERRUPT)) __attribute__((__signal__
- static void [pinChangePortCServiceRoutine](#) () __asm__(STR(EXT_INT_PIN_CHANGE_PORTC_INTERRUPT)) __attribute__((__signal__
- static void [pinChangePortDServiceRoutine](#) () __asm__(STR(EXT_INT_PIN_CHANGE_PORTD_INTERRUPT)) __attribute__((__signal__

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [ExternInterrupt](#) ()
- [~ExternInterrupt](#) ()
Destructor.
- [ExternInterrupt](#) (const [ExternInterrupt](#) &)
Overried Copy constructor.
- const [ExternInterrupt](#) & [operator=](#) (const [ExternInterrupt](#) &)
Override assign operator.

6.5.1 Detailed Description

Definition at line 162 of file [ExternInterrupt.h](#).

6.5.2 Constructor & Destructor Documentation

6.5.2.1 ExternInterrupt() [1/2]

```
core::ExternInterrupt::ExternInterrupt ( ) [private]
```

Definition at line 11 of file [ExternInterrupt.cpp](#).

```
00012 {
00013     sei();
00014
00015 }
```

6.5.2.2 ~ExternInterrupt()

```
core::ExternInterrupt::~~ExternInterrupt ( ) [private]
```

Destructor.

Definition at line 17 of file [ExternInterrupt.cpp](#).

```
00018 {  
00019  
00020 }
```

6.5.2.3 ExternInterrupt() [2/2]

```
core::ExternInterrupt::ExternInterrupt (  
    const ExternInterrupt & ) [private]
```

Overried Copy constructor.

6.5.3 Member Function Documentation

6.5.3.1 enableInt0()

```
void core::ExternInterrupt::enableInt0 (  
    const uint8_t a_enable )
```

Definition at line 34 of file [ExternInterrupt.cpp](#).

```
00035 {  
00036     if (a_enable) {  
00037         EXT\_INT\_ENABLE\_INT0;  
00038     } else {  
00039         EXT\_INT\_DISABLE\_INT0;  
00040     }  
00041 }  
00042  
00043 }
```

References [EXT_INT_DISABLE_INT0](#), and [EXT_INT_ENABLE_INT0](#).

6.5.3.2 enableInt1()

```
void core::ExternInterrupt::enableInt1 (  
    const uint8_t a_enable )
```

Definition at line 45 of file [ExternInterrupt.cpp](#).

```
00046 {  
00047     if (a_enable) {  
00048         EXT\_INT\_ENABLE\_INT1;  
00049     } else {  
00050         EXT\_INT\_DISABLE\_INT1;  
00051     }  
00052 }  
00053 }
```

References [EXT_INT_DISABLE_INT1](#), and [EXT_INT_ENABLE_INT1](#).

6.5.3.3 enablePinChange()

```
void core::ExternInterrupt::enablePinChange (
    const pinChangePort & ar_pinChangePort,
    const uint8_t a_enable )
```

Definition at line 56 of file [ExternInterrupt.cpp](#).

```
00057 {
00058     if (a_enable) {
00059         EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT(static_cast<uint8_t>(ar_pinChangePort));
00060     } else {
00061         EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT(static_cast<uint8_t>(ar_pinChangePort));
00062     }
00063 }
00064
00065 }
```

References [EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT](#), and [EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT](#).

6.5.3.4 enablePinChangeMaskPortB()

```
void core::ExternInterrupt::enablePinChangeMaskPortB (
    const uint8_t a_pinNumber,
    const uint8_t a_enable )
```

Definition at line 67 of file [ExternInterrupt.cpp](#).

```
00068 {
00069     if (a_enable) {
00070         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(a_pinNumber);
00071     } else {
00072         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(a_pinNumber);
00073     }
00074 }
00075
00076 }
```

References [EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB](#).

6.5.3.5 enablePinChangeMaskPortC()

```
void core::ExternInterrupt::enablePinChangeMaskPortC (
    const uint8_t a_pinNumber,
    const uint8_t a_enable )
```

Definition at line 79 of file [ExternInterrupt.cpp](#).

```
00080 {
00081     if (a_enable) {
00082         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(a_pinNumber);
00083     } else {
00084         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(a_pinNumber);
00085     }
00086 }
00087
00088 }
```

References [EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC](#).

6.5.3.6 enablePinChangeMaskPortD()

```
void core::ExternInterrupt::enablePinChangeMaskPortD (
    const uint8_t a_pinNumber,
    const uint8_t a_enable )
```

Definition at line 90 of file [ExternInterrupt.cpp](#).

```
00091 {
00092     if (a_enable) {
00093         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(a_pinNumber);
00094     } else {
00095         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(a_pinNumber);
00096     }
00097 }
00098 }
```

References [EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD](#).

6.5.3.7 getInstance()

```
core::ExternInterrupt & core::ExternInterrupt::getInstance ( ) [static]
```

Definition at line 3 of file [ExternInterrupt.cpp](#).

```
00004 {
00005     static ExternInterrupt l_instance;
00006     return l_instance;
00007 }
00008 }
```

6.5.3.8 Int0ServiceRoutine()

```
static void core::ExternInterrupt::Int0ServiceRoutine ( ) [static]
```

6.5.3.9 Int1ServiceRoutine()

```
static void core::ExternInterrupt::Int1ServiceRoutine ( ) [static]
```

6.5.3.10 operator=()

```
const ExternInterrupt& core::ExternInterrupt::operator= (
    const ExternInterrupt & ) [private]
```

Override assign operator.

6.5.3.11 pinChangePortBServiceRoutine()

```
static void core::ExternInterrupt::pinChangePortBServiceRoutine ( ) [static]
```

6.5.3.12 pinChangePortCServiceRoutine()

```
static void core::ExternInterrupt::pinChangePortCServiceRoutine ( ) [static]
```

6.5.3.13 pinChangePortDServiceRoutine()

```
static void core::ExternInterrupt::pinChangePortDServiceRoutine ( ) [static]
```

6.5.3.14 setInt0SenseControl()

```
void core::ExternInterrupt::setInt0SenseControl (
    const senseControl & ar_senseControl )
```

Definition at line 22 of file [ExternInterrupt.cpp](#).

```
00023 {
00024     EXT\_INT\_SET\_INT0\_SENSE\_CONTROL(static_cast<uint8_t>(ar_senseControl));
00025
00026 }
```

References [EXT_INT_SET_INT0_SENSE_CONTROL](#).

6.5.3.15 setInt1SenseControl()

```
void core::ExternInterrupt::setInt1SenseControl (
    const senseControl & ar_senseControl )
```

Definition at line 28 of file [ExternInterrupt.cpp](#).

```
00029 {
00030     EXT\_INT\_SET\_INT1\_SENSE\_CONTROL(static_cast<uint8_t>(ar_senseControl));
00031
00032 }
```

References [EXT_INT_SET_INT1_SENSE_CONTROL](#).

6.5.4 Member Data Documentation

6.5.4.1 `__externally_visible__`

```
static void core::ExternInterrupt::__externally_visible__
```

Definition at line 185 of file [ExternInterrupt.h](#).

6.5.4.2 `__used__`

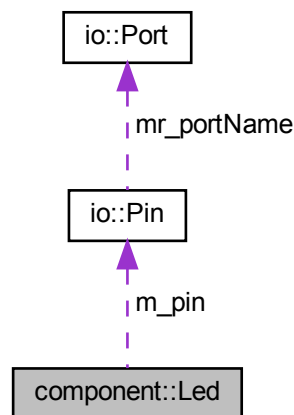
```
static void core::ExternInterrupt::__used__
```

Definition at line 185 of file [ExternInterrupt.h](#).

6.6 component::Led Class Reference

```
#include <Led.h>
```

Collaboration diagram for component::Led:



Public Member Functions

- [Led](#) (const [io::Pin](#) &ar_pin)
Constructor.
- [~Led](#) ()
Destructor.
- void [on](#) ()
Turn led On.
- void [off](#) ()
Turn led Off.
- void [toggle](#) ()
Toggle led state.
- uint8_t [isOn](#) ()
Is led On.
- uint8_t [isOff](#) ()
Is led Off.

Private Attributes

- [io::Pin m_pin](#)
pin object

6.6.1 Detailed Description

Definition at line 32 of file [Led.h](#).

6.6.2 Constructor & Destructor Documentation

6.6.2.1 Led()

```
component::Led::Led (
    const io::Pin & ar_pin )
```

Constructor.

Initializes the led object

Parameters

ar_pin	constant reference to pin object
------------------------	----------------------------------

Definition at line 3 of file [Led.cpp](#).

```
00004         : m_pin(ar_pin)
00005 {
00006     m_pin.toOutput();
00007 }
```

References [m_pin](#), and [io::Pin::toOutput\(\)](#).

6.6.2.2 ~Led()

```
component::Led::~Led ( )
```

Destructor.

Definition at line 9 of file [Led.cpp](#).

```
00010 {
00011
00012 }
```

6.6.3 Member Function Documentation

6.6.3.1 isOff()

```
uint8_t component::Led::isOff ( )
```

Is led Off.

Definition at line 41 of file [Led.cpp](#).

```
00042 {  
00043     return m_pin.isLow();  
00044 }  
00045 }
```

6.6.3.2 isOn()

```
uint8_t component::Led::isOn ( )
```

Is led On.

Definition at line 34 of file [Led.cpp](#).

```
00035 {  
00036     return m_pin.isHigh();  
00037 }  
00038 }
```

6.6.3.3 off()

```
void component::Led::off ( )
```

Turn led Off.

Definition at line 21 of file [Led.cpp](#).

```
00022 {  
00023     m_pin.setLow();  
00024 }  
00025 }
```

6.6.3.4 on()

```
void component::Led::on ( )
```

Turn led On.

Definition at line 15 of file [Led.cpp](#).

```
00016 {  
00017     m_pin.setHigh();  
00018 }  
00019 }
```


6.6.3.5 toggle()

```
void component::Led::toggle ( )
```

Toggle led state.

Definition at line 28 of file [Led.cpp](#).

```
00029 {
00030     m_pin.toggle();
00031
00032 }
```

6.6.4 Member Data Documentation

6.6.4.1 m_pin

```
io::Pin component::Led:m_pin [private]
```

pin object

Definition at line 67 of file [Led.h](#).

Referenced by [Led\(\)](#).

6.7 core::MCU Class Reference

```
#include <MCU.h>
```

Static Public Member Functions

- static void [init](#) ()
- static void [selectSleepMode](#) (const [sleepMode](#) &a_sleepMode)
- static void [goToSleep](#) (const [BODMode](#) &a_BODMode)
- static void [sleepEnable](#) (const uint8_t a_enable)
- static void [enableUSART0](#) (const uint8_t a_enable)
- static void [enableTimerCounter0](#) (const uint8_t a_enable)
- static void [enableTimerCounter1](#) (const uint8_t a_enable)
- static void [enableTimerCounter2](#) (const uint8_t a_enable)
- static void [enableTWI](#) (const uint8_t a_enable)
- static void [enableSPI](#) (const uint8_t a_enable)
- static void [enableADC](#) (const uint8_t a_enable)
- static void [disableBOD](#) ()

6.7.1 Detailed Description

Definition at line 91 of file [MCU.h](#).

6.7.2 Member Function Documentation

6.7.2.1 disableBOD()

```
void core::MCU::disableBOD ( ) [static]
```

Definition at line 126 of file [MCU.cpp](#).

```
00127 {  
00128     MCU_BOD_DISABLE;  
00129 }
```

References [MCU_BOD_DISABLE](#).

6.7.2.2 enableADC()

```
void core::MCU::enableADC (  
    const uint8_t a_enable ) [static]
```

Definition at line 117 of file [MCU.cpp](#).

```
00118 {  
00119     if (a_enable) {  
00120         MCU_ADC_ENABLE;  
00121     } else {  
00122         MCU_ADC_DISABLE;  
00123     }  
00124 }
```

References [MCU_ADC_DISABLE](#), and [MCU_ADC_ENABLE](#).

Referenced by [core::ADConverter::ADConverter\(\)](#), and [init\(\)](#).

6.7.2.3 enableSPI()

```
void core::MCU::enableSPI (  
    const uint8_t a_enable ) [static]
```

Definition at line 107 of file [MCU.cpp](#).

```
00108 {  
00109     if (a_enable) {  
00110         MCU_SPI_ENABLE;  
00111     } else {  
00112         MCU_SPI_DISABLE;  
00113     }  
00114 }  
00115 }
```

References [MCU_SPI_DISABLE](#), and [MCU_SPI_ENABLE](#).

Referenced by [init\(\)](#), and [io::SPI::SPI\(\)](#).

6.7.2.4 enableTimerCounter0()

```
void core::MCU::enableTimerCounter0 (
    const uint8_t a_enable ) [static]
```

Definition at line 67 of file [MCU.cpp](#).

```
00068 {
00069     if (a_enable) {
00070         MCU_TIMER0_ENABLE;
00071     } else {
00072         MCU_TIMER0_DISABLE;
00073     }
00074 }
00075 }
```

References [MCU_TIMER0_DISABLE](#), and [MCU_TIMER0_ENABLE](#).

Referenced by [init\(\)](#), and [core::TimerCounter0::TimerCounter0\(\)](#).

6.7.2.5 enableTimerCounter1()

```
void core::MCU::enableTimerCounter1 (
    const uint8_t a_enable ) [static]
```

Definition at line 77 of file [MCU.cpp](#).

```
00078 {
00079     if (a_enable) {
00080         MCU_TIMER1_ENABLE;
00081     } else {
00082         MCU_TIMER1_DISABLE;
00083     }
00084 }
00085 }
```

References [MCU_TIMER1_DISABLE](#), and [MCU_TIMER1_ENABLE](#).

Referenced by [init\(\)](#), and [core::TimerCounter1::TimerCounter1\(\)](#).

6.7.2.6 enableTimerCounter2()

```
void core::MCU::enableTimerCounter2 (
    const uint8_t a_enable ) [static]
```

Definition at line 87 of file [MCU.cpp](#).

```
00088 {
00089     if (a_enable) {
00090         MCU_TIMER2_ENABLE;
00091     } else {
00092         MCU_TIMER2_DISABLE;
00093     }
00094 }
00095 }
```

References [MCU_TIMER2_DISABLE](#), and [MCU_TIMER2_ENABLE](#).

Referenced by [init\(\)](#), and [core::TimerCounter2::TimerCounter2\(\)](#).

6.7.2.7 enableTWI()

```
void core::MCU::enableTWI (
    const uint8_t a_enable ) [static]
```

Definition at line 97 of file [MCU.cpp](#).

```
00098 {
00099     if (a_enable) {
00100         MCU_TWI_ENABLE;
00101     } else {
00102         MCU_TWI_DISABLE;
00103     }
00104 }
00105 }
```

References [MCU_TWI_DISABLE](#), and [MCU_TWI_ENABLE](#).

Referenced by [init\(\)](#).

6.7.2.8 enableUSART0()

```
void core::MCU::enableUSART0 (
    const uint8_t a_enable ) [static]
```

Definition at line 57 of file [MCU.cpp](#).

```
00058 {
00059     if (a_enable) {
00060         MCU_USART0_ENABLE;
00061     } else {
00062         MCU_USART0_DISABLE;
00063     }
00064 }
00065 }
```

References [MCU_USART0_DISABLE](#), and [MCU_USART0_ENABLE](#).

Referenced by [init\(\)](#), and [io::USART0::USART0\(\)](#).

6.7.2.9 goToSleep()

```
void core::MCU::goToSleep (
    const BODMode & a_BODMode ) [static]
```

Definition at line 21 of file [MCU.cpp](#).

```
00022 {
00023     cli();
00024     switch (a_BODMode)
00025     {
00026         case core::BODMode::enabled:
00027         {
00028             sleepEnable(1);
00029             sei();
00030             sleep_cpu();
00031             sleepEnable(0);
00032             break;
00033         }
00034         case core::BODMode::disabled:
00035         {
00036             sleepEnable(1);
00037             disableBOD();
00038             sei();
00039             sleep_cpu();
00040             sleepEnable(0);
00041             break;
00042         }
00043     }
00044 }
00045 }
```

References [core::disabled](#), and [core::enabled](#).

6.7.2.10 init()

```
void core::MCU::init ( ) [static]
```

Definition at line 3 of file [MCU.cpp](#).

```
00004 {  
00005     enableUSART0(0);  
00006     enableTimerCounter0(0);  
00007     enableTimerCounter1(0);  
00008     enableTimerCounter2(0);  
00009     enableTWI(0);  
00010     enableSPI(0);  
00011     enableADC(0);  
00012  
00013 }
```

References [enableADC\(\)](#), [enableSPI\(\)](#), [enableTimerCounter0\(\)](#), [enableTimerCounter1\(\)](#), [enableTimerCounter2\(\)](#), [enableTWI\(\)](#), and [enableUSART0\(\)](#).

6.7.2.11 selectSleepMode()

```
void core::MCU::selectSleepMode (  
    const sleepMode & a_sleepMode ) [static]
```

Definition at line 15 of file [MCU.cpp](#).

```
00016 {  
00017     MCU_SELECT_SLEEP_MODE(static_cast<uint8_t>(a_sleepMode));  
00018  
00019 }
```

References [MCU_SELECT_SLEEP_MODE](#).

6.7.2.12 sleepEnable()

```
void core::MCU::sleepEnable (  
    const uint8_t ar_enable ) [static]
```

Definition at line 47 of file [MCU.cpp](#).

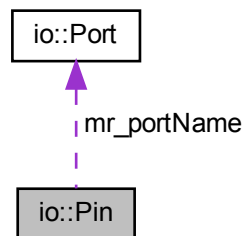
```
00048 {  
00049     if (a_enable) {  
00050         MCU_SLEEP_ENABLE;  
00051     } else {  
00052         MCU_SLEEP_DISABLE;  
00053     }  
00054  
00055 }
```

References [MCU_SLEEP_DISABLE](#), and [MCU_SLEEP_ENABLE](#).

6.8 io::Pin Class Reference

```
#include <Pin.h>
```

Collaboration diagram for io::Pin:



Public Member Functions

- [Pin](#) (const uint8_t a_pinNumber, const [Port](#) &ar_portName)
Constructor.
- [~Pin](#) ()
Destructor.
- void [toOutput](#) ()
Configures pin to output.
- void [toInput](#) (const uint8_t &ar_useInternalPullUp)
Configures pin to input.
- void [setLow](#) ()
Set pin to logic low.
- void [setHigh](#) ()
Set pin to logic high.
- void [toggle](#) ()
Toggle pin state.
- uint8_t [isHigh](#) ()
Check if pin is logic high.
- uint8_t [isLow](#) ()
Check if pin is logic low.
- uint8_t [getPinNumber](#) ()
Get pin number.

Private Attributes

- const [Port](#) & [mr_portName](#)
constant reference to port object
- const uint8_t [m_pinNumber](#)
pin number

6.8.1 Detailed Description

Definition at line 20 of file [Pin.h](#).

6.8.2 Constructor & Destructor Documentation

6.8.2.1 Pin()

```
io::Pin::Pin (
    const uint8_t a_pinNumber,
    const Port & ar_portName )
```

Constructor.

Initializes the pin object

@param ar_portName defines the port name of the avr chip
@param ar_pinNumber defines the pin number of the avr chip

Definition at line 4 of file [Pin.cpp](#).

```
00005         : mr_portName(mr_portName), m_pinNumber(a_pinNumber)
00006 {
00007
00008 }
```

6.8.2.2 ~Pin()

```
io::Pin::~~Pin ( )
```

Destructor.

Definition at line 11 of file [Pin.cpp](#).

```
00013 {
00014
00015 }
```

6.8.3 Member Function Documentation

6.8.3.1 getPinNumber()

```
uint8_t io::Pin::getPinNumber ( )
```

Get pin number.

Definition at line 73 of file [Pin.cpp](#).

```
00074 {
00075     return m_pinNumber;
00076 }
```

Referenced by [core::ADConverter::selectAnalogInput\(\)](#).

6.8.3.2 isHigh()

```
uint8_t io::Pin::isHigh ( )
```

Check if pin is logic high.

Definition at line 63 of file [Pin.cpp](#).

```
00064 {  
00065     return    *mr_portName.mp_pinReg & (1 << m_pinNumber);  
00066 }
```

6.8.3.3 isLow()

```
uint8_t io::Pin::isLow ( )
```

Check if pin is logic low.

Definition at line 68 of file [Pin.cpp](#).

```
00069 {  
00070     return    !(*mr_portName.mp_pinReg & (1 << m_pinNumber));  
00071 }
```

6.8.3.4 setHigh()

```
void io::Pin::setHigh ( )
```

Set pin to logic high.

Definition at line 47 of file [Pin.cpp](#).

```
00048 {  
00049     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))  
00050     {  
00051         *mr_portName.mp_portReg |= (1 << m_pinNumber);  
00052     }  
00053 }
```

6.8.3.5 setLow()

```
void io::Pin::setLow ( )
```

Set pin to logic low.

Definition at line 39 of file [Pin.cpp](#).

```
00040 {  
00041     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))  
00042     {  
00043         *mr_portName.mp_portReg &= ~(1 << m_pinNumber);  
00044     }  
00045 }
```


6.8.3.6 toggle()

```
void io::Pin::toggle ( )
```

Toggle pin state.

Definition at line 55 of file [Pin.cpp](#).

```
00056 {
00057     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))
00058     {
00059         *mr_portName.mp_portReg ^= 1 << m_pinNumber;
00060     }
00061 }
```

6.8.3.7 toInput()

```
void io::Pin::toInput (
    const uint8_t & ar_useInternalPullUp )
```

Configures pin to input.

Parameters

<i>ar_useInternalPullUp</i>	indicates if internal pull up resistor is used
-----------------------------	--

Definition at line 22 of file [Pin.cpp](#).

```
00023 {
00024     if (ar_useInternalPullUp)
00025     {
00026         *mr_portName.mp_portReg |= (1 << m_pinNumber);
00027         *mr_portName.mp_ddrReg  &= ~(1 << m_pinNumber);
00028     }
00029
00030 }
00031 else
00032 {
00033     *mr_portName.mp_portReg &= ~(1 << m_pinNumber);
00034     *mr_portName.mp_ddrReg  &= ~(1 << m_pinNumber);
00035 }
00036
00037 }
```

Referenced by [component::PushButton::PushButton\(\)](#), and [core::ADConverter::selectAnalogInput\(\)](#).

6.8.3.8 toOutput()

```
void io::Pin::toOutput ( )
```

Configures pin to output.

Definition at line 17 of file [Pin.cpp](#).

```
00018 {
00019     *mr_portName.mp_ddrReg |= (1 << m_pinNumber);
00020 }
```

Referenced by [component::Buzzer::Buzzer\(\)](#), [component::DCMotor::DCMotor\(\)](#), [component::Led::Led\(\)](#), [component::ServoMotor::ServoMotor\(\)](#), and [component::StepperMotor::StepperMotor\(\)](#).

6.8.4 Member Data Documentation

6.8.4.1 m_pinNumber

```
const uint8_t io::Pin::m_pinNumber [private]
```

pin number

Definition at line 66 of file [Pin.h](#).

6.8.4.2 mr_portName

```
const Port& io::Pin::mr_portName [private]
```

constant reference to port object

Definition at line 65 of file [Pin.h](#).

6.9 io::Port Struct Reference

Structure.

```
#include <Pin.h>
```

Public Attributes

- volatile uint8_t * [mp_ddrReg](#)
pointer to the data direction register
- volatile uint8_t * [mp_portReg](#)
pointer to the port register
- volatile uint8_t * [mp_pinReg](#)
pointer to the pin register

6.9.1 Detailed Description

Structure.

Contains pointers to the [Port](#)'s registers

Definition at line 11 of file [Pin.h](#).

6.9.2 Member Data Documentation

6.9.2.1 mp_ddrReg

```
volatile uint8_t* io::Port::mp_ddrReg
```

pointer to the data direction register

Definition at line 13 of file [Pin.h](#).

6.9.2.2 mp_pinReg

```
volatile uint8_t* io::Port::mp_pinReg
```

pointer to the pin register

Definition at line 17 of file [Pin.h](#).

6.9.2.3 mp_portReg

```
volatile uint8_t* io::Port::mp_portReg
```

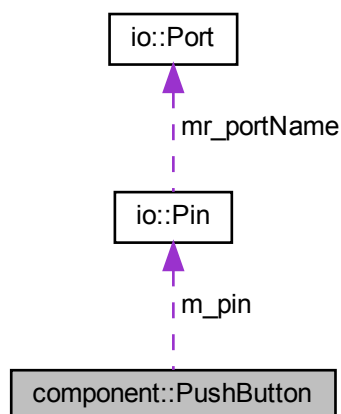
pointer to the port register

Definition at line 15 of file [Pin.h](#).

6.10 component::PushButton Class Reference

```
#include <PushButton.h>
```

Collaboration diagram for component::PushButton:



Public Member Functions

- [PushButton](#) (const [io::Pin](#) &ar_pin, const uint8_t &ar_useInternalPullUp=1, const uint8_t &ar_isActiveLow=1)
Constructor.
- [~PushButton](#) ()
Destructor.
- uint8_t [isPressed](#) ()
Is pushbutton pressed.
- uint8_t [getPressedCount](#) () const
Get pushbutton pressed count.
- void [resetPressedCount](#) ()
Reset pushbutton pressed count.

Private Attributes

- [io::Pin](#) [m_pin](#)
pin object
- const uint8_t & [mr_isActiveLow](#)
indicates led active state
- const uint8_t & [mr_useInternalPullUp](#)
indicates if internal pullup resistor used
- uint8_t [m_buttonPressed](#)
pushbutton pressed count

6.10.1 Detailed Description

Definition at line 95 of file [PushButton.h](#).

6.10.2 Constructor & Destructor Documentation

6.10.2.1 PushButton()

```
component::PushButton::PushButton (
    const io::Pin & ar_pin,
    const uint8_t & ar_useInternalPullUp = 1,
    const uint8_t & ar_isActiveLow = 1 )
```

Constructor.

Initializes pushbutton object

@param ar_pin pin object
@param ar_useInternalPullUp indicates if internal pull up resistor used

Definition at line 3 of file [PushButton.cpp](#).

```
00004 : m\_pin(ar_pin),
00005     mr\_isActiveLow(ar_isActiveLow),
00006     mr\_useInternalPullUp(ar_useInternalPullUp)
00007
00008
00009 {
00010     m\_pin.toInput(mr\_useInternalPullUp);
00011     m\_buttonPressed = 0;
00012 }
```

References [m_buttonPressed](#), [m_pin](#), [mr_useInternalPullUp](#), and [io::Pin::toInput\(\)](#).

6.10.2.2 ~PushButton()

```
component::PushButton::~~PushButton ( )
```

Destructor.

Definition at line 14 of file [PushButton.cpp](#).

```
00015 {  
00016  
00017 }
```

6.10.3 Member Function Documentation

6.10.3.1 getPressedCount()

```
uint8_t component::PushButton::getPressedCount ( ) const
```

Get pushbutton pressed count.

Definition at line 46 of file [PushButton.cpp](#).

```
00047 {  
00048  
00049     return m_buttonPressed;  
00050  
00051 }
```

6.10.3.2 isPressed()

```
uint8_t component::PushButton::isPressed ( )
```

Is pushbutton pressed.

Definition at line 20 of file [PushButton.cpp](#).

```
00021 {  
00022     if (mr_isActiveLow || mr_useInternalPullUp) {  
00023         if (m_pin.isLow()) {  
00024             _delay_us(PUSHBUTTON_DEBOUNCE_TIME_US);  
00025             if (m_pin.isLow()) {  
00026                 ++m_buttonPressed;  
00027                 return 1;  
00028             }  
00029         }  
00030     } else {  
00031  
00032         if (m_pin.isHigh()) {  
00033             _delay_us(PUSHBUTTON_DEBOUNCE_TIME_US);  
00034             if (m_pin.isHigh()) {  
00035                 ++m_buttonPressed;  
00036                 return 1;  
00037             }  
00038         }  
00039     }  
00040 }  
00041 m_buttonPressed = 0;  
00042 return 0;  
00043  
00044 }
```

References [PUSHBUTTON_DEBOUNCE_TIME_US](#).

6.10.3.3 resetPressedCount()

```
void component::PushButton::resetPressedCount ( )
```

Reset pushbutton pressed count.

Definition at line 53 of file [PushButton.cpp](#).

```
00054 {  
00055     m_buttonPressed = 0;  
00056  
00057 }
```

6.10.4 Member Data Documentation

6.10.4.1 m_buttonPressed

```
uint8_t component::PushButton::m_buttonPressed [private]
```

pushbutton pressed count

Definition at line 125 of file [PushButton.h](#).

Referenced by [PushButton\(\)](#).

6.10.4.2 m_pin

```
io::Pin component::PushButton::m_pin [private]
```

pin object

Definition at line 122 of file [PushButton.h](#).

Referenced by [PushButton\(\)](#).

6.10.4.3 mr_isActiveLow

```
const uint8_t& component::PushButton::mr_isActiveLow [private]
```

indicates led active state

Definition at line 123 of file [PushButton.h](#).

6.10.4.4 mr_useInternalPullUp

```
const uint8_t& component::PushButton::mr_useInternalPullUp [private]
```

indicates if internal pullup resistor used

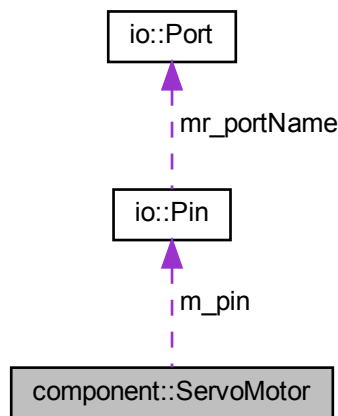
Definition at line 124 of file [PushButton.h](#).

Referenced by [PushButton\(\)](#).

6.11 component::ServoMotor Class Reference

```
#include <ServoMotor.h>
```

Collaboration diagram for component::ServoMotor:



Public Member Functions

- [ServoMotor](#) (const [io::Pin](#) &ar_pin, const uint16_t &ar_pulseCycle=0, const uint16_t &ar_pulseWidthMin=0, const uint16_t &ar_pulseWidthMid=0, const uint16_t &ar_pulseWidthMax=0)
- [~ServoMotor](#) ()
- void [on](#) ()
Turn servo motor On.
- void [off](#) ()
Turn servo motor Off.
- void [toggle](#) ()
Toggle servo motor state.
- uint16_t [computePulseCycleCount](#) (const uint16_t &ar_clockPrescaler)
- uint16_t [computePulseWidthMinCount](#) (const uint16_t &ar_clockPrescaler)
- uint16_t [computePulseWidthMidCount](#) (const uint16_t &ar_clockPrescaler)
- uint16_t [computePulseWidthMaxCount](#) (const uint16_t &ar_clockPrescaler)
- uint16_t [computeRotationAngleCount](#) (const uint8_t &ar_angle_deg, const uint16_t &ar_clockPrescaler)
- void [rotate](#) ([core::TimerCounter1](#) &ar_timerCounter1, const uint8_t &ar_angle_deg, const [core::channel](#) &ar_channel=[core::channel::A](#))
- void [connect](#) ([core::TimerCounter1](#) &ar_timerCounter1, const [core::channel](#) &ar_channel=[core::channel::A](#))
- void [disconnect](#) ([core::TimerCounter1](#) &ar_timerCounter1, const [core::channel](#) &ar_channel=[core::channel::A](#))

Private Attributes

- [io::Pin m_pin](#)
pin object
- [uint16_t m_pulseCycle](#)
pulse cycle [us]
- [uint16_t m_pulseWidthMin](#)
pulse width min [us]
- [uint16_t m_pulseWidthMid](#)
pulse width mid [us]
- [uint16_t m_pulseWidthMax](#)
pulse width max [us]

6.11.1 Detailed Description

Definition at line 138 of file [ServoMotor.h](#).

6.11.2 Constructor & Destructor Documentation

6.11.2.1 ServoMotor()

```
component::ServoMotor::ServoMotor (
    const io::Pin & ar_pin,
    const uint16_t & ar_pulseCycle = 0,
    const uint16_t & ar_pulseWidthMin = 0,
    const uint16_t & ar_pulseWidthMid = 0,
    const uint16_t & ar_pulseWidthMax = 0 )
```

Definition at line 5 of file [ServoMotor.cpp](#).

```
00010         : m_pin(ar_pin),
00011           m_pulseCycle(ar_pulseCycle),
00012           m_pulseWidthMin(ar_pulseWidthMin),
00013           m_pulseWidthMid(ar_pulseWidthMid),
00014           m_pulseWidthMax(ar_pulseWidthMax)
00015 {
00016     m_pin.toOutput();
00017 }
00018 }
```

References [m_pin](#), and [io::Pin::toOutput\(\)](#).

6.11.2.2 ~ServoMotor()

```
component::ServoMotor::~~ServoMotor ( )
```

Definition at line 20 of file [ServoMotor.cpp](#).

```
00021 {
00022 }
00023 }
```


6.11.3 Member Function Documentation

6.11.3.1 computePulseCycleCount()

```
uint16_t component::ServoMotor::computePulseCycleCount (
    const uint16_t & ar_clockPrescaler )
```

Definition at line 44 of file [ServoMotor.cpp](#).

```
00045 {
00046     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseCycle,ar_clockPrescaler);
00047 }
```

References [SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT](#).

6.11.3.2 computePulseWidthMaxCount()

```
uint16_t component::ServoMotor::computePulseWidthMaxCount (
    const uint16_t & ar_clockPrescaler )
```

Definition at line 54 of file [ServoMotor.cpp](#).

```
00055 {
00056     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMax,ar_clockPrescaler);
00057 }
```

References [SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT](#).

6.11.3.3 computePulseWidthMidCount()

```
uint16_t component::ServoMotor::computePulseWidthMidCount (
    const uint16_t & ar_clockPrescaler )
```

Definition at line 59 of file [ServoMotor.cpp](#).

```
00060 {
00061     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMid,ar_clockPrescaler);
00062 }
```

References [SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT](#).

6.11.3.4 computePulseWidthMinCount()

```
uint16_t component::ServoMotor::computePulseWidthMinCount (
    const uint16_t & ar_clockPrescaler )
```

Definition at line 49 of file [ServoMotor.cpp](#).

```
00050 {
00051     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMin,ar_clockPrescaler);
00052 }
```

References [SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT](#).

6.11.3.5 computeRotationAngleCount()

```
uint16_t component::ServoMotor::computeRotationAngleCount (
    const uint8_t & ar_angle_deg,
    const uint16_t & ar_clockPrescaler )
```

Definition at line 64 of file [ServoMotor.cpp](#).

```
00065 {
00066     return
00067     static_cast<uint16_t> (SERVOMOTOR_TIMER_ANGLE_COUNT (ar_angle_deg, static_cast<long> (computePulseWidthMinCount (ar_clockPr
```

References [SERVOMOTOR_TIMER_ANGLE_COUNT](#).

6.11.3.6 connect()

```
void component::ServoMotor::connect (
    core::TimerCounter1 & ar_timerCounter1,
    const core::channel & ar_channel = core::channel::A )
```

Definition at line 85 of file [ServoMotor.cpp](#).

```
00087 {
00088
00089
00090     ar_timerCounter1.setInputCaptureRegister (computePulseCycleCount (ar_timerCounter1.getClockPrescaler ()));
00091     ar_timerCounter1.selectOperationMode (core::operationMode::fast_PWM_ICR);
00092     ar_timerCounter1.selectCompareOutputMode (ar_channel, core::compareOutputMode::clear);
00093     ar_timerCounter1.setCounter (0);
00094
00095 }
```

References [core::clear](#), [core::fast_PWM_ICR](#), [core::TimerCounter1::getClockPrescaler\(\)](#), [core::TimerCounter1::selectCompareOutputMode\(\)](#), [core::TimerCounter1::selectOperationMode\(\)](#), [core::TimerCounter1::setCounter\(\)](#), and [core::TimerCounter1::setInputCaptureRegister\(\)](#).

6.11.3.7 disconnect()

```
void component::ServoMotor::disconnect (
    core::TimerCounter1 & ar_timerCounter1,
    const core::channel & ar_channel = core::channel::A )
```

Definition at line 97 of file [ServoMotor.cpp](#).

```
00099 {
00100     ar_timerCounter1.selectCompareOutputMode (ar_channel, core::compareOutputMode::normal);
00101     // stop timer
00102     ar_timerCounter1.stop ();
00103 }
```

References [core::normal](#), [core::TimerCounter1::selectCompareOutputMode\(\)](#), and [core::TimerCounter1::stop\(\)](#).

6.11.3.8 off()

```
void component::ServoMotor::off ( )
```

Turn servo motor Off.

Definition at line 33 of file [ServoMotor.cpp](#).

```
00034 {  
00035     m_pin.setLow();  
00036 }
```

6.11.3.9 on()

```
void component::ServoMotor::on ( )
```

Turn servo motor On.

Definition at line 28 of file [ServoMotor.cpp](#).

```
00029 {  
00030     m_pin.setHigh();  
00031 }
```

6.11.3.10 rotate()

```
void component::ServoMotor::rotate (  
    core::TimerCounter1 & ar_timerCounter1,  
    const uint8_t & ar_angle_deg,  
    const core::channel & ar_channel = core::channel::A )
```

Definition at line 71 of file [ServoMotor.cpp](#).

```
00074 {  
00075  
00076     ar_timerCounter1.setOutputCompareRegister(ar_channel,  
        computeRotationAngleCount(ar_angle_deg, ar_timerCounter1.getClockPrescaler()));  
00077  
00078     // start timer  
00079     ar_timerCounter1.start();  
00080  
00081  
00082 }
```

References [core::TimerCounter1::getClockPrescaler\(\)](#), [core::TimerCounter1::setOutputCompareRegister\(\)](#), and [core::TimerCounter1::start\(\)](#).

6.11.3.11 toggle()

```
void component::ServoMotor::toggle ( )
```

Toggle servo motor state.

Definition at line 38 of file [ServoMotor.cpp](#).

```
00039 {  
00040     m_pin.toggle();  
00041  
00042 }
```

6.11.4 Member Data Documentation

6.11.4.1 m_pin

```
io::Pin component::ServoMotor::m_pin [private]
```

pin object

Definition at line 188 of file [ServoMotor.h](#).

Referenced by [ServoMotor\(\)](#).

6.11.4.2 m_pulseCycle

```
uint16_t component::ServoMotor::m_pulseCycle [private]
```

pulse cycle [us]

Definition at line 190 of file [ServoMotor.h](#).

6.11.4.3 m_pulseWidthMax

```
uint16_t component::ServoMotor::m_pulseWidthMax [private]
```

pulse width max [us]

Definition at line 196 of file [ServoMotor.h](#).

6.11.4.4 m_pulseWidthMid

```
uint16_t component::ServoMotor::m_pulseWidthMid [private]
```

pulse width mid [us]

Definition at line 194 of file [ServoMotor.h](#).

6.11.4.5 m_pulseWidthMin

```
uint16_t component::ServoMotor::m_pulseWidthMin [private]
```

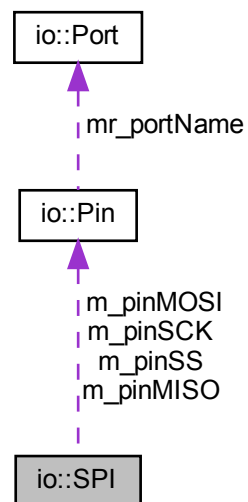
pulse width min [us]

Definition at line 192 of file [ServoMotor.h](#).

6.12 io::SPI Class Reference

```
#include <SPI.h>
```

Collaboration diagram for io::SPI:



Public Member Functions

- void [selectDataMode](#) (const [dataMode](#) &ar_dataMode)
- void [selectDataOrder](#) (const [dataOrder](#) &ar_dataOrder)
- void [selectOperationMode](#) (const [operationMode](#) &ar_operationMode)
- void [selectClockPrescaler](#) (const [clockPrescaler](#) &ar_clockPrescaler)
- void [selectSlave](#) (const uint8_t a_select)
- uint8_t [writeCollision](#) ()
Is there write collision.
- uint8_t [transferComplete](#) ()
Is serial transfer complete.
- void [masterSendByte](#) (const uint8_t &ar_byte)
- void [masterReceiveByte](#) (uint8_t &ar_byte)
- void [slaveReceiveByte](#) (uint8_t &ar_byte)

Static Public Member Functions

- static [SPI](#) & [getInstance](#) (const [io::Pin](#) &ar_pinSCK, const [io::Pin](#) &ar_pinMISO, const [io::Pin](#) &ar_pinMOSI, const [io::Pin](#) &ar_pinSS)
- static void [enableTransferCompleteInterrupt](#) (const uint8_t a_enable)
- static void [transferCompleteServiceRoutine](#) () `__asm__(STR(SPI_TRANSFER_COMPLETE_INTERRUPT))`
`__attribute__((__signal__`
Serial transfer complete ISR.

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [SPI](#) (const [io::Pin](#) &ar_pinSCK, const [io::Pin](#) &ar_pinMISO, const [io::Pin](#) &ar_pinMOSI, const [io::Pin](#) &ar_pinSS)
Constructor.
- [~SPI](#) ()
Destructor.
- [SPI](#) (const [SPI](#) &)
Overried Copy constructor.
- const [SPI](#) & [operator=](#) (const [SPI](#) &)
Override assign operator.

Private Attributes

- [io::Pin](#) m_pinSCK
pin object
- [io::Pin](#) m_pinMISO
pin object
- [io::Pin](#) m_pinMOSI
pin object
- [io::Pin](#) m_pinSS
pin object

Static Private Attributes

- static volatile uint8_t [m_data](#) = 0

6.12.1 Detailed Description

Definition at line 86 of file [SPI.h](#).

6.12.2 Constructor & Destructor Documentation

6.12.2.1 SPI() [1/2]

```
io::SPI::SPI (
    const io::Pin & ar_pinSCK,
    const io::Pin & ar_pinMISO,
    const io::Pin & ar_pinMOSI,
    const io::Pin & ar_pinSS ) [private]
```

Constructor.

Initializes the [USART0](#) object

@param ar_transMode defines transmission mode
 @param ar_comMode defines communication mode
 @param ar_frameSize defines data frame size
 @param ar_stopBit defines number of stop bits
 @param ar_parityMode defines parity mode

Definition at line 22 of file [SPI.cpp](#).

```
00026         : m_pinSCK(ar_pinSCK),
00027           m_pinMISO(ar_pinMISO),
00028           m_pinMOSI(ar_pinMOSI),
00029           m_pinSS(ar_pinSS)
00030 {
00031     core::MCU::enableSPI(1);
00032     sei();
00033     enableTransferCompleteInterrupt(1);
00034
00035 }
```

References [core::MCU::enableSPI\(\)](#), and [enableTransferCompleteInterrupt\(\)](#).

6.12.2.2 ~SPI()

```
io::SPI::~~SPI ( ) [private]
```

Destructor.

Definition at line 37 of file [SPI.cpp](#).

```
00038 {
00039
00040 }
```

6.12.2.3 SPI() [2/2]

```
io::SPI::SPI (
    const SPI & ) [private]
```

Overried Copy constructor.

6.12.3 Member Function Documentation

6.12.3.1 enableTransferCompleteInterrupt()

```
void io::SPI::enableTransferCompleteInterrupt (
    const uint8_t a_enable ) [static]
```

Definition at line 110 of file [SPI.cpp](#).

```
00111 {
00112     if (a_enable) {
00113         SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT;
00114     } else {
00115         SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT;
00116     }
00117 }
```

References [SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT](#), and [SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT](#).

Referenced by [SPI\(\)](#).

6.12.3.2 getInstance()

```
io::SPI & io::SPI::getInstance (
    const io::Pin & ar_pinSCK,
    const io::Pin & ar_pinMISO,
    const io::Pin & ar_pinMOSI,
    const io::Pin & ar_pinSS ) [static]
```

Definition at line 8 of file [SPI.cpp](#).

```
00012 {
00013     static SPI l_instance(ar_pinSCK,
00014                           ar_pinMISO,
00015                           ar_pinMOSI,
00016                           ar_pinSS);
00017
00018     return l_instance;
00019
00020 }
```

6.12.3.3 masterReceiveByte()

```
void io::SPI::masterReceiveByte (
    uint8_t & ar_byte )
```

Definition at line 147 of file [SPI.cpp](#).

```
00148 {
00149     masterSendByte(0);
00150     ar_byte = m_data;
00151
00152 }
```


6.12.3.4 masterSendByte()

```
void io::SPI::masterSendByte (
    const uint8_t & ar_byte )
```

Definition at line 135 of file [SPI.cpp](#).

```
00136 {
00137
00138     SPI_DATA_REGISTER = ar_byte;
00139     selectSlave(1);
00140     while(!transferComplete()){};
00141     selectSlave(0);
00142
00143
00144
00145 }
```

References [SPI_DATA_REGISTER](#).

6.12.3.5 operator=()

```
const SPI& io::SPI::operator= (
    const SPI & ) [private]
```

Override assign operator.

6.12.3.6 selectClockPrescaler()

```
void io::SPI::selectClockPrescaler (
    const clockPrescaler & ar_clockPrescaler )
```

Definition at line 53 of file [SPI.cpp](#).

```
00054 {
00055     SPI_SELECT_CLOCK_PRESCALER(static_cast<uint8_t>(ar_clockPrescaler));
00056
00057 }
```

References [SPI_SELECT_CLOCK_PRESCALER](#).

6.12.3.7 selectDataMode()

```
void io::SPI::selectDataMode (
    const dataMode & ar_dataMode )
```

Definition at line 99 of file [SPI.cpp](#).

```
00100 {
00101     SPI_SELECT_DATA_MODE(static_cast<uint8_t>(ar_dataMode));
00102 }
```

References [SPI_SELECT_DATA_MODE](#).

6.12.3.8 selectDataOrder()

```
void io::SPI::selectDataOrder (
    const dataOrder & ar_dataOrder )
```

Definition at line 104 of file [SPI.cpp](#).

```
00105 {
00106     SPI\_SELECT\_DATA\_ORDER(static_cast<uint8_t>(ar_dataOrder));
00107 }
00108 }
```

References [SPI_SELECT_DATA_ORDER](#).

6.12.3.9 selectOperationMode()

```
void io::SPI::selectOperationMode (
    const operationMode & ar_operationMode )
```

Definition at line 59 of file [SPI.cpp](#).

```
00060 {
00061     switch (ar_operationMode)
00062     {
00063         case operationMode::master:
00064         {
00065             m_pinMOSI.toOutput();
00066             m_pinSCK.toOutput();
00067             m_pinMISO.toInput(1);
00068             m_pinSS.toOutput();
00069             m_pinSS.setHigh();
00070             SPI\_SELECT\_MASTER\_MODE;
00071             SPI\_ENABLE;
00072             break;
00073         }
00074         case operationMode::slave:
00075         {
00076             m_pinMISO.toOutput();
00077             SPI\_SELECT\_SLAVE\_MODE;
00078             SPI\_ENABLE;
00079             break;
00080         }
00081         case operationMode::submaster:
00082         {
00083             m_pinMOSI.toOutput();
00084             m_pinSCK.toOutput();
00085             m_pinMISO.toInput(1);
00086             m_pinSS.toInput(1);
00087             SPI\_SELECT\_MASTER\_MODE;
00088             SPI\_ENABLE;
00089             break;
00090         }
00091         case operationMode::disable:
00092         {
00093             SPI\_DISABLE;
00094             break;
00095         }
00096     }
00097 }
```

References [io::disable](#), [io::master](#), [io::slave](#), [SPI_DISABLE](#), [SPI_ENABLE](#), [SPI_SELECT_MASTER_MODE](#), [SPI_SELECT_SLAVE_MODE](#), and [io::submaster](#).

6.12.3.10 selectSlave()

```
void io::SPI::selectSlave (
    const uint8_t a_select )
```

Definition at line 119 of file [SPI.cpp](#).

```
00120 {
00121     if (a_select) {
00122         m_pinSS.setLow();
00123     } else {
00124         m_pinSS.setHigh();
00125     }
00126 }
00127
00128 }
```

6.12.3.11 slaveReceiveByte()

```
void io::SPI::slaveReceiveByte (
    uint8_t & ar_byte )
```

Definition at line 154 of file [SPI.cpp](#).

```
00155 {
00156     ar_byte = m_data;
00157 }
00158 }
```

6.12.3.12 transferComplete()

```
uint8_t io::SPI::transferComplete ( )
```

Is serial transfer complete.

Definition at line 48 of file [SPI.cpp](#).

```
00049 {
00050     return (SPI_STATUS_REGISTER & (1 << SPI_TRANSFER_COMPLETE));
00051 }
```

References [SPI_STATUS_REGISTER](#), and [SPI_TRANSFER_COMPLETE](#).

6.12.3.13 transferCompleteServiceRoutine()

```
void io::SPI::transferCompleteServiceRoutine ( ) [static]
```

Serial transfer complete ISR.

Definition at line 129 of file [SPI.cpp](#).

```
00130 {
00131
00132     m_data = SPI_DATA_REGISTER;
00133 }
```

References [SPI_DATA_REGISTER](#).

6.12.3.14 writeCollision()

```
uint8_t io::SPI::writeCollision ( )
```

Is there write collision.

Definition at line 42 of file [SPI.cpp](#).

```
00043 {  
00044     return (SPI_STATUS_REGISTER & (1 « SPI_WRITE_COLLISION));  
00045 }
```

References [SPI_STATUS_REGISTER](#), and [SPI_WRITE_COLLISION](#).

6.12.4 Member Data Documentation

6.12.4.1 __externally_visible__

```
void io::SPI::__externally_visible__
```

Definition at line 124 of file [SPI.h](#).

6.12.4.2 __used__

```
void io::SPI::__used__
```

Definition at line 124 of file [SPI.h](#).

6.12.4.3 m_data

```
volatile uint8_t io::SPI::m_data = 0 [static], [private]
```

Definition at line 154 of file [SPI.h](#).

6.12.4.4 m_pinMISO

```
io::Pin io::SPI::m_pinMISO [private]
```

pin object

Definition at line 157 of file [SPI.h](#).

6.12.4.5 m_pinMOSI

```
io::Pin io::SPI::m_pinMOSI [private]
```

pin object

Definition at line 158 of file [SPI.h](#).

6.12.4.6 m_pinSCK

```
io::Pin io::SPI::m_pinSCK [private]
```

pin object

Definition at line 156 of file [SPI.h](#).

6.12.4.7 m_pinSS

```
io::Pin io::SPI::m_pinSS [private]
```

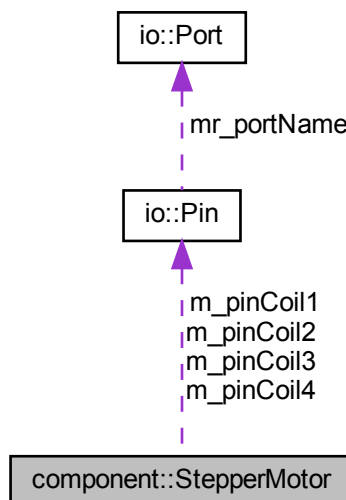
pin object

Definition at line 159 of file [SPI.h](#).

6.13 component::StepperMotor Class Reference

```
#include <StepperMotor.h>
```

Collaboration diagram for component::StepperMotor:



Public Member Functions

- [StepperMotor](#) (const [mode](#) &ar_mode, const [io::Pin](#) &ar_pinCoil1, const [io::Pin](#) &ar_pinCoil2, const [io::Pin](#) &ar_pinCoil3, const [io::Pin](#) &ar_pinCoil4)
- [~StepperMotor](#) ()
- void [step](#) (const [uint16_t](#) a_step, const [uint16_t](#) a_speed)
Turn servo motor On.
- void [step](#) (const [uint16_t](#) a_step, const [uint16_t](#) a_speed, const float a_stepAngle)
- void [step](#) (const [uint16_t](#) a_step, const [uint16_t](#) a_speed, const [uint16_t](#) a_accel, const [uint16_t](#) a_decel)
- void [stepPulse](#) (const [uint8_t](#) a_stepPulse)
- void [stepDelay](#) ([uint8_t](#) a_stepDelay)
- [uint8_t](#) [goalReached](#) ()
- void [setCurrentPos](#) ([uint16_t](#) a_currentPos)
- [uint16_t](#) [currentPos](#) ()
- [uint8_t](#) [computeStepDelay](#) ([uint16_t](#) a_step, const [uint16_t](#) a_speed, const [uint16_t](#) a_accel, const [uint16_t](#) a_decel)

Public Attributes

- [uint16_t](#) [m_accelTime](#)
pulse delay in ms
- [uint16_t](#) [m_decelTime](#)
pulse delay in ms
- [uint16_t](#) [m_constSpeedTime](#)
pulse delay in ms

Private Attributes

- [io::Pin](#) [m_pinCoil1](#)
pin object
- [io::Pin](#) [m_pinCoil2](#)
pin object
- [io::Pin](#) [m_pinCoil3](#)
pin object
- [io::Pin](#) [m_pinCoil4](#)
pin object
- [mode](#) [stepMode](#)
steps per revolution
- [uint8_t](#) [m_goalReached](#)
- [uint16_t](#) [m_currentPos](#)
pulse delay in ms

6.13.1 Detailed Description

Definition at line 75 of file [StepperMotor.h](#).

6.13.2 Constructor & Destructor Documentation

6.13.2.1 StepperMotor()

```
component::StepperMotor::StepperMotor (
    const mode & ar_mode,
    const io::Pin & ar_pinCoil1,
    const io::Pin & ar_pinCoil2,
    const io::Pin & ar_pinCoil3,
    const io::Pin & ar_pinCoil4 )
```

Definition at line 8 of file [StepperMotor.cpp](#).

```
00013 : m_pinCoil1(ar_pinCoil1),
00014     m_pinCoil2(ar_pinCoil2),
00015     m_pinCoil3(ar_pinCoil3),
00016     m_pinCoil4(ar_pinCoil4),
00017     stepMode(ar_mode)
00018 {
00019
00020     m_pinCoil1.toOutput();
00021     m_pinCoil2.toOutput();
00022     m_pinCoil3.toOutput();
00023     m_pinCoil4.toOutput();
00024     m_goalReached = 0;
00025     m_currentPos = 0;
00026
00027
00028 }
```

References [m_currentPos](#), [m_goalReached](#), [m_pinCoil1](#), [m_pinCoil2](#), [m_pinCoil3](#), [m_pinCoil4](#), and [io::Pin::toOutput\(\)](#).

6.13.2.2 ~StepperMotor()

```
component::StepperMotor::~~StepperMotor ( )
```

Definition at line 30 of file [StepperMotor.cpp](#).

```
00031 {
00032
00033 }
```

6.13.3 Member Function Documentation

6.13.3.1 computeStepDelay()

```
uint8_t component::StepperMotor::computeStepDelay (
    uint16_t a_step,
    const uint16_t a_speed,
    const uint16_t a_accel,
    const uint16_t a_decel )
```

Definition at line 127 of file [StepperMotor.cpp](#).

```
00131 {
00132
00133
00134     uint32_t l_accelTime= (1000UL*a_speed/a_accel);
00135     uint16_t l_decelTime = (1000UL*a_speed/a_decel);
00136     int16_t l_constSpeedTime=((1000UL*a_step/a_speed)-(l_accelTime/2)-(l_decelTime/2));
00137     static uint32_t l_time=0;
00138     static uint32_t l_speed=0;
00139     static uint64_t l_speed_time_product=0;
```

```

00140     static uint64_t l_current_position=0;
00141
00142
00143
00144
00145
00146
00147
00148     if (l_constSpeedTime<0)
00149     {
00150         l_constSpeedTime=0;
00151         l_accelTime = static_cast<uint32_t>(1000UL*sqrtf(a_step/a_accel));
00152         a_speed=l_accelTime*a_accel/1000UL;
00153         l_decelTime = 1000UL*a_speed/a_decel;
00154
00155     }
00156
00157
00158
00159
00160     if (l_time<=l_accelTime)
00161     {
00162         l_speed=a_accel*l_time;
00163
00164     }
00165     else if ((l_time>l_accelTime) && (l_time<=(l_accelTime+l_constSpeedTime)))
00166     {
00167         l_speed=1000UL*a_speed;
00168
00169     }
00170     else if
00171     ((l_time>(l_accelTime+l_constSpeedTime)) && (l_time<=l_accelTime+l_constSpeedTime+l_decelTime))
00172     {
00173         l_speed= (1000UL*a_speed)-a_decel*(l_time-l_accelTime-l_constSpeedTime);
00174
00175     }
00176
00177
00178     l_time=l_time+1;
00179
00180
00181     l_speed_time_product = l_speed_time_product+l_speed;
00182
00183     if (l_speed_time_product - l_current_position >= 1000000UL)
00184     {
00185         l_current_position=l_current_position+1000000UL;
00186         return 1;
00187     }
00188     else
00189     {
00190         stepDelay(1);
00191         return 0;
00192     }
00193
00194
00195
00196
00197
00198 }

```

6.13.3.2 currentPos()

uint16_t component::StepperMotor::currentPos ()

Definition at line 40 of file [StepperMotor.cpp](#).

```

00041 {
00042     return m_currentPos;
00043 }

```


6.13.3.3 goalReached()

```
uint8_t component::StepperMotor::goalReached ( )
```

Definition at line 403 of file [StepperMotor.cpp](#).

```
00404 {
00405     return m_goalReached;
00406 }
00407 }
```

6.13.3.4 setCurrentPos()

```
void component::StepperMotor::setCurrentPos (
    uint16_t a_currentPos )
```

Definition at line 35 of file [StepperMotor.cpp](#).

```
00036 {
00037     m_currentPos = a_currentPos;
00038 }
```

6.13.3.5 step() [1/3]

```
void component::StepperMotor::step (
    const int16_t a_step,
    const uint16_t a_speed )
```

Turn servo motor On.

Definition at line 201 of file [StepperMotor.cpp](#).

```
00202 {
00203     static int16_t l_stepNumber = 0;
00204     static uint8_t l_stepDelay_ms = static_cast<uint8_t>(1000UL/a_speed);
00205
00206     if (a_step<=0)
00207     {
00208         if (l_stepNumber== -a_step)
00209         {
00210             m_goalReached = 1;
00211         } else {
00212             l_stepNumber++;
00213             m_currentPos++;
00214         }
00215     }
00216
00217     } else {
00218
00219         if (l_stepNumber == -a_step)
00220         {
00221             m_goalReached = 1;
00222         } else {
00223             l_stepNumber--;
00224             m_currentPos--;
00225         }
00226     }
00227
00228     }
00229
00230
00231
00232     if (m_goalReached == 0)
00233     {
00234
00235         switch (stepMode)
00236         {
00237             case mode::fullStep:
```

```

00238         {
00239             // equivalent to l_stepNumber % 4
00240             // 1 3 5 7 <->
00241             stepPulse(2*(l_stepNumber & 3)+1);
00242             break;
00243         }
00244
00245         case mode::halfStep:
00246         {
00247             // equivalent to l_stepNumber % 8
00248             // 0 1 2 3 4 5 6 7 <->
00249             stepPulse(l_stepNumber & 7);
00250             break;
00251         }
00252     }
00253
00254     stepDelay(l_stepDelay_ms);
00255 }
00256 }
00257 }

```

References [component::fullStep](#), and [component::halfStep](#).

6.13.3.6 step() [2/3]

```

void component::StepperMotor::step (
    const int16_t a_step,
    const uint16_t a_speed,
    const float a_stepAngle )

```

Definition at line 259 of file [StepperMotor.cpp](#).

```

00260 {
00261     static int16_t l_stepNumber = 0;
00262     static uint8_t l_stepDelay_ms = static_cast<uint8_t>(1000UL*a_stepAngle/a_speed);
00263
00264     if (a_step<=0)
00265     {
00266         if (l_stepNumber== -a_step)
00267         {
00268             m_goalReached = 1;
00269         } else {
00270             l_stepNumber++;
00271             m_currentPos++;
00272         }
00273     }
00274
00275     } else {
00276         if (l_stepNumber == -a_step)
00277         {
00278             m_goalReached = 1;
00279         } else {
00280             l_stepNumber--;
00281             m_currentPos--;
00282         }
00283     }
00284
00285     if (m_goalReached == 0)
00286     {
00287         switch (stepMode)
00288         {
00289             case mode::fullStep:
00290             {
00291                 // equivalent to l_stepNumber % 4
00292                 // 1 3 5 7 <->
00293                 stepPulse(2*(l_stepNumber & 3)+1);
00294                 break;
00295             }
00296
00297             case mode::halfStep:
00298             {
00299
00300
00301
00302
00303
00304

```

```

00305             // equivalent to l_stepNumber % 8
00306             // 0 1 2 3 4 5 6 7 <->
00307             stepPulse(l_stepNumber & 7);
00308             break;
00309         }
00310     }
00311
00312     stepDelay(l_stepDelay_ms);
00313
00314 }
00315
00316
00317 }

```

References [component::fullStep](#), and [component::halfStep](#).

6.13.3.7 step() [3/3]

```

void component::StepperMotor::step (
    const int16_t a_step,
    const uint16_t a_speed,
    const uint16_t a_accel,
    const uint16_t a_decel )

```

Definition at line 47 of file [StepperMotor.cpp](#).

```

00051 {
00052     static int16_t l_stepNumber = 0;
00053     uint8_t l_stepDelay_ms = 0;
00054     uint16_t l_step=0;
00055
00056     if (a_step<=0)
00057     {
00058         l_step = -a_step;
00059     } else
00060     {
00061         l_step = a_step;
00062     }
00063
00064     l_stepDelay_ms = computeStepDelay(l_step,
00065                                     a_speed,
00066                                     a_accel,
00067                                     a_decel);
00068
00069     if (l_stepDelay_ms>0)
00070     {
00071
00072         if (a_step<=0)
00073         {
00074             if (l_stepNumber== -a_step)
00075             {
00076                 m_goalReached = 1;
00077             } else {
00078                 l_stepNumber++;
00079                 m_currentPos++;
00080             }
00081         }
00082
00083     } else {
00084
00085         if (l_stepNumber == -a_step)
00086         {
00087             m_goalReached = 1;
00088         } else {
00089             l_stepNumber--;
00090             m_currentPos--;
00091         }
00092     }
00093
00094 }
00095
00096
00097
00098     if (m_goalReached == 0)
00099     {
00100
00101         switch (stepMode)

```

```

00102     {
00103         case mode::fullStep:
00104         {
00105             // equivalent to l_stepNumber % 4
00106             // 1 3 5 7 <->
00107             stepPulse(2*(l_stepNumber & 3)+1);
00108             break;
00109         }
00110
00111         case mode::halfStep:
00112         {
00113             // equivalent to l_stepNumber % 8
00114             // 0 1 2 3 4 5 6 7 <->
00115             stepPulse(l_stepNumber & 7);
00116             break;
00117         }
00118     }
00119     stepDelay(l_stepDelay_ms);
00120 }
00121 }
00122 }
00123 }
00124 }
00125 }

```

References [component::fullStep](#), and [component::halfStep](#).

6.13.3.8 stepDelay()

```

void component::StepperMotor::stepDelay (
    uint8_t a_stepDelay )

```

Definition at line 395 of file [StepperMotor.cpp](#).

```

00396 {
00397     while(a_stepDelay-->0)
00398     {
00399         _delay_ms(1);
00400     }
00401 }

```

6.13.3.9 stepPulse()

```

void component::StepperMotor::stepPulse (
    const uint8_t a_stepPulse )

```

Definition at line 320 of file [StepperMotor.cpp](#).

```

00321 {
00322
00323     switch (a_stepPulse) {
00324     case 0: // 1000
00325     {
00326         m_pinCoil1.setHigh();
00327         m_pinCoil2.setLow();
00328         m_pinCoil3.setLow();
00329         m_pinCoil4.setLow();
00330         break;
00331     }
00332     case 1: // 1100
00333     {
00334         m_pinCoil1.setHigh();
00335         m_pinCoil2.setHigh();
00336         m_pinCoil3.setLow();
00337         m_pinCoil4.setLow();
00338         break;
00339     }
00340     case 2: // 0100
00341     {
00342         m_pinCoil1.setLow();

```

```

00343         m_pinCoil2.setHigh();
00344         m_pinCoil3.setLow();
00345         m_pinCoil4.setLow();
00346         break;
00347     }
00348     case 3:        //0110
00349     {
00350         m_pinCoil1.setLow();
00351         m_pinCoil2.setHigh();
00352         m_pinCoil3.setHigh();
00353         m_pinCoil4.setLow();
00354         break;
00355     }
00356     case 4:        //0010
00357     {
00358         m_pinCoil1.setLow();
00359         m_pinCoil2.setLow();
00360         m_pinCoil3.setHigh();
00361         m_pinCoil4.setLow();
00362         break;
00363     }
00364     case 5:        //0011
00365     {
00366         m_pinCoil1.setLow();
00367         m_pinCoil2.setLow();
00368         m_pinCoil3.setHigh();
00369         m_pinCoil4.setHigh();
00370         break;
00371     }
00372     case 6:        //0001
00373     {
00374         m_pinCoil1.setLow();
00375         m_pinCoil2.setLow();
00376         m_pinCoil3.setLow();
00377         m_pinCoil4.setHigh();
00378         break;
00379     }
00380     case 7:        //1001
00381     {
00382         m_pinCoil1.setHigh();
00383         m_pinCoil2.setLow();
00384         m_pinCoil3.setLow();
00385         m_pinCoil4.setHigh();
00386         break;
00387     }
00388 }
00389
00390
00391 }

```

6.13.4 Member Data Documentation

6.13.4.1 m_accelTime

uint16_t component::StepperMotor::m_accelTime

pulse delay in ms

Definition at line 118 of file [StepperMotor.h](#).

6.13.4.2 m_constSpeedTime

uint16_t component::StepperMotor::m_constSpeedTime

pulse delay in ms

Definition at line 120 of file [StepperMotor.h](#).

6.13.4.3 m_currentPos

`uint16_t component::StepperMotor::m_currentPos [private]`

pulse delay in ms

Definition at line 139 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.4 m_decelTime

`uint16_t component::StepperMotor::m_decelTime`

pulse delay in ms

Definition at line 119 of file [StepperMotor.h](#).

6.13.4.5 m_goalReached

`uint8_t component::StepperMotor::m_goalReached [private]`

Definition at line 138 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.6 m_pinCoil1

`io::Pin component::StepperMotor::m_pinCoil1 [private]`

pin object

Definition at line 132 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.7 m_pinCoil2

`io::Pin component::StepperMotor::m_pinCoil2 [private]`

pin object

Definition at line 133 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.8 m_pinCoil3

```
io::Pin component::StepperMotor::m_pinCoil3 [private]
```

pin object

Definition at line 134 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.9 m_pinCoil4

```
io::Pin component::StepperMotor::m_pinCoil4 [private]
```

pin object

Definition at line 135 of file [StepperMotor.h](#).

Referenced by [StepperMotor\(\)](#).

6.13.4.10 stepMode

```
mode component::StepperMotor::stepMode [private]
```

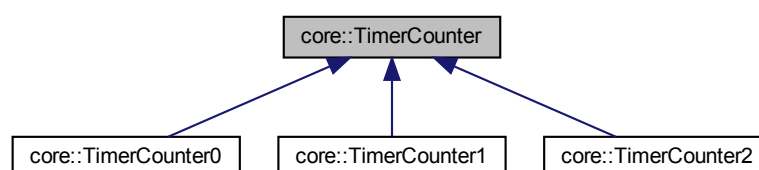
steps per revolution

Definition at line 137 of file [StepperMotor.h](#).

6.14 core::TimerCounter Class Reference

```
#include <TimerCounter.h>
```

Inheritance diagram for core::TimerCounter:



Public Member Functions

- virtual void [selectOperationMode](#) (const [operationMode](#) &ar_operationMode)=0
- virtual void [start](#) ()=0
- virtual void [stop](#) ()=0
- virtual void [selectClockSource](#) (const [clockSource](#) &ar_clockSource)=0
- virtual void [selectCompareOutputMode](#) (const [channel](#) &ar_channel, const [compareOutputMode](#) &ar_↔compareOutputMode)=0
- virtual void [setCounter](#) (const uint16_t &ar_dataBuffer)=0
- virtual uint16_t [getCounter](#) () const =0
- virtual void [setOutputCompareRegister](#) (const [channel](#) &ar_channel, const uint16_t &ar_dataBuffer)=0
- virtual uint16_t [getOutputCompareRegister](#) (const [channel](#) &ar_channel) const =0
- virtual void [enableOutputCompareMatchInterrupt](#) (const [channel](#) &ar_channel, const uint8_t a_enable)=0
- virtual void [enableOverflowInterrupt](#) (const uint8_t a_enable)=0
- virtual uint16_t [getClockPrescaler](#) ()=0

6.14.1 Detailed Description

Definition at line 517 of file [TimerCounter.h](#).

6.14.2 Member Function Documentation

6.14.2.1 enableOutputCompareMatchInterrupt()

```
virtual void core::TimerCounter::enableOutputCompareMatchInterrupt (
    const channel & ar_channel,
    const uint8_t a_enable ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.2 enableOverflowInterrupt()

```
virtual void core::TimerCounter::enableOverflowInterrupt (
    const uint8_t a_enable ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.3 getClockPrescaler()

```
virtual uint16_t core::TimerCounter::getClockPrescaler ( ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.4 getCounter()

```
virtual uint16_t core::TimerCounter::getCounter ( ) const [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.5 getOutputCompareRegister()

```
virtual uint16_t core::TimerCounter::getOutputCompareRegister (
    const channel & ar_channel ) const [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.6 selectClockSource()

```
virtual void core::TimerCounter::selectClockSource (
    const clockSource & ar_clockSource ) [pure virtual]
```

Implemented in [core::TimerCounter0](#), [core::TimerCounter1](#), and [core::TimerCounter2](#).

6.14.2.7 selectCompareOutputMode()

```
virtual void core::TimerCounter::selectCompareOutputMode (
    const channel & ar_channel,
    const compareOutputMode & ar_compareOutputMode ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.8 selectOperationMode()

```
virtual void core::TimerCounter::selectOperationMode (
    const operationMode & ar_operationMode ) [pure virtual]
```

Implemented in [core::TimerCounter0](#), [core::TimerCounter1](#), and [core::TimerCounter2](#).

6.14.2.9 setCounter()

```
virtual void core::TimerCounter::setCounter (
    const uint16_t & ar_dataBuffer ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.10 setOutputCompareRegister()

```
virtual void core::TimerCounter::setOutputCompareRegister (
    const channel & ar_channel,
    const uint16_t & ar_dataBuffer ) [pure virtual]
```

Implemented in [core::TimerCounter1](#), [core::TimerCounter0](#), and [core::TimerCounter2](#).

6.14.2.11 start()

```
virtual void core::TimerCounter::start ( ) [pure virtual]
```

Implemented in [core::TimerCounter0](#), [core::TimerCounter1](#), and [core::TimerCounter2](#).

6.14.2.12 stop()

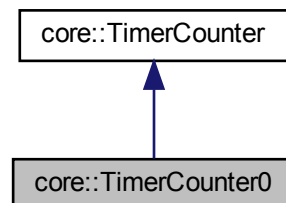
```
virtual void core::TimerCounter::stop ( ) [pure virtual]
```

Implemented in [core::TimerCounter0](#), [core::TimerCounter1](#), and [core::TimerCounter2](#).

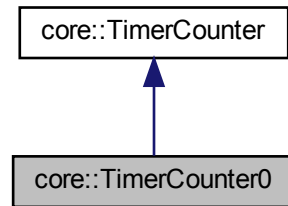
6.15 core::TimerCounter0 Class Reference

```
#include <TimerCounter0.h>
```

Inheritance diagram for core::TimerCounter0:



Collaboration diagram for core::TimerCounter0:



Public Member Functions

- void [selectOperationMode](#) (const [operationMode](#) &ar_operationMode) override
- void [start](#) () override
- void [stop](#) () override
- void [selectClockSource](#) (const [clockSource](#) &ar_clockSource) override
- void [selectCompareOutputMode](#) (const [channel](#) &ar_channel, const [compareOutputMode](#) &ar_compareOutputMode) override
- void [setCounter](#) (const uint16_t &ar_dataBuffer) override
- uint16_t [getCounter](#) () const override
- void [setOutputCompareRegister](#) (const [channel](#) &ar_channel, const uint16_t &ar_dataBuffer) override
- uint16_t [getOutputCompareRegister](#) (const [channel](#) &ar_channel) const override
- void [enableOutputCompareMatchInterrupt](#) (const [channel](#) &ar_channel, const uint8_t a_enable) override
- void [enableOverflowInterrupt](#) (const uint8_t a_enable) override
- uint16_t [getClockPrescaler](#) () override

Static Public Member Functions

- static [TimerCounter0](#) & [getInstance](#) (const [channel](#) &ar_channel=[channel::A](#), const [operationMode](#) &ar_operationMode=[operationMode::normal](#), const [clockSource](#) &ar_clockSource=[clockSource::noClock](#), const [compareOutputMode](#) &ar_compareOutputMode=[compareOutputMode::normal](#))
- static void [outputCompareMatchAServiceRoutine](#) () __asm__(STR(TIMERO0_COM_CHANNEL_A_INTERRUPT)) __attribute__((__signal__))
- static void [outputCompareMatchBServiceRoutine](#) () __asm__(STR(TIMERO0_COM_CHANNEL_B_INTERRUPT)) __attribute__((__signal__))
- static void [overflowServiceRoutine](#) () __asm__(STR(TIMERO0_OVERFLOW_INTERRUPT)) __attribute__((__signal__))

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [TimerCounter0](#) (const [channel](#) &ar_channel, const [operationMode](#) &ar_operationMode, const [clockSource](#) &ar_clockSource, const [compareOutputMode](#) &ar_compareOutputMode)
- [~TimerCounter0](#) ()
- [TimerCounter0](#) (const [TimerCounter0](#) &)
Overried Copy constructor.
- const [TimerCounter0](#) & [operator=](#) (const [TimerCounter0](#) &)
Override assign operator.

Private Attributes

- uint16_t [m_clockPrescaler](#)
- uint8_t [m_clockSource](#)

6.15.1 Detailed Description

Definition at line 279 of file [TimerCounter0.h](#).

6.15.2 Constructor & Destructor Documentation

6.15.2.1 TimerCounter0() [1/2]

```
core::TimerCounter0::TimerCounter0 (
    const channel & ar_channel,
    const operationMode & ar_operationMode,
    const clockSource & ar_clockSource,
    const compareOutputMode & ar_compareOutputMode ) [private]
```

Definition at line 20 of file [TimerCounter0.cpp](#).

```
00024 {
00025     core::MCU::enableTimerCounter0(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel, ar_compareOutputMode);
00030
00031
00032
00033 }
```

References [core::MCU::enableTimerCounter0\(\)](#).

6.15.2.2 ~TimerCounter0()

```
core::TimerCounter0::~~TimerCounter0 ( ) [private]
```

Definition at line 34 of file [TimerCounter0.cpp](#).

```
00035 {
00036
00037 }
```

6.15.2.3 TimerCounter0() [2/2]

```
core::TimerCounter0::TimerCounter0 (
    const TimerCounter0 & ) [private]
```

Overried Copy constructor.

6.15.3 Member Function Documentation

6.15.3.1 enableOutputCompareMatchInterrupt()

```
void core::TimerCounter0::enableOutputCompareMatchInterrupt (
    const channel & ar_channel,
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 216 of file [TimerCounter0.cpp](#).

```
00217 {
00218     switch (ar_channel)
00219     {
00220         case core::channel::A:
00221         {
00222             if (a_enable) {
00223                 TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT;
00224             } else {
00225                 TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT;
00226             }
00227             break;
00228         }
00229         case core::channel::B:
00230         {
00231             if (a_enable) {
00232                 TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT;
00233             } else {
00234                 TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT;
00235             }
00236             break;
00237         }
00238     }
00239 }
```

References [core::A](#), [core::B](#), [TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT](#), [TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT](#), [TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT](#), and [TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT](#).

6.15.3.2 enableOverflowInterrupt()

```
void core::TimerCounter0::enableOverflowInterrupt (
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 251 of file [TimerCounter0.cpp](#).

```
00252 {
00253
00254     if (a_enable) {
00255
00256         TIMER0_ENABLE_OVERFLOW_INTERRUPT;
00257
00258     } else {
00259
00260         TIMER0_DISABLE_OVERFLOW_INTERRUPT;
00261     }
00262
00263 }
```

References [TIMER0_DISABLE_OVERFLOW_INTERRUPT](#), and [TIMER0_ENABLE_OVERFLOW_INTERRUPT](#).

6.15.3.3 getClockPrescaler()

```
uint16_t core::TimerCounter0::getClockPrescaler ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 141 of file [TimerCounter0.cpp](#).

```
00142 {
00143     return m_clockPrescaler;
00144 }
```

6.15.3.4 getCounter()

```
uint16_t core::TimerCounter0::getCounter ( ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 176 of file [TimerCounter0.cpp](#).

```
00177 {
00178     return TCNT0;
00179 }
```

6.15.3.5 getInstance()

```
core::TimerCounter0 & core::TimerCounter0::getInstance (
    const channel & ar_channel = channel::A,
    const operationMode & ar_operationMode = operationMode::normal,
    const clockSource & ar_clockSource = clockSource::noClock,
    const compareOutputMode & ar_compareOutputMode = compareOutputMode::normal )
[static]
```

Definition at line 5 of file [TimerCounter0.cpp](#).

```
00009 {
00010     static TimerCounter0 l_instance(ar_channel,
00011                                     ar_operationMode,
00012                                     ar_clockSource,
00013                                     ar_compareOutputMode);
00014
00015     return l_instance;
00016
00017
00018 }
```

6.15.3.6 getOutputCompareRegister()

```
uint16_t core::TimerCounter0::getOutputCompareRegister (
    const channel & ar_channel ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 201 of file [TimerCounter0.cpp](#).

```
00202 {
00203     switch (ar_channel)
00204     {
00205         case core::channel::A:
00206         {
00207             return OCR0A;
00208         }
00209         case core::channel::B:
00210         {
00211             return OCR0B;
00212         }
00213     }
00214 }
```

References [core::A](#), and [core::B](#).

6.15.3.7 operator=()

```
const TimerCounter0& core::TimerCounter0::operator= (
    const TimerCounter0 & ) [private]
```

Override assign operator.

6.15.3.8 outputCompareMatchAServiceRoutine()

```
static void core::TimerCounter0::outputCompareMatchAServiceRoutine ( ) [static]
```

6.15.3.9 outputCompareMatchBServiceRoutine()

```
static void core::TimerCounter0::outputCompareMatchBServiceRoutine ( ) [static]
```

6.15.3.10 overflowServiceRoutine()

```
static void core::TimerCounter0::overflowServiceRoutine ( ) [static]
```

6.15.3.11 selectClockSource()

```
void core::TimerCounter0::selectClockSource (
    const clockSource & ar_clockSource ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 39 of file [TimerCounter0.cpp](#).

```
00040 {
00041     switch (ar_clockSource)
00042     {
00043         case core::clockSource::noClock:
00044         {
00045             m_clockPrescaler=0;
00046             m_clockSource=0;
00047             break;
00048         }
00049         case core::clockSource::PS_1:
00050         {
00051             m_clockPrescaler=1;
00052             m_clockSource=1;
00053             break;
00054         }
00055         case core::clockSource::PS_8:
00056         {
00057             m_clockPrescaler=8;
00058             m_clockSource=2;
00059             break;
00060         }
00061         case core::clockSource::PS_64:
00062         {
00063             m_clockPrescaler=64;
00064             m_clockSource=3;
00065             break;
00066         }
00067         case core::clockSource::PS_256:
00068         {
00069             m_clockPrescaler=256;
00070             m_clockSource=4;
00071             break;
00072         }
00073         case core::clockSource::PS_1024:
00074         {
00075             m_clockPrescaler=1024;
00076             m_clockSource=5;
00077             break;
00078         }
00079         case core::clockSource::extern_Clock_T0_Falling_Edge:
00080         {
00081             m_clockPrescaler=0;
00082             m_clockSource=6;
00083             break;
00084         }
00085         case core::clockSource::extern_Clock_T0_Rising_Edge:
00086         {
00087             m_clockPrescaler=0;
00088             m_clockSource=7;
00089             break;
00090         }
00091     }
```



```
00092
00093
00094 }
```

References [core::extern_Clock_T0_Falling_Edge](#), [core::extern_Clock_T0_Rising_Edge](#), [core::noClock](#), [core::PS_1](#), [core::PS_1024](#), [core::PS_256](#), [core::PS_64](#), and [core::PS_8](#).

6.15.3.12 selectCompareOutputMode()

```
void core::TimerCounter0::selectCompareOutputMode (
    const channel & ar_channel,
    const compareOutputMode & ar_compareOutputMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 152 of file [TimerCounter0.cpp](#).

```
00153 {
00154     switch (ar_channel)
00155     {
00156         case core::channel::A:
00157         {
00158             TIMER0_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00159             break;
00160         }
00161         case core::channel::B:
00162         {
00163             TIMER0_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00164             break;
00165         }
00166     }
00167 }
```

References [core::A](#), [core::B](#), [TIMER0_SELECT_COM_CHANNEL_A](#), and [TIMER0_SELECT_COM_CHANNEL_B](#).

6.15.3.13 selectOperationMode()

```
void core::TimerCounter0::selectOperationMode (
    const operationMode & ar_operationMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 96 of file [TimerCounter0.cpp](#).

```
00097 {
00098     switch (ar_operationMode)
00099     {
00100         case core::operationMode::normal:
00101         {
00102             TIMER0_SELECT_OPERATION_MODE(0);
00103             break;
00104         }
00105         case core::operationMode::PWM_PC:
00106         {
00107             TIMER0_SELECT_OPERATION_MODE(1);
00108             break;
00109         }
00110         case core::operationMode::CTC_OCR:
00111         {
00112             TIMER0_SELECT_OPERATION_MODE(2);
00113             break;
00114         }
00115         case core::operationMode::fast_PWM:
00116         {
00117             TIMER0_SELECT_OPERATION_MODE(3);
00118             break;
00119         }
00120     }
00121 }
```

```

00119     }
00120     case core::operationMode::PWM_PC_OCR:
00121     {
00122         TIMER0_SELECT_OPERATION_MODE(5);
00123         break;
00124     }
00125     case core::operationMode::fast_PWM_OCR:
00126     {
00127         TIMER0_SELECT_OPERATION_MODE(7);
00128         break;
00129     }
00130
00131 }
00132
00133 }

```

References [core::CTC_OCR](#), [core::fast_PWM](#), [core::fast_PWM_OCR](#), [core::normal](#), [core::PWM_PC](#), [core::PWM_PC_OCR](#), and [TIMER0_SELECT_OPERATION_MODE](#).

6.15.3.14 setCounter()

```

void core::TimerCounter0::setCounter (
    const uint16_t & ar_dataBuffer ) [override], [virtual]

```

Implements [core::TimerCounter](#).

Definition at line 171 of file [TimerCounter0.cpp](#).

```

00172 {
00173     TCNT0 = static_cast<uint8_t>(ar_dataBuffer);
00174 }

```

6.15.3.15 setOutputCompareRegister()

```

void core::TimerCounter0::setOutputCompareRegister (
    const channel & ar_channel,
    const uint16_t & ar_dataBuffer ) [override], [virtual]

```

Implements [core::TimerCounter](#).

Definition at line 181 of file [TimerCounter0.cpp](#).

```

00182 {
00183     switch (ar_channel)
00184     {
00185         case core::channel::A:
00186         {
00187             OCR0A = static_cast<uint8_t>(ar_dataBuffer);
00188             break;
00189         }
00190         case core::channel::B:
00191         {
00192             OCR0B = static_cast<uint8_t>(ar_dataBuffer);
00193             break;
00194         }
00195     }
00196 }
00197 }

```

References [core::A](#), and [core::B](#).

6.15.3.16 start()

```
void core::TimerCounter0::start ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 136 of file [TimerCounter0.cpp](#).

```
00137 {  
00138     TIMER0_SELECT_CLOCK_SOURCE(m_clockSource);  
00139 }
```

References [TIMER0_SELECT_CLOCK_SOURCE](#).

6.15.3.17 stop()

```
void core::TimerCounter0::stop ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 146 of file [TimerCounter0.cpp](#).

```
00147 {  
00148     TIMER0_STOP;  
00149 }
```

References [TIMER0_STOP](#).

6.15.4 Member Data Documentation

6.15.4.1 __externally_visible__

```
static void core::TimerCounter0::__externally_visible__
```

Definition at line 313 of file [TimerCounter0.h](#).

6.15.4.2 __used__

```
static void core::TimerCounter0::__used__
```

Definition at line 313 of file [TimerCounter0.h](#).

6.15.4.3 m_clockPrescaler

```
uint16_t core::TimerCounter0::m_clockPrescaler [private]
```

Definition at line 340 of file [TimerCounter0.h](#).

6.15.4.4 m_clockSource

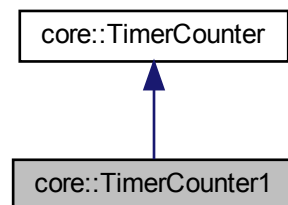
```
uint8_t core::TimerCounter0::m_clockSource [private]
```

Definition at line 342 of file [TimerCounter0.h](#).

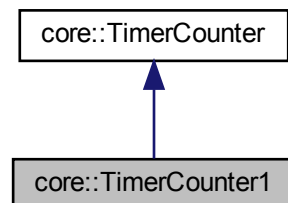
6.16 core::TimerCounter1 Class Reference

```
#include <TimerCounter1.h>
```

Inheritance diagram for core::TimerCounter1:



Collaboration diagram for core::TimerCounter1:



Public Member Functions

- void [selectOperationMode](#) (const [operationMode](#) &ar_operationMode) override
- void [start](#) () override
- void [stop](#) () override
- void [selectClockSource](#) (const [clockSource](#) &ar_clockSource) override
- void [selectCompareOutputMode](#) (const [channel](#) &ar_channel, const [compareOutputMode](#) &ar_compareOutputMode) override
- void [setCounter](#) (const uint16_t &ar_dataBuffer) override
- uint16_t [getCounter](#) () const override
- void [setOutputCompareRegister](#) (const [channel](#) &ar_channel, const uint16_t &ar_dataBuffer) override
- uint16_t [getOutputCompareRegister](#) (const [channel](#) &ar_channel) const override
- void [setInputCaptureRegister](#) (const uint16_t &ar_dataBuffer)
- uint16_t [getInputCaptureRegister](#) () const
- void [enableOutputCompareMatchInterrupt](#) (const [channel](#) &ar_channel, const uint8_t a_enable) override
- void [enableOverflowInterrupt](#) (const uint8_t a_enable) override
- void [enableInputCaptureInterrupt](#) (const uint8_t a_enable)
- uint16_t [getClockPrescaler](#) () override

Static Public Member Functions

- static [TimerCounter1](#) & [getInstance](#) (const [channel](#) &ar_channel=[channel::A](#), const [operationMode](#) &ar_operationMode=[operationMode::normal](#), const [clockSource](#) &ar_clockSource=[clockSource::noClock](#), const [compareOutputMode](#) &ar_compareOutputMode=[compareOutputMode::normal](#))
- static void [outputCompareMatchAServiceRoutine](#) () __asm__(STR(TIMER1_COM_CHANNEL_A_INTERRUPT)) __attribute__((__signal__
- static void [outputCompareMatchBServiceRoutine](#) () __asm__(STR(TIMER1_COM_CHANNEL_B_INTERRUPT)) __attribute__((__signal__
- static void [overflowServiceRoutine](#) () __asm__(STR(TIMER1_OVERFLOW_INTERRUPT)) __attribute__((__signal__
- static void [inputCaptureServiceRoutine](#) () __asm__(STR(TIMER1_INPUT_CAPTURE_INTERRUPT)) __attribute__((__signal__

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [TimerCounter1](#) (const [channel](#) &ar_channel, const [operationMode](#) &ar_operationMode, const [clockSource](#) &ar_clockSource, const [compareOutputMode](#) &ar_compareOutputMode)
- [~TimerCounter1](#) ()
- [TimerCounter1](#) (const [TimerCounter1](#) &)
Overried Copy constructor.
- const [TimerCounter1](#) & [operator=](#) (const [TimerCounter1](#) &)
Override assign operator.

Private Attributes

- uint16_t [m_clockPrescaler](#)
- uint8_t [m_clockSource](#)

6.16.1 Detailed Description

Definition at line 279 of file [TimerCounter1.h](#).

6.16.2 Constructor & Destructor Documentation

6.16.2.1 TimerCounter1() [1/2]

```
core::TimerCounter1::TimerCounter1 (
    const channel & ar_channel,
    const operationMode & ar_operationMode,
    const clockSource & ar_clockSource,
    const compareOutputMode & ar_compareOutputMode ) [private]
```

Definition at line 20 of file [TimerCounter1.cpp](#).

```
00024 {
00025     core::MCU::enableTimerCounter1(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel,ar_compareOutputMode);
00030
00031
00032 }
```

References [core::MCU::enableTimerCounter1\(\)](#).

6.16.2.2 ~TimerCounter1()

```
core::TimerCounter1::~~TimerCounter1 ( ) [private]
```

Definition at line 33 of file [TimerCounter1.cpp](#).

```
00034 {
00035
00036 }
```

6.16.2.3 TimerCounter1() [2/2]

```
core::TimerCounter1::TimerCounter1 (
    const TimerCounter1 & ) [private]
```

Overried Copy constructor.

6.16.3 Member Function Documentation

6.16.3.1 enableInputCaptureInterrupt()

```
void core::TimerCounter1::enableInputCaptureInterrupt (
    const uint8_t a_enable )
```

Definition at line 309 of file [TimerCounter1.cpp](#).

```
00310 {
00311     if (a_enable) {
00312
00313         TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT;
00314
00315     } else {
00316
00317         TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT;
00318     }
00319 }
```

References [TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT](#), and [TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT](#).

6.16.3.2 enableOutputCompareMatchInterrupt()

```
void core::TimerCounter1::enableOutputCompareMatchInterrupt (
    const channel & ar_channel,
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 260 of file [TimerCounter1.cpp](#).

```
00261 {
00262     switch (ar_channel)
00263     {
00264         case core::channel::A:
00265         {
00266             if (a_enable) {
00267
00268                 TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT;
00269
00270             } else {
00271
00272                 TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT;
00273             }
00274             break;
00275         }
00276         case core::channel::B:
00277         {
00278             if (a_enable) {
00279
00280                 TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT;
00281
00282             } else {
00283
00284                 TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT;
00285             }
00286             break;
00287         }
00288     }
00289 }
00290
00291 }
```

References [core::A](#), [core::B](#), [TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT](#), [TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT](#), [TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT](#), and [TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT](#).

6.16.3.3 enableOverflowInterrupt()

```
void core::TimerCounter1::enableOverflowInterrupt (
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 295 of file [TimerCounter1.cpp](#).

```
00296 {
00297
00298     if (a_enable) {
00299
00300         TIMER1_ENABLE_OVERFLOW_INTERRUPT;
00301
00302     } else {
00303
00304         TIMER1_DISABLE_OVERFLOW_INTERRUPT;
00305     }
00306 }
00307 }
```

References [TIMER1_DISABLE_OVERFLOW_INTERRUPT](#), and [TIMER1_ENABLE_OVERFLOW_INTERRUPT](#).

6.16.3.4 getClockPrescaler()

```
uint16_t core::TimerCounter1::getClockPrescaler ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 186 of file [TimerCounter1.cpp](#).

```
00187 {
00188     return m_clockPrescaler;
00189 }
```

Referenced by [component::ServoMotor::connect\(\)](#), and [component::ServoMotor::rotate\(\)](#).

6.16.3.5 getCounter()

```
uint16_t core::TimerCounter1::getCounter ( ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 221 of file [TimerCounter1.cpp](#).

```
00222 {
00223     return TCNT1;
00224 }
```

6.16.3.6 getInputCaptureRegister()

```
uint16_t core::TimerCounter1::getInputCaptureRegister ( ) const
```

Definition at line 327 of file [TimerCounter1.cpp](#).

```
00328 {
00329     return ICR1;
00330 }
```


6.16.3.7 getInstance()

```
core::TimerCounter1 & core::TimerCounter1::getInstance (
    const channel & ar_channel = channel::A,
    const operationMode & ar_operationMode = operationMode::normal,
    const clockSource & ar_clockSource = clockSource::noClock,
    const compareOutputMode & ar_compareOutputMode = compareOutputMode::normal )
[static]
```

Definition at line 5 of file [TimerCounter1.cpp](#).

```
00009 {
00010     static TimerCounter1 l_instance(ar_channel,
00011                                     ar_operationMode,
00012                                     ar_clockSource,
00013                                     ar_compareOutputMode);
00014
00015     return l_instance;
00016
00017
00018 }
```

6.16.3.8 getOutputCompareRegister()

```
uint16_t core::TimerCounter1::getOutputCompareRegister (
    const channel & ar_channel ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 245 of file [TimerCounter1.cpp](#).

```
00246 {
00247     switch (ar_channel)
00248     {
00249         case core::channel::A:
00250         {
00251             return OCR1A;
00252         }
00253         case core::channel::B:
00254         {
00255             return OCR1B;
00256         }
00257     }
00258 }
```

References [core::A](#), and [core::B](#).

6.16.3.9 inputCaptureServiceRoutine()

```
static void core::TimerCounter1::inputCaptureServiceRoutine ( ) [static]
```

6.16.3.10 operator=()

```
const TimerCounter1& core::TimerCounter1::operator= (
    const TimerCounter1 & ) [private]
```

Override assign operator.

6.16.3.11 outputCompareMatchAServiceRoutine()

```
static void core::TimerCounter1::outputCompareMatchAServiceRoutine ( ) [static]
```

6.16.3.12 outputCompareMatchBServiceRoutine()

```
static void core::TimerCounter1::outputCompareMatchBServiceRoutine ( ) [static]
```

6.16.3.13 overflowServiceRoutine()

```
static void core::TimerCounter1::overflowServiceRoutine ( ) [static]
```

6.16.3.14 selectClockSource()

```
void core::TimerCounter1::selectClockSource (
    const clockSource & ar_clockSource ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 38 of file [TimerCounter1.cpp](#).

```
00039 {
00040     switch (ar_clockSource)
00041     {
00042         case core::clockSource::noClock:
00043         {
00044             m_clockPrescaler=0;
00045             m_clockSource=0;
00046             break;
00047         }
00048         case core::clockSource::PS_1:
00049         {
00050             m_clockPrescaler=1;
00051             m_clockSource=1;
00052             break;
00053         }
00054         case core::clockSource::PS_8:
00055         {
00056             m_clockPrescaler=8;
00057             m_clockSource=2;
00058             break;
00059         }
00060         case core::clockSource::PS_64:
00061         {
00062             m_clockPrescaler=64;
00063             m_clockSource=3;
00064             break;
00065         }
00066         case core::clockSource::PS_256:
00067         {
00068             m_clockPrescaler=256;
00069             m_clockSource=4;
00070             break;
00071         }
00072         case core::clockSource::PS_1024:
00073         {
00074             m_clockPrescaler=1024;
00075             m_clockSource=5;
00076             break;
00077         }
00078         case core::clockSource::extern_Clock_T0_Falling_Edge:
```

```

00079     {
00080         m_clockPrescaler=0;
00081         m_clockSource=6;
00082         break;
00083     }
00084     case core::clockSource::extern_Clock_T0_Rising_Edge:
00085     {
00086         m_clockPrescaler=0;
00087         m_clockSource=7;
00088         break;
00089     }
00090 }
00091
00092
00093 }
```

References [core::extern_Clock_T0_Falling_Edge](#), [core::extern_Clock_T0_Rising_Edge](#), [core::noClock](#), [core::PS_1](#), [core::PS_1024](#), [core::PS_256](#), [core::PS_64](#), and [core::PS_8](#).

6.16.3.15 selectCompareOutputMode()

```

void core::TimerCounter1::selectCompareOutputMode (
    const channel & ar_channel,
    const compareOutputMode & ar_compareOutputMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 197 of file [TimerCounter1.cpp](#).

```

00198 {
00199     switch (ar_channel)
00200     {
00201         case core::channel::A:
00202         {
00203             TIMER1_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00204             break;
00205         }
00206         case core::channel::B:
00207         {
00208             TIMER1_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00209             break;
00210         }
00211     }
00212 }
00213 }
```

References [core::A](#), [core::B](#), [TIMER1_SELECT_COM_CHANNEL_A](#), and [TIMER1_SELECT_COM_CHANNEL_B](#).

Referenced by [component::ServoMotor::connect\(\)](#), and [component::ServoMotor::disconnect\(\)](#).

6.16.3.16 selectOperationMode()

```

void core::TimerCounter1::selectOperationMode (
    const operationMode & ar_operationMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 95 of file [TimerCounter1.cpp](#).

```

00096 {
00097     switch (ar_operationMode)
00098     {
00099         case core::operationMode::normal:
00100         {
00101             TIMER1_SELECT_OPERATION_MODE(0);
```

```

00102         break;
00103     }
00104     case core::operationMode::PWM_PC_8bit:
00105     {
00106         TIMER1_SELECT_OPERATION_MODE(1);
00107         break;
00108     }
00109     case core::operationMode::PWM_PC_9bit:
00110     {
00111         TIMER1_SELECT_OPERATION_MODE(2);
00112         break;
00113     }
00114     case core::operationMode::PWM_PC_10bit:
00115     {
00116         TIMER1_SELECT_OPERATION_MODE(3);
00117         break;
00118     }
00119     case core::operationMode::CTC_OCR:
00120     {
00121         TIMER1_SELECT_OPERATION_MODE(4);
00122         break;
00123     }
00124     case core::operationMode::fast_PWM_8bit:
00125     {
00126         TIMER1_SELECT_OPERATION_MODE(5);
00127         break;
00128     }
00129     case core::operationMode::fast_PWM_9bit:
00130     {
00131         TIMER1_SELECT_OPERATION_MODE(6);
00132         break;
00133     }
00134     case core::operationMode::fast_PWM_10bit:
00135     {
00136         TIMER1_SELECT_OPERATION_MODE(7);
00137         break;
00138     }
00139     case core::operationMode::PWM_PFC_ICR:
00140     {
00141         TIMER1_SELECT_OPERATION_MODE(8);
00142         break;
00143     }
00144     case core::operationMode::PWM_PFC_OCR:
00145     {
00146         TIMER1_SELECT_OPERATION_MODE(9);
00147         break;
00148     }
00149     case core::operationMode::PWM_PC_ICR:
00150     {
00151         TIMER1_SELECT_OPERATION_MODE(10);
00152         break;
00153     }
00154     case core::operationMode::PWM_PC_OCR:
00155     {
00156         TIMER1_SELECT_OPERATION_MODE(11);
00157         break;
00158     }
00159     case core::operationMode::CTC_ICR:
00160     {
00161         TIMER1_SELECT_OPERATION_MODE(12);
00162         break;
00163     }
00164     case core::operationMode::fast_PWM_ICR:
00165     {
00166         TIMER1_SELECT_OPERATION_MODE(14);
00167         break;
00168     }
00169     case core::operationMode::fast_PWM_OCR:
00170     {
00171         TIMER1_SELECT_OPERATION_MODE(15);
00172         break;
00173     }
00174 }
00175 }
00176
00177
00178 }

```

References [core::CTC_ICR](#), [core::CTC_OCR](#), [core::fast_PWM_10bit](#), [core::fast_PWM_8bit](#), [core::fast_PWM_9bit](#), [core::fast_PWM_ICR](#), [core::fast_PWM_OCR](#), [core::normal](#), [core::PWM_PC_10bit](#), [core::PWM_PC_8bit](#), [core::PWM_PC_9bit](#), [core::PWM_PC_ICR](#), [core::PWM_PC_OCR](#), [core::PWM_PFC_ICR](#), [core::PWM_PFC_OCR](#), and [TIMER1_SELECT_OPERATION_MODE](#).

Referenced by [component::ServoMotor::connect\(\)](#).

6.16.3.17 setCounter()

```
void core::TimerCounter1::setCounter (
    const uint16_t & ar_dataBuffer ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 216 of file [TimerCounter1.cpp](#).

```
00217 {
00218     TCNT1 = ar_dataBuffer;
00219 }
```

Referenced by [component::ServoMotor::connect\(\)](#).

6.16.3.18 setInputCaptureRegister()

```
void core::TimerCounter1::setInputCaptureRegister (
    const uint16_t & ar_dataBuffer )
```

Definition at line 321 of file [TimerCounter1.cpp](#).

```
00322 {
00323     ICR1 = ar_dataBuffer;
00324 }
```

Referenced by [component::ServoMotor::connect\(\)](#).

6.16.3.19 setOutputCompareRegister()

```
void core::TimerCounter1::setOutputCompareRegister (
    const channel & ar_channel,
    const uint16_t & ar_dataBuffer ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 226 of file [TimerCounter1.cpp](#).

```
00227 {
00228     switch (ar_channel)
00229     {
00230         case core::channel::A:
00231         {
00232             OCR1A = ar_dataBuffer;
00233             break;
00234         }
00235         case core::channel::B:
00236         {
00237             OCR1B = ar_dataBuffer;
00238             break;
00239         }
00240     }
00241 }
```

References [core::A](#), and [core::B](#).

Referenced by [component::ServoMotor::rotate\(\)](#).

6.16.3.20 start()

```
void core::TimerCounter1::start ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 181 of file [TimerCounter1.cpp](#).

```
00182 {  
00183     TIMER1\_SELECT\_CLOCK\_SOURCE(m_clockSource);  
00184 }
```

References [TIMER1_SELECT_CLOCK_SOURCE](#).

Referenced by [component::ServoMotor::rotate\(\)](#).

6.16.3.21 stop()

```
void core::TimerCounter1::stop ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 191 of file [TimerCounter1.cpp](#).

```
00192 {  
00193     TIMER1\_STOP;  
00194 }
```

References [TIMER1_STOP](#).

Referenced by [component::ServoMotor::disconnect\(\)](#).

6.16.4 Member Data Documentation

6.16.4.1 __externally_visible__

```
static void core::TimerCounter1::__externally_visible__
```

Definition at line 320 of file [TimerCounter1.h](#).

6.16.4.2 __used__

```
static void core::TimerCounter1::__used__
```

Definition at line 320 of file [TimerCounter1.h](#).

6.16.4.3 m_clockPrescaler

```
uint16_t core::TimerCounter1::m_clockPrescaler [private]
```

Definition at line 349 of file [TimerCounter1.h](#).

6.16.4.4 m_clockSource

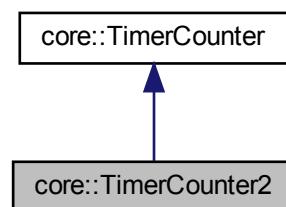
```
uint8_t core::TimerCounter1::m_clockSource [private]
```

Definition at line 351 of file [TimerCounter1.h](#).

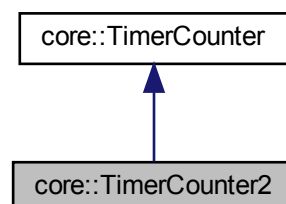
6.17 core::TimerCounter2 Class Reference

```
#include <TimerCounter2.h>
```

Inheritance diagram for core::TimerCounter2:



Collaboration diagram for core::TimerCounter2:



Public Member Functions

- void [selectOperationMode](#) (const [operationMode](#) &ar_operationMode) override
- void [start](#) () override
- void [stop](#) () override
- void [selectClockSource](#) (const [clockSource](#) &ar_clockSource) override
- void [selectCompareOutputMode](#) (const [channel](#) &ar_channel, const [compareOutputMode](#) &ar_compareOutputMode) override
- void [setCounter](#) (const uint16_t &ar_dataBuffer) override
- uint16_t [getCounter](#) () const override
- void [setOutputCompareRegister](#) (const [channel](#) &ar_channel, const uint16_t &ar_dataBuffer) override
- uint16_t [getOutputCompareRegister](#) (const [channel](#) &ar_channel) const override
- void [enableOutputCompareMatchInterrupt](#) (const [channel](#) &ar_channel, const uint8_t a_enable) override
- void [enableOverflowInterrupt](#) (const uint8_t a_enable) override
- uint16_t [getClockPrescaler](#) () override

Static Public Member Functions

- static [TimerCounter2](#) & [getInstance](#) (const [channel](#) &ar_channel=[channel::A](#), const [operationMode](#) &ar_operationMode=[operationMode::normal](#), const [clockSource](#) &ar_clockSource=[clockSource::noClock](#), const [compareOutputMode](#) &ar_compareOutputMode=[compareOutputMode::normal](#))
- static void [outputCompareMatchAServiceRoutine](#) () __asm__(STR(TIMER2_COM_CHANNEL_A_INTERRUPT)) __attribute__((__signal__))
- static void [outputCompareMatchBServiceRoutine](#) () __asm__(STR(TIMER2_COM_CHANNEL_B_INTERRUPT)) __attribute__((__signal__))
- static void [overflowServiceRoutine](#) () __asm__(STR(TIMER2_OVERFLOW_INTERRUPT)) __attribute__((__signal__))

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [TimerCounter2](#) (const [channel](#) &ar_channel, const [operationMode](#) &ar_operationMode, const [clockSource](#) &ar_clockSource, const [compareOutputMode](#) &ar_compareOutputMode)
- [~TimerCounter2](#) ()
- [TimerCounter2](#) (const [TimerCounter2](#) &)
Overried Copy constructor.
- const [TimerCounter2](#) & [operator=](#) (const [TimerCounter2](#) &)
Override assign operator.

Private Attributes

- uint16_t [m_clockPrescaler](#)
- uint8_t [m_clockSource](#)

6.17.1 Detailed Description

Definition at line 279 of file [TimerCounter2.h](#).

6.17.2 Constructor & Destructor Documentation

6.17.2.1 TimerCounter2() [1/2]

```
core::TimerCounter2::TimerCounter2 (
    const channel & ar_channel,
    const operationMode & ar_operationMode,
    const clockSource & ar_clockSource,
    const compareOutputMode & ar_compareOutputMode ) [private]
```

Definition at line 20 of file [TimerCounter2.cpp](#).

```
00024 {
00025     core::MCU::enableTimerCounter2(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel, ar_compareOutputMode);
00030
00031 }
```

References [core::MCU::enableTimerCounter2\(\)](#).

6.17.2.2 ~TimerCounter2()

```
core::TimerCounter2::~~TimerCounter2 ( ) [private]
```

Definition at line 32 of file [TimerCounter2.cpp](#).

```
00033 {
00034
00035 }
```

6.17.2.3 TimerCounter2() [2/2]

```
core::TimerCounter2::TimerCounter2 (
    const TimerCounter2 & ) [private]
```

Overried Copy constructor.

6.17.3 Member Function Documentation

6.17.3.1 enableOutputCompareMatchInterrupt()

```
void core::TimerCounter2::enableOutputCompareMatchInterrupt (
    const channel & ar_channel,
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 215 of file [TimerCounter2.cpp](#).

```
00216 {
00217     switch (ar_channel)
00218     {
00219         case core::channel::A:
00220         {
00221             if (a_enable) {
00222
00223                 TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT;
00224
00225             } else {
00226
00227                 TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT;
00228
00229             }
00230             break;
00231         }
00232         case core::channel::B:
00233         {
00234             if (a_enable) {
00235
00236                 TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT;
00237
00238             } else {
00239
00240                 TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT;
00241
00242             }
00243             break;
00244         }
00245     }
00246 }
```

References [core::A](#), [core::B](#), [TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT](#), [TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT](#), [TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT](#), and [TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT](#).

6.17.3.2 enableOverflowInterrupt()

```
void core::TimerCounter2::enableOverflowInterrupt (
    const uint8_t a_enable ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 250 of file [TimerCounter2.cpp](#).

```
00251 {
00252
00253     if (a_enable) {
00254
00255         TIMER2_ENABLE_OVERFLOW_INTERRUPT;
00256
00257     } else {
00258
00259         TIMER2_DISABLE_OVERFLOW_INTERRUPT;
00260     }
00261 }
00262 }
```

References [TIMER2_DISABLE_OVERFLOW_INTERRUPT](#), and [TIMER2_ENABLE_OVERFLOW_INTERRUPT](#).

6.17.3.3 getClockPrescaler()

```
uint16_t core::TimerCounter2::getClockPrescaler ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 138 of file [TimerCounter2.cpp](#).

```
00139 {  
00140     return m_clockPrescaler;  
00141 }
```

6.17.3.4 getCounter()

```
uint16_t core::TimerCounter2::getCounter ( ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 176 of file [TimerCounter2.cpp](#).

```
00177 {  
00178     return TCNT2;  
00179 }
```

6.17.3.5 getInstance()

```
core::TimerCounter2 & core::TimerCounter2::getInstance (  
    const channel & ar_channel = channel::A,  
    const operationMode & ar_operationMode = operationMode::normal,  
    const clockSource & ar_clockSource = clockSource::noClock,  
    const compareOutputMode & ar_compareOutputMode = compareOutputMode::normal )  
[static]
```

Definition at line 5 of file [TimerCounter2.cpp](#).

```
00009 {  
00010     static TimerCounter2 l_instance(ar_channel,  
00011                                     ar_operationMode,  
00012                                     ar_clockSource,  
00013                                     ar_compareOutputMode);  
00014  
00015     return l_instance;  
00016  
00017  
00018 }
```

6.17.3.6 getOutputCompareRegister()

```
uint16_t core::TimerCounter2::getOutputCompareRegister (
    const channel & ar_channel ) const [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 199 of file [TimerCounter2.cpp](#).

```
00200 {
00201     switch (ar_channel)
00202     {
00203         case core::channel::A:
00204         {
00205             return OCR2A;
00206         }
00207         case core::channel::B:
00208         {
00209             return OCR2B;
00210         }
00211     }
00212 }
00213 }
```

References [core::A](#), and [core::B](#).

6.17.3.7 operator=()

```
const TimerCounter2& core::TimerCounter2::operator= (
    const TimerCounter2 & ) [private]
```

Override assign operator.

6.17.3.8 outputCompareMatchAServiceRoutine()

```
static void core::TimerCounter2::outputCompareMatchAServiceRoutine ( ) [static]
```

6.17.3.9 outputCompareMatchBServiceRoutine()

```
static void core::TimerCounter2::outputCompareMatchBServiceRoutine ( ) [static]
```

6.17.3.10 overflowServiceRoutine()

```
static void core::TimerCounter2::overflowServiceRoutine ( ) [static]
```

6.17.3.11 selectClockSource()

```
void core::TimerCounter2::selectClockSource (
    const clockSource & ar_clockSource ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 37 of file [TimerCounter2.cpp](#).

```
00038 {
00039     switch (ar_clockSource)
00040     {
00041         case core::clockSource::noClock:
00042         {
00043             m_clockPrescaler=0;
00044             m_clockSource=0;
00045             break;
00046         }
00047         case core::clockSource::PS_1:
00048         {
00049             m_clockPrescaler=1;
00050             m_clockSource=1;
00051             break;
00052         }
00053         case core::clockSource::PS_8:
00054         {
00055             m_clockPrescaler=8;
00056             m_clockSource=2;
00057             break;
00058         }
00059         case core::clockSource::PS_32:
00060         {
00061             m_clockPrescaler=32;
00062             m_clockSource=3;
00063             break;
00064         }
00065         case core::clockSource::PS_64:
00066         {
00067             m_clockPrescaler=64;
00068             m_clockSource=4;
00069             break;
00070         }
00071         case core::clockSource::PS_128:
00072         {
00073             m_clockPrescaler=128;
00074             m_clockSource=5;
00075             break;
00076         }
00077         case core::clockSource::PS_256:
00078         {
00079             m_clockPrescaler=256;
00080             m_clockSource=6;
00081             break;
00082         }
00083         case core::clockSource::PS_1024:
00084         {
00085             m_clockPrescaler=1024;
00086             m_clockSource=7;
00087             break;
00088         }
00089     }
00090 }
00091 }
```

References [core::noClock](#), [core::PS_1](#), [core::PS_1024](#), [core::PS_128](#), [core::PS_256](#), [core::PS_32](#), [core::PS_64](#), and [core::PS_8](#).

6.17.3.12 selectCompareOutputMode()

```
void core::TimerCounter2::selectCompareOutputMode (
    const channel & ar_channel,
    const compareOutputMode & ar_compareOutputMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 150 of file [TimerCounter2.cpp](#).

```
00151 {
00152     switch (ar_channel)
00153     {
00154         case core::channel::A:
00155         {
00156             TIMER2_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00157             break;
00158         }
00159         case core::channel::B:
00160         {
00161             TIMER2_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00162             break;
00163         }
00164     }
00165 }
00166
00167 }
```

References [core::A](#), [core::B](#), [TIMER2_SELECT_COM_CHANNEL_A](#), and [TIMER2_SELECT_COM_CHANNEL_B](#).

6.17.3.13 selectOperationMode()

```
void core::TimerCounter2::selectOperationMode (
    const operationMode & ar_operationMode ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 93 of file [TimerCounter2.cpp](#).

```
00094 {
00095     switch (ar_operationMode)
00096     {
00097         case core::operationMode::normal:
00098         {
00099             TIMER2_SELECT_OPERATION_MODE(0);
00100             break;
00101         }
00102         case core::operationMode::PWM_PC:
00103         {
00104             TIMER2_SELECT_OPERATION_MODE(1);
00105             break;
00106         }
00107         case core::operationMode::CTC_OCR:
00108         {
00109             TIMER2_SELECT_OPERATION_MODE(2);
00110             break;
00111         }
00112         case core::operationMode::fast_PWM:
00113         {
00114             TIMER2_SELECT_OPERATION_MODE(3);
00115             break;
00116         }
00117         case core::operationMode::PWM_PC_OCR:
00118         {
00119             TIMER2_SELECT_OPERATION_MODE(5);
00120             break;
00121         }
00122         case core::operationMode::fast_PWM_OCR:
00123         {
00124             TIMER2_SELECT_OPERATION_MODE(7);
00125             break;
00126         }
00127     }
00128 }
00129
00130 }
```

References [core::CTC_OCR](#), [core::fast_PWM](#), [core::fast_PWM_OCR](#), [core::normal](#), [core::PWM_PC](#), [core::PWM_PC_OCR](#), and [TIMER2_SELECT_OPERATION_MODE](#).

6.17.3.14 setCounter()

```
void core::TimerCounter2::setCounter (
    const uint16_t & ar_dataBuffer ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 171 of file [TimerCounter2.cpp](#).

```
00172 {
00173     TCNT2 = static_cast<uint8_t>(ar_dataBuffer);
00174 }
```

6.17.3.15 setOutputCompareRegister()

```
void core::TimerCounter2::setOutputCompareRegister (
    const channel & ar_channel,
    const uint16_t & ar_dataBuffer ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 181 of file [TimerCounter2.cpp](#).

```
00182 {
00183     switch (ar_channel)
00184     {
00185         case core::channel::A:
00186         {
00187             OCR2A = static_cast<uint8_t>(ar_dataBuffer);
00188             break;
00189         }
00190         case core::channel::B:
00191         {
00192             OCR2B = static_cast<uint8_t>(ar_dataBuffer);
00193             break;
00194         }
00195     }
00196 }
```

References [core::A](#), and [core::B](#).

6.17.3.16 start()

```
void core::TimerCounter2::start ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 133 of file [TimerCounter2.cpp](#).

```
00134 {
00135     TIMER2_SELECT_CLOCK_SOURCE(m_clockSource);
00136 }
```

References [TIMER2_SELECT_CLOCK_SOURCE](#).

6.17.3.17 stop()

```
void core::TimerCounter2::stop ( ) [override], [virtual]
```

Implements [core::TimerCounter](#).

Definition at line 144 of file [TimerCounter2.cpp](#).

```
00145 {  
00146     TIMER2_STOP;  
00147 }
```

References [TIMER2_STOP](#).

6.17.4 Member Data Documentation

6.17.4.1 __externally_visible__

```
static void core::TimerCounter2::__externally_visible__
```

Definition at line 313 of file [TimerCounter2.h](#).

6.17.4.2 __used__

```
static void core::TimerCounter2::__used__
```

Definition at line 313 of file [TimerCounter2.h](#).

6.17.4.3 m_clockPrescaler

```
uint16_t core::TimerCounter2::m_clockPrescaler [private]
```

Definition at line 338 of file [TimerCounter2.h](#).

6.17.4.4 m_clockSource

```
uint8_t core::TimerCounter2::m_clockSource [private]
```

Definition at line 340 of file [TimerCounter2.h](#).

6.18 io::USART0 Class Reference

```
#include <USART0.h>
```

Public Member Functions

- void [setBaudRate](#) ()
Set baud rate.
- void [setTransmissionMode](#) (const [transmissionMode](#) &ar_transMode)
Set transmission mode.
- void [setCommunicationMode](#) (const [communicationMode](#) &ar_comMode)
Set communication mode.
- void [setParityMode](#) (const [parityMode](#) &ar_parityMode)
Set parity mode in data frame.
- void [setFrameSize](#) (const [frameSize](#) &ar_frameSize)
Set data frame size.
- void [setStopBit](#) (const [stopBit](#) &ar_stopBit)
Set number of stop bits in data frame.
- void [sendFrames](#) (const uint8_t *ap_dataBuffer, const uint8_t a_size)
Transmit data frames.
- void [sendString](#) (const char *ap_string)
Transmit string.
- void [receiveString](#) (const char *ap_string)
Transmit string.
- void [sendChar](#) (const uint8_t &ar_char)
Transmit character.
- void [sendByte](#) (const uint8_t &ar_byte)
Transmit byte.
- void [sendWord](#) (const uint16_t &ar_word)
Transmit word.
- void [sendLong](#) (const uint32_t &ar_long)
Transmit word.
- void [receiveChar](#) (uint8_t &ar_char)
Receive character.
- void [receiveFrames](#) (uint8_t *ap_dataBuffer, const uint8_t a_size)
Receive data frames.
- void [enableTransmitCompleteInterrupt](#) (const uint8_t ar_enable)
Enable transmit complete interrupt.
- void [enableReceiveCompleteInterrupt](#) (const uint8_t ar_enable)
Enable receive complete interrupt.
- uint8_t [frameError](#) ()
Is there frame error in received data.
- uint8_t [dataOverrun](#) ()
Is there data overrun in received data.
- uint8_t [parityError](#) ()
Is there parity error in received data.
- uint16_t [getNumberBytesReceived](#) ()
Get number of bytes received.
- uint16_t [getNumberBytesSent](#) ()
Get number of bytes sent.
- uint8_t [ready2Send](#) ()
Is ready to send.
- void [resetNumberBytesReceived](#) ()
Reset number of bytes received.

Static Public Member Functions

- static `USART0 & getInstance` (const `transmissionMode` &ar_transMode=transmissionMode::async, const `communicationMode` &ar_comMode=communicationMode::duplex, const `frameSize` &ar_frameSize=frameSize::eightBits, const `stopBit` &ar_stopBit=stopBit::oneStopBit, const `parityMode` &ar_parityMode=parityMode::noParity)
Create a single instance of the USART0 object.
- static void `enableDataRegisterEmptyInterrupt` (const uint8_t ar_enable)
Enable data register empty interrupt.
- static void `receiveCompleteServiceRoutine` () __asm__(STR(USART0_RECEIVE_COMPLETE_INTERRUPT)) __attribute__((__signal__))
Receive complete ISR.
- static void `dataRegisterEmptyServiceRoutine` () __asm__(STR(USART0_DATA_REGISTER_EMPTY_INTERRUPT)) __attribute__((__signal__))
Data register empty ISR.
- static void `transmitCompleteServiceRoutine` () __asm__(STR(USART0_TRANSMIT_COMPLETE_INTERRUPT)) __attribute__((__signal__))
Transmit complete ISR.

Public Attributes

- static void `__used__`
- static void `__externally_visible__`

Private Member Functions

- `USART0` (const `transmissionMode` &ar_transMode, const `communicationMode` &ar_comMode, const `frameSize` &ar_frameSize, const `stopBit` &ar_stopBit, const `parityMode` &ar_parityMode)
Constructor.
- `~USART0` ()
Destructor.
- `USART0` (const `USART0` &)
Overried Copy constructor.
- const `USART0` & `operator=` (const `USART0` &)
Override assign operator.

Static Private Attributes

- static volatile uint8_t `m_status` = 0
received data status
- static const uint8_t * `mp_data2Send` = nullptr
pointer to transmitter buffer
- static uint8_t * `mp_data2Receive` = nullptr
pointer to receiver buffer
- static uint16_t `m_sizeData2Send` = 0
size of data to be transmitted
- static uint16_t `m_sizeData2Receive` = 0
size of data to be received
- static volatile uint16_t `m_numberBytesReceived` = 0
number of bytes received
- static volatile uint16_t `m_numberBytesSent` = 0
number of bytes sent
- static volatile uint8_t `m_ready2Send` = 1
ready to send flag

6.18.1 Detailed Description

Definition at line 112 of file [USART0.h](#).

6.18.2 Constructor & Destructor Documentation

6.18.2.1 USART0() [1/2]

```
io::USART0::USART0 (
    const transmissionMode & ar_transMode,
    const communicationMode & ar_comMode,
    const frameSize & ar_frameSize,
    const stopBit & ar_stopBit,
    const parityMode & ar_parityMode ) [private]
```

Constructor.

Initializes the [USART0](#) object

@param ar_transMode defines transmission mode
 @param ar_comMode defines communication mode
 @param ar_frameSize defines data frame size
 @param ar_stopBit defines number of stop bits
 @param ar_parityMode defines parity mode

Definition at line 34 of file [USART0.cpp](#).

```
00040 {
00041     core::MCU::enableUSART0(1);
00042     setBaudRate();
00043     setTransmissionMode(ar_transMode);
00044     setCommunicationMode(ar_comMode);
00045     setParityMode(ar_parityMode);
00046     setFrameSize(ar_frameSize);
00047     setStopBit(ar_stopBit);
00048     sei();
00049     enableReceiveCompleteInterrupt(1);
00050 }
```

References [core::MCU::enableUSART0\(\)](#).

6.18.2.2 ~USART0()

```
io::USART0::~~USART0 ( ) [private]
```

Destructor.

Definition at line 52 of file [USART0.cpp](#).

```
00053 {
00054
00055 }
```

6.18.2.3 USART0() [2/2]

```
io::USART0::USART0 (
    const USART0 & ) [private]
```

Overried Copy constructor.

6.18.3 Member Function Documentation

6.18.3.1 dataOverrun()

```
uint8_t io::USART0::dataOverrun ( )
```

Is there data overrun in received data.

Definition at line 195 of file USART0.cpp.

```
00196 {
00197     return (m_status & (1 << USART0_DATA_OVERRUN));
00198 }
00199 }
```

References [USART0_DATA_OVERRUN](#).

6.18.3.2 dataRegisterEmptyServiceRoutine()

```
void io::USART0::dataRegisterEmptyServiceRoutine ( ) [static]
```

Data register empty ISR.

Definition at line 331 of file USART0.cpp.

```
00332 {
00333     if (m_sizeData2Send)
00334     {
00335         m_ready2Send = 0;
00336         USART0_DATA_REGISTER = *mp_data2Send++;
00337         m_sizeData2Send--;
00338         m_numberBytesSent++;
00339     }
00340     else
00341     {
00342         enableDataRegisterEmptyInterrupt (0);
00343         m_numberBytesSent = 0;
00344         m_ready2Send = 1;
00345     }
00346 }
00347 }
00348 }
00349 }
00350 }
```

References [USART0_DATA_REGISTER](#).

6.18.3.3 enableDataRegisterEmptyInterrupt()

```
void io::USART0::enableDataRegisterEmptyInterrupt (
    const uint8_t ar_enable ) [static]
```

Enable data register empty interrupt.

@param ar_enable indicates if interrupt is enabled

Definition at line 374 of file [USART0.cpp](#).

```
00375 {
00376     if (ar_enable) {
00377         USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT;
00378     } else {
00379         USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT;
00380     }
00381 }
00382
00383 }
```

References [USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT](#), and [USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT](#).

6.18.3.4 enableReceiveCompleteInterrupt()

```
void io::USART0::enableReceiveCompleteInterrupt (
    const uint8_t ar_enable )
```

Enable receive complete interrupt.

@param ar_enable indicates if interrupt is enabled

Definition at line 363 of file [USART0.cpp](#).

```
00364 {
00365     if (ar_enable) {
00366         USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT;
00367     } else {
00368         USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT;
00369     }
00370 }
00371
00372 }
```

References [USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT](#), and [USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT](#).

6.18.3.5 enableTransmitCompleteInterrupt()

```
void io::USART0::enableTransmitCompleteInterrupt (
    const uint8_t ar_enable )
```

Enable transmit complete interrupt.

@param ar_enable indicates if interrupt is enabled

Definition at line 353 of file [USART0.cpp](#).

```
00354 {
00355     if (ar_enable) {
00356         USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT;
00357     } else {
00358         USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT;
00359     }
00360 }
00361 }
```

References [USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT](#), and [USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT](#).

6.18.3.6 frameError()

```
uint8_t io::USART0::frameError ( )
```

Is there frame error in received data.

Definition at line 189 of file USART0.cpp.

```
00190 {
00191     return (m_status & (1 << USART0_FRAME_ERROR));
00192
00193 }
```

References [USART0_FRAME_ERROR](#).

6.18.3.7 getInstance()

```
io::USART0 & io::USART0::getInstance (
    const transmissionMode & ar_transMode = transmissionMode::async,
    const communicationMode & ar_comMode = communicationMode::duplex,
    const frameSize & ar_frameSize = frameSize::eightBits,
    const stopBit & ar_stopBit = stopBit::oneStopBit,
    const parityMode & ar_parityMode = parityMode::noParity ) [static]
```

Create a single instance of the [USART0](#) object.

```
@param ar_transMode defines transmission mode
@param ar_comMode defines communication mode
@param ar_frameSize defines data frame size
@param ar_stopBit defines number of stop bits
@param ar_parityMode defines parity mode
```

Definition at line 17 of file USART0.cpp.

```
00022 {
00023     static USART0 l_instance(ar_transMode,
00024                             ar_comMode,
00025                             ar_frameSize,
00026                             ar_stopBit,
00027                             ar_parityMode);
00028
00029     return l_instance;
00030 }
```

6.18.3.8 getNumberBytesReceived()

```
uint16_t io::USART0::getNumberBytesReceived ( )
```

Get number of bytes received.

Definition at line 395 of file USART0.cpp.

```
00396 {
00397     return m_numberBytesReceived;
00398 }
```

6.18.3.9 getNumberBytesSent()

```
uint16_t io::USART0::getNumberBytesSent ( )
```

Get number of bytes sent.

Definition at line 390 of file [USART0.cpp](#).

```
00391 {  
00392     return m_numberBytesSent;  
00393 }
```

6.18.3.10 operator=()

```
const USART0& io::USART0::operator= (  
    const USART0 & ) [private]
```

Override assign operator.

6.18.3.11 parityError()

```
uint8_t io::USART0::parityError ( )
```

Is there parity error in received data.

Definition at line 201 of file [USART0.cpp](#).

```
00202 {  
00203     return (m_status & (1 « USART0_PARITY_ERROR));  
00204  
00205 }
```

References [USART0_PARITY_ERROR](#).

6.18.3.12 ready2Send()

```
uint8_t io::USART0::ready2Send ( )
```

Is ready to send.

Definition at line 405 of file [USART0.cpp](#).

```
00406 {  
00407     return m_ready2Send;  
00408  
00409 }
```

6.18.3.13 receiveChar()

```
void io::USART0::receiveChar (
    uint8_t & ar_char )
```

Receive character.

@param ar_char defines charcter to be received

Definition at line 284 of file [USART0.cpp](#).

```
00285 {
00286     m_sizeData2Receive = 1;
00287     mp_data2Receive = &ar_char;
00288 }
```

6.18.3.14 receiveCompleteServiceRoutine()

```
void io::USART0::receiveCompleteServiceRoutine ( ) [static]
```

Receive complete ISR.

Definition at line 306 of file [USART0.cpp](#).

```
00307 {
00308     static volatile uint8_t *lp_dataReceived = mp_data2Receive;
00309     static uint16_t l_dataSize = m_sizeData2Receive;
00310
00311     m_status = USART0_CONTROL_STATUS_REGISTER;
00312
00313     if (l_dataSize)
00314     {
00315         *lp_dataReceived++ = USART0_DATA_REGISTER;
00316         l_dataSize--;
00317         m_numberBytesReceived++;
00318     }
00319     else
00320     {
00321         l_dataSize = m_sizeData2Receive;
00322         lp_dataReceived = mp_data2Receive;
00323     }
00324 }
```

References [USART0_CONTROL_STATUS_REGISTER](#), and [USART0_DATA_REGISTER](#).

6.18.3.15 receiveFrames()

```
void io::USART0::receiveFrames (
    uint8_t * ap_dataBuffer,
    const uint8_t a_size )
```

Receive data frames.

@param ap_dataBuffer defines pointer to receiver buffer

@param a_size defines size of receiver buffer

@param a_ready2Receive indicates if chip ready to receive data

Definition at line 291 of file [USART0.cpp](#).

```
00292 {
00293     m_sizeData2Receive = a_size;
00294     mp_data2Receive = ap_dataBuffer;
00295
00296
00297
00298 }
```


6.18.3.16 receiveString()

```
void io::USART0::receiveString (
    const char * ap_string )
```

Transmit string.

@param ap_string defines pointer to string

Definition at line 300 of file [USART0.cpp](#).

```
00301 {
00302
00303 }
```

6.18.3.17 resetNumberBytesReceived()

```
void io::USART0::resetNumberBytesReceived ( )
```

Reset number of bytes received.

Definition at line 400 of file [USART0.cpp](#).

```
00401 {
00402     m_numberBytesReceived = 0;
00403 }
```

6.18.3.18 sendByte()

```
void io::USART0::sendByte (
    const uint8_t & ar_byte )
```

Transmit byte.

@param ar_byte defines byte to be sent

Definition at line 226 of file [USART0.cpp](#).

```
00227 {
00228     static uint8_t l_byte2Send[3];
00229     l_byte2Send[0] = '0' + (ar_byte / 100);
00230     l_byte2Send[1] = '0' + ((ar_byte / 10) % 10);
00231     l_byte2Send[2] = '0' + (ar_byte % 10);
00232
00233     while (!ready2Send()){};
00234     m_sizeData2Send = 3;
00235     mp_data2Send = l_byte2Send;
00236     enableDataRegisterEmptyInterrupt(1);
00237
00238 }
```

6.18.3.19 sendChar()

```
void io::USART0::sendChar (
    const uint8_t & ar_char )
```

Transmit character.

@param ar_char defines character to be sent

Definition at line 275 of file [USART0.cpp](#).

```
00276 {
00277     while (!ready2Send()){};
00278     m_sizeData2Send = 1;
00279     mp_data2Send = &ar_char;
00280     enableDataRegisterEmptyInterrupt(1);
00281
00282 }
```

6.18.3.20 sendFrames()

```
void io::USART0::sendFrames (
    const uint8_t * ap_dataBuffer,
    const uint8_t a_size )
```

Transmit data frames.

@param ap_dataBuffer defines pointer to transmitter buffer

@param a_size defines size of transmitter buffer

Definition at line 207 of file [USART0.cpp](#).

```
00208 {
00209     while (!ready2Send()){};
00210     m_sizeData2Send = a_size;
00211     mp_data2Send = ap_dataBuffer;
00212     enableDataRegisterEmptyInterrupt(1);
00213 }
```

6.18.3.21 sendLong()

```
void io::USART0::sendLong (
    const uint32_t & ar_long )
```

Transmit word.

@param ar_word defines word to be sent

Definition at line 239 of file [USART0.cpp](#).

```
00240 {
00241     static uint8_t l_word2Send[10];
00242     l_word2Send[0] = '0' + (ar_long / 1000000000);
00243     l_word2Send[1] = '0' + ((ar_long / 100000000) % 10);
00244     l_word2Send[2] = '0' + ((ar_long / 10000000) % 10);
00245     l_word2Send[3] = '0' + ((ar_long / 1000000) % 10);
00246     l_word2Send[4] = '0' + ((ar_long / 100000) % 10);
00247     l_word2Send[5] = '0' + ((ar_long / 10000) % 10);
00248     l_word2Send[6] = '0' + ((ar_long / 1000) % 10);
00249     l_word2Send[7] = '0' + ((ar_long / 100) % 10);
00250     l_word2Send[8] = '0' + ((ar_long / 10) % 10);
00251     l_word2Send[9] = '0' + (ar_long % 10);
00252
00253     while (!ready2Send()){};
00254     m_sizeData2Send = 10;
00255     mp_data2Send = l_word2Send;
00256     enableDataRegisterEmptyInterrupt(1);
00257
00258 }
```

6.18.3.22 sendString()

```
void io::USART0::sendString (
    const char * ap_string )
```

Transmit string.

@param ap_string defines pointer to string

Definition at line 216 of file [USART0.cpp](#).

```
00217 {
00218     while (!ready2Send()){};
00219     m_sizeData2Send = strlen(ap_string);
00220     mp_data2Send = reinterpret_cast<const uint8_t*>(ap_string);
00221     enableDataRegisterEmptyInterrupt(1);
00222 }
00223 }
```

6.18.3.23 sendWord()

```
void io::USART0::sendWord (
    const uint16_t & ar_word )
```

Transmit word.

@param ar_word defines word to be sent

Definition at line 259 of file [USART0.cpp](#).

```
00260 {
00261     static uint8_t l_word2Send[5];
00262     l_word2Send[0] = '0' + (ar_word / 10000);
00263     l_word2Send[1] = '0' + ((ar_word / 1000) % 10);
00264     l_word2Send[2] = '0' + ((ar_word / 100) % 10);
00265     l_word2Send[3] = '0' + ((ar_word / 10) % 10);
00266     l_word2Send[4] = '0' + (ar_word % 10);
00267 }
00268 while (!ready2Send()){};
00269 m_sizeData2Send = 5;
00270 mp_data2Send = l_word2Send;
00271 enableDataRegisterEmptyInterrupt(1);
00272 }
00273 }
```

6.18.3.24 setBaudRate()

```
void io::USART0::setBaudRate ( )
```

Set baud rate.

Definition at line 57 of file [USART0.cpp](#).

```
00058 {
00059     USART0_SET_BAUDRATE_HIGH_REGISTER;
00060     USART0_SET_BAUDRATE_LOW_REGISTER;
00061 }
00062 }
```

References [USART0_SET_BAUDRATE_HIGH_REGISTER](#), and [USART0_SET_BAUDRATE_LOW_REGISTER](#).

6.18.3.25 setCommunicationMode()

```
void io::USART0::setCommunicationMode (
    const communicationMode & ar_comMode )
```

Set communication mode.

@param *ar_comMode* defines communication mode

Definition at line 89 of file [USART0.cpp](#).

```
00090 {
00091     switch (ar_comMode)
00092     {
00093         case communicationMode::duplex:
00094         {
00095             USART0_ENABLE_TRANSMITTER;
00096             USART0_ENABLE_RECEIVER;
00097             break;
00098         }
00099         case communicationMode::receive:
00100         {
00101             USART0_ENABLE_RECEIVER;
00102             USART0_DISABLE_TRANSMITTER;
00103             break;
00104         }
00105         case communicationMode::transmit:
00106         {
00107             USART0_ENABLE_TRANSMITTER;
00108             USART0_DISABLE_RECEIVER;
00109             break;
00110         }
00111     }
00112 }
00113 }
```

References [io::duplex](#), [io::receive](#), [io::transmit](#), [USART0_DISABLE_RECEIVER](#), [USART0_DISABLE_TRANSMITTER](#), [USART0_ENABLE_RECEIVER](#), and [USART0_ENABLE_TRANSMITTER](#).

6.18.3.26 setFrameSize()

```
void io::USART0::setFrameSize (
    const frameSize & ar_frameSize )
```

Set data frame size.

@param *ar_frameSize* defines data frame size

Definition at line 138 of file [USART0.cpp](#).

```
00139 {
00140     switch (ar_frameSize)
00141     {
00142         case frameSize::eightBits:
00143         {
00144             USART0_SET_8BIT_FRAME_SIZE;
00145             break;
00146         }
00147         case frameSize::sevenBits:
00148         {
00149             USART0_SET_7BIT_FRAME_SIZE;
00150             break;
00151         }
00152         case frameSize::sixBits:
00153         {
00154             USART0_SET_6BIT_FRAME_SIZE;
00155             break;
00156         }
00157     }
00158 }
```

```

00157         case frameSize::fiveBits:
00158         {
00159             USART0_SET_5BIT_FRAME_SIZE;
00160             break;
00161         }
00162         case frameSize::neineBits:
00163         {
00164             USART0_SET_9BIT_FRAME_SIZE;
00165             break;
00166         }
00167     }
00168 }
00169 }

```

References [io::eightBits](#), [io::fiveBits](#), [io::neineBits](#), [io::sevenBits](#), [io::sixBits](#), [USART0_SET_5BIT_FRAME_SIZE](#), [USART0_SET_6BIT_FRAME_SIZE](#), [USART0_SET_7BIT_FRAME_SIZE](#), [USART0_SET_8BIT_FRAME_SIZE](#), and [USART0_SET_9BIT_FRAME_SIZE](#).

6.18.3.27 setParityMode()

```

void io::USART0::setParityMode (
    const parityMode & ar_parityMode )

```

Set parity mode in data frame.

@param ar_parityMode defines parity mode

Definition at line 115 of file [USART0.cpp](#).

```

00116 {
00117     switch (ar_parityMode)
00118     {
00119         case parityMode::noParity:
00120         {
00121             USART0_DISABLE_PARITY_MODE;
00122             break;
00123         }
00124         case parityMode::evenParity:
00125         {
00126             USART0_ENABLE_EVEN_PARITY_MODE;
00127             break;
00128         }
00129         case parityMode::oddParity:
00130         {
00131             USART0_ENABLE_ODD_PARITY_MODE;
00132             break;
00133         }
00134     }
00135 }
00136 }

```

References [io::evenParity](#), [io::noParity](#), [io::oddParity](#), [USART0_DISABLE_PARITY_MODE](#), [USART0_ENABLE_EVEN_PARITY_MODE](#), and [USART0_ENABLE_ODD_PARITY_MODE](#).

6.18.3.28 setStopBit()

```
void io::USART0::setStopBit (
    const stopBit & ar_stopBit )
```

Set number of stop bits in data frame.

@param ar_stopBit defines number of stop bits

Definition at line 170 of file USART0.cpp.

```
00171 {
00172     switch (ar_stopBit)
00173     {
00174         case stopBit::oneStopBit:
00175         {
00176             USART0_SET_ONE_STOP_BIT;
00177             break;
00178         }
00179         case stopBit::twoStopBits:
00180         {
00181             USART0_SET_TWO_STOP_BITS;
00182             break;
00183         }
00184     }
00185 }
00186 }
```

References [io::oneStopBit](#), [io::twoStopBits](#), [USART0_SET_ONE_STOP_BIT](#), and [USART0_SET_TWO_STOP_BITS](#).

6.18.3.29 setTransmissionMode()

```
void io::USART0::setTransmissionMode (
    const transmissionMode & ar_transMode )
```

Set transnmission mode.

@param ar_transMode defines transmission mode

Definition at line 64 of file USART0.cpp.

```
00065 {
00066     switch (ar_transMode)
00067     {
00068         case transmissionMode::async:
00069         {
00070             USART0_ENABLE_ASYNC_TRANSMISSION_MODE;
00071             break;
00072         }
00073         case transmissionMode::sync:
00074         {
00075             USART0_DISABLE_DOUBLE_SPEED_MODE;
00076             USART0_ENABLE_SYNC_TRANSMISSION_MODE;
00077             break;
00078         }
00079         case transmissionMode::masterSPI:
00080         {
00081             USART0_ENABLE_MASTER_SPI_MODE;
00082             break;
00083         }
00084     }
00085 }
00086 }
00087 }
```

References [io::async](#), [io::masterSPI](#), [io::sync](#), [USART0_DISABLE_DOUBLE_SPEED_MODE](#), [USART0_ENABLE_ASYNC_TRANSMISSION_MODE](#), [USART0_ENABLE_MASTER_SPI_MODE](#), and [USART0_ENABLE_SYNC_TRANSMISSION_MODE](#).

6.18.3.30 transmitCompleteServiceRoutine()

```
void io::USART0::transmitCompleteServiceRoutine ( ) [static]
```

Transmit complete ISR.

Definition at line 385 of file [USART0.cpp](#).

```
00386 {  
00387  
00388 }
```

6.18.4 Member Data Documentation

6.18.4.1 __externally_visible__

```
static void io::USART0::__externally_visible__
```

Definition at line 249 of file [USART0.h](#).

6.18.4.2 __used__

```
static void io::USART0::__used__
```

Definition at line 249 of file [USART0.h](#).

6.18.4.3 m_numberBytesReceived

```
volatile uint16_t io::USART0::m_numberBytesReceived = 0 [static], [private]
```

number of bytes received

Definition at line 300 of file [USART0.h](#).

6.18.4.4 m_numberBytesSent

```
volatile uint16_t io::USART0::m_numberBytesSent = 0 [static], [private]
```

number of bytes sent

Definition at line 302 of file [USART0.h](#).

6.18.4.5 m_ready2Send

```
volatile uint8_t io::USART0::m_ready2Send = 1 [static], [private]
```

ready to send flag

Definition at line 304 of file [USART0.h](#).

6.18.4.6 m_sizeData2Receive

```
uint16_t io::USART0::m_sizeData2Receive = 0 [static], [private]
```

size of data to be received

Definition at line 298 of file [USART0.h](#).

6.18.4.7 m_sizeData2Send

```
uint16_t io::USART0::m_sizeData2Send = 0 [static], [private]
```

size of data to be transmitted

Definition at line 296 of file [USART0.h](#).

6.18.4.8 m_status

```
volatile uint8_t io::USART0::m_status = 0 [static], [private]
```

received data status

Definition at line 290 of file [USART0.h](#).

6.18.4.9 mp_data2Receive

```
uint8_t * io::USART0::mp_data2Receive = nullptr [static], [private]
```

pointer to receiver buffer

Definition at line 294 of file [USART0.h](#).

6.18.4.10 mp_data2Send

```
const uint8_t * io::USART0::mp_data2Send = nullptr [static], [private]
```

pointer to transmitter buffer

Definition at line 292 of file [USART0.h](#).

6.19 core::WatchdogTimer Class Reference

```
#include <WatchdogTimer.h>
```

Public Member Functions

- void [selectTimeOut](#) (const [timeOut](#) &ar_timeOut)
- void [reset](#) ()
- void [start](#) (const [operationMode](#) &ar_operationMode)
- void [start](#) (const [operationMode](#) &ar_operationMode, const [timeOut](#) &ar_timeOut)
- void [stop](#) ()

Static Public Member Functions

- static [WatchdogTimer](#) & [getInstance](#) ()
- static void [timeOutServiceRoutine](#) () __asm__(STR(WATCHDOG_TIMEOUT_INTERRUPT)) __attribute__((__signal__))

Public Attributes

- static void [__used__](#)
- static void [__externally_visible__](#)

Private Member Functions

- [WatchdogTimer](#) ()
- [~WatchdogTimer](#) ()
Destructor.
- [WatchdogTimer](#) (const [WatchdogTimer](#) &)
Overried Copy constructor.
- const [WatchdogTimer](#) & [operator=](#) (const [WatchdogTimer](#) &)
Override assign operator.

Private Attributes

- uint8_t [m_timeOut](#)
- uint8_t [m_operationMode](#)

6.19.1 Detailed Description

Definition at line 84 of file [WatchdogTimer.h](#).

6.19.2 Constructor & Destructor Documentation

6.19.2.1 WatchdogTimer() [1/2]

```
core::WatchdogTimer::WatchdogTimer ( ) [private]
```

Definition at line 11 of file [WatchdogTimer.cpp](#).

```
00012 {  
00013     sei();  
00014     stop();  
00015 }
```

6.19.2.2 ~WatchdogTimer()

```
core::WatchdogTimer::~~WatchdogTimer ( ) [private]
```

Destructor.

Definition at line 17 of file [WatchdogTimer.cpp](#).

```
00018 {  
00019  
00020 }
```

6.19.2.3 WatchdogTimer() [2/2]

```
core::WatchdogTimer::WatchdogTimer (  
    const WatchdogTimer & ) [private]
```

Overried Copy constructor.

6.19.3 Member Function Documentation

6.19.3.1 getInstance()

```
core::WatchdogTimer & core::WatchdogTimer::getInstance ( ) [static]
```

Definition at line 4 of file [WatchdogTimer.cpp](#).

```
00005 {  
00006     static WatchdogTimer l_instance;  
00007     return l_instance;  
00008  
00009 }
```

6.19.3.2 operator=()

```
const WatchdogTimer& core::WatchdogTimer::operator= (
    const WatchdogTimer & ) [private]
```

Override assign operator.

6.19.3.3 reset()

```
void core::WatchdogTimer::reset ( )
```

Definition at line 33 of file [WatchdogTimer.cpp](#).

```
00034 {
00035     wdt_reset();
00036
00037 }
```

6.19.3.4 selectTimeOut()

```
void core::WatchdogTimer::selectTimeOut (
    const timeOut & ar_timeOut )
```

Definition at line 22 of file [WatchdogTimer.cpp](#).

```
00023 {
00024     m_timeOut = static_cast<uint8_t>(ar_timeOut);
00025     m_timeOut = static_cast<uint8_t>((m_timeOut & 7) | ((m_timeOut & 8) << 2));
00026     cli();
00027     wdt_reset();
00028     WATCHDOG_SELECT_TIMEOUT(m_timeOut);
00029     sei();
00030
00031 }
```

References [WATCHDOG_SELECT_TIMEOUT](#).

6.19.3.5 start() [1/2]

```
void core::WatchdogTimer::start (
    const operationMode & ar_operationMode )
```

Definition at line 39 of file [WatchdogTimer.cpp](#).

```
00040 {
00041     m_operationMode = static_cast<uint8_t>(ar_operationMode);
00042     m_operationMode = static_cast<uint8_t>((m_operationMode & 1) << 6) | ((m_operationMode & 2) << 3
00043 );
00043     cli();
00044     wdt_reset();
00045     WATCHDOG_START(m_operationMode,m_timeOut);
00046     sei();
00047
00048 }
```

References [WATCHDOG_START](#).

6.19.3.6 start() [2/2]

```
void core::WatchdogTimer::start (
    const operationMode & ar_operationMode,
    const timeOut & ar_timeOut )
```

Definition at line 50 of file [WatchdogTimer.cpp](#).

```
00051 {
00052     m_timeOut = static_cast<uint8_t>(ar_timeOut);
00053     m_timeOut = static_cast<uint8_t>((m_timeOut & 7) | ((m_timeOut & 8) << 2));
00054     m_operationMode = static_cast<uint8_t>(ar_operationMode);
00055     m_operationMode = static_cast<uint8_t>((m_operationMode & 1) << 6) | ((m_operationMode & 2) << 3
    ));
00056     cli();
00057     wdt_reset();
00058     WATCHDOG_START(m_operationMode,m_timeOut);
00059     sei();
00060 }
00061 }
```

References [WATCHDOG_START](#).

6.19.3.7 stop()

```
void core::WatchdogTimer::stop ( )
```

Definition at line 63 of file [WatchdogTimer.cpp](#).

```
00064 {
00065     cli();
00066     wdt_reset();
00067     WATCHDOG_STOP;
00068     sei();
00069 }
00070 }
```

References [WATCHDOG_STOP](#).

6.19.3.8 timeOutServiceRoutine()

```
static void core::WatchdogTimer::timeOutServiceRoutine ( ) [static]
```

6.19.4 Member Data Documentation

6.19.4.1 __externally_visible__

```
void core::WatchdogTimer::__externally_visible__
```

Definition at line 102 of file [WatchdogTimer.h](#).

6.19.4.2 `__used__`

```
void core::WatchdogTimer::__used__
```

Definition at line 102 of file [WatchdogTimer.h](#).

6.19.4.3 `m_operationMode`

```
uint8_t core::WatchdogTimer::m_operationMode [private]
```

Definition at line 125 of file [WatchdogTimer.h](#).

6.19.4.4 `m_timeOut`

```
uint8_t core::WatchdogTimer::m_timeOut [private]
```

Definition at line 123 of file [WatchdogTimer.h](#).

Chapter 7

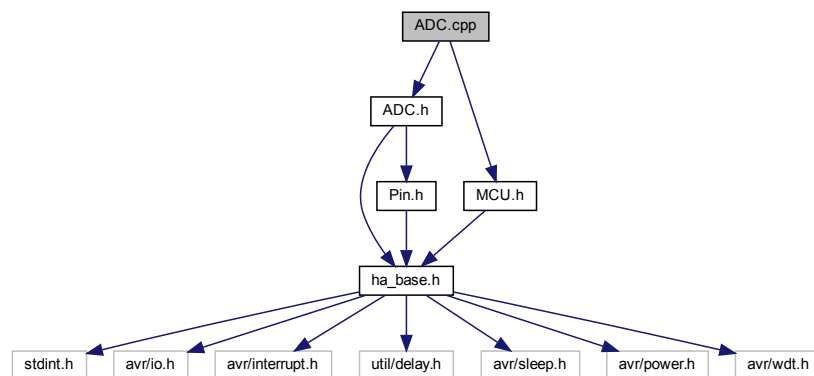
File Documentation

7.1 ADC.cpp File Reference

```
#include "ADC.h"
```

```
#include "MCU.h"
```

Include dependency graph for ADC.cpp:



7.2 ADC.cpp

```
00001 #include "ADC.h"
00002 #include "MCU.h"
00003
00004 volatile uint16_t* core::ADConverter::mp_conversionResult = nullptr;
00005 volatile uint8_t core::ADConverter::m_conversionComplete = 0;
00006 uint8_t core::ADConverter::m_resolution = 10;
00007
00008
00009 core::ADConverter& core::ADConverter::getInstance(const referenceVoltage &ar_refVoltage,
00010                                                    const clockPrescaler& ar_clockPrescaler,
00011                                                    const autoTriggerSource& ar_autoTriggerSource,
00012                                                    const io::Pin &ar_pin)
00013 {
00014
00015     static ADConverter l_instance(ar_refVoltage,
00016                                   ar_clockPrescaler,
00017                                   ar_autoTriggerSource,
00018                                   ar_pin);
```

```

00019
00020     return l_instance;
00021 }
00022
00023 core::ADConverter::ADConverter(const referenceVoltage& ar_refVoltage,
00024                               const clockPrescaler& ar_clockPrescaler,
00025                               const autoTriggerSource& ar_autoTriggerSource,
00026                               const io::Pin& ar_pin)
00027 {
00028     core::MCU::enableADC(1);
00029     selectAnalogInput(ar_pin);
00030     selectReferenceVoltage(ar_refVoltage);
00031     selectClockPrescaler(ar_clockPrescaler);
00032     enableAutoTrigger(1);
00033     selectAutoTriggerSource(ar_autoTriggerSource);
00034     sei();
00035     enableConversionCompleteInterrupt(1);
00036 }
00037
00038 }
00039
00040
00041 core::ADConverter::~ADConverter()
00042 {
00043 }
00044 }
00045
00046
00047 void core::ADConverter::selectReferenceVoltage(const referenceVoltage& ar_refVoltage)
00048 {
00049     ADC_SELECT_REF_VOLTAGE(static_cast<uint8_t>(ar_refVoltage));
00050 }
00051 }
00052
00053 void core::ADConverter::selectAnalogInput(io::Pin a_pin)
00054 {
00055     a_pin.toInput(0);
00056     ADC_SELECT_ANALOG_INPUT(a_pin.getPinNumber());
00057     ADC_DISABLE_DIGITAL_INPUT_REGISTER(a_pin.getPinNumber());
00058 }
00059 }
00060
00061 void core::ADConverter::start()
00062 {
00063     ADC_ENABLE;
00064     ADC_START_CONVERSION;
00065 }
00066
00067 void core::ADConverter::stop()
00068 {
00069     ADC_STOP_CONVERSION;
00070     ADC_DISABLE;
00071 }
00072
00073 void core::ADConverter::enableAutoTrigger(const uint8_t a_enable)
00074 {
00075     if (a_enable) {
00076         ADC_ENABLE_AUTOTRIGGER;
00077     } else {
00078         ADC_DISABLE_AUTOTRIGGER;
00079     }
00080 }
00081 }
00082 }
00083
00084 void core::ADConverter::enableConversionCompleteInterrupt(const uint8_t a_enable)
00085 {
00086     if (a_enable) {
00087         ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT;
00088     } else {
00089         ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT;
00090     }
00091 }
00092 }
00093 }
00094
00095 void core::ADConverter::selectClockPrescaler(const clockPrescaler& ar_clockPrescaler)
00096 {
00097     ADC_SELECT_CLOCK_PRESCALER(static_cast<uint8_t>(ar_clockPrescaler));
00098 }
00099 }
00100
00101
00102 void core::ADConverter::selectAutoTriggerSource(const autoTriggerSource& ar_autoTriggerSource)
00103 {
00104     ADC_SELECT_AUTO_TRIGGER_SOURCE(static_cast<uint8_t>(ar_autoTriggerSource));
00105 }

```



```
00106
00107 }
00108
00109 void core::ADConverter::conversionCompleteServiceRoutine()
00110 {
00111
00112     static uint32_t l_resultData = 0;
00113     static uint16_t l_resultDataIndex = 0;
00114
00115     m_conversionComplete = 0;
00116     switch (m_resolution)
00117     {
00118     case 8:
00119     {
00120         *mp_conversionResult = ADC » 8;
00121         m_conversionComplete = 1;
00122         break;
00123     }
00124     case 9:
00125     {
00126         *mp_conversionResult = ADC » 7;
00127         m_conversionComplete = 1;
00128         break;
00129     }
00130     case 10:
00131     {
00132         *mp_conversionResult = ADC;
00133         m_conversionComplete = 1;
00134         break;
00135     }
00136     case 11:
00137     {
00138
00139         if (l_resultDataIndex < 4)
00140         {
00141             l_resultData += ADC;
00142             l_resultDataIndex++;
00143         }
00144         else
00145         {
00146             *mp_conversionResult = l_resultData » 1;
00147             l_resultData = 0;
00148             l_resultDataIndex = 0;
00149             m_conversionComplete = 1;
00150         }
00151     }
00152     }
00153     break;
00154 }
00155 case 12:
00156 {
00157     if (l_resultDataIndex < 16)
00158     {
00159         l_resultData += ADC;
00160         l_resultDataIndex++;
00161     }
00162     else
00163     {
00164         *mp_conversionResult = l_resultData » 2;
00165         l_resultData = 0;
00166         l_resultDataIndex = 0;
00167         m_conversionComplete = 1;
00168     }
00169 }
00170 break;
00171 }
00172 case 13:
00173 {
00174     if (l_resultDataIndex < 64)
00175     {
00176         l_resultData += ADC;
00177         l_resultDataIndex++;
00178     }
00179     else
00180     {
00181         *mp_conversionResult = l_resultData » 3;
00182         l_resultData = 0;
00183         l_resultDataIndex = 0;
00184         m_conversionComplete = 1;
00185     }
00186 }
00187 break;
00188 }
00189 case 14:
```

```

00193     {
00194         if (l_resultDataIndex < 256)
00195         {
00196             l_resultData += ADC;
00197             l_resultDataIndex++;
00198         }
00199     }
00200     else
00201     {
00202         *mp_conversionResult = l_resultData » 4;
00203         l_resultData = 0;
00204         l_resultDataIndex = 0;
00205         m_conversionComplete = 1;
00206     }
00207     break;
00208 }
00209 case 15:
00210 {
00211     if (l_resultDataIndex < 1024)
00212     {
00213         l_resultData += ADC;
00214         l_resultDataIndex++;
00215     }
00216     else
00217     {
00218         *mp_conversionResult = l_resultData » 5;
00219         l_resultData = 0;
00220         l_resultDataIndex = 0;
00221         m_conversionComplete = 1;
00222     }
00223     break;
00224 }
00225 case 16:
00226 {
00227     if (l_resultDataIndex < 4096)
00228     {
00229         l_resultData += ADC;
00230         l_resultDataIndex++;
00231     }
00232     else
00233     {
00234         *mp_conversionResult = l_resultData » 6;
00235         l_resultData = 0;
00236         l_resultDataIndex = 0;
00237         m_conversionComplete = 1;
00238     }
00239     break;
00240 }
00241 }
00242 }
00243 }
00244 }
00245 }
00246 }
00247 }
00248 }
00249 }
00250 }
00251 }
00252 }
00253 }
00254 }
00255 uint8_t core::ADConverter::conversionComplete()
00256 {
00257     return m_conversionComplete;
00258 }
00259 }
00260 }
00261 }
00262 void core::ADConverter::getConversionResult(uint16_t *ap_resultData, const resolution& ar_resolution)
00263 {
00264     mp_conversionResult = ap_resultData;
00265     switch (ar_resolution)
00266     {
00267     case core::resolution::res_8bit:
00268     {
00269         ADC_ADJUST_RESULT_LEFT;
00270         m_resolution = 8;
00271         break;
00272     }
00273     case core::resolution::res_9bit:
00274     {
00275         ADC_ADJUST_RESULT_LEFT;
00276         m_resolution = 9;
00277         break;
00278     }
00279     }

```

```

00280     case core::resolution::res_10bit:
00281     {
00282         ADC_ADJUST_RESULT_RIGHT;
00283         m_resolution = 10;
00284         break;
00285     }
00286     case core::resolution::res_11bit:
00287     {
00288
00289         m_resolution = 11;
00290         break;
00291     }
00292     case core::resolution::res_12bit:
00293     {
00294         m_resolution = 12;
00295         break;
00296     }
00297     case core::resolution::res_13bit:
00298     {
00299         m_resolution = 13;
00300         break;
00301     }
00302     case core::resolution::res_14bit:
00303     {
00304         m_resolution = 14;
00305         break;
00306     }
00307     case core::resolution::res_15bit:
00308     {
00309         m_resolution = 15;
00310         break;
00311     }
00312     case core::resolution::res_16bit:
00313     {
00314         m_resolution = 16;
00315         break;
00316     }
00317 }
00318
00319
00320 }

```

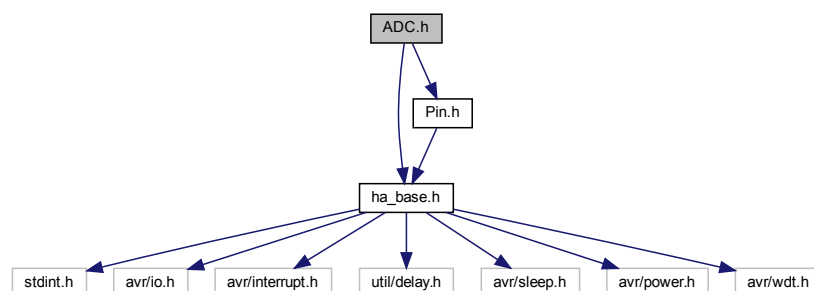
7.3 ADC.h File Reference

Header file of the ADC class.

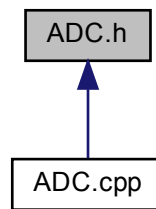
```
#include "ha_base.h"
```

```
#include "Pin.h"
```

Include dependency graph for ADC.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::ADConverter](#)

Namespaces

- [core](#)

Enumerations

- enum [core::resolution](#) : uint8_t {
[core::resolution::res_8bit](#) =0, [core::resolution::res_9bit](#), [core::resolution::res_10bit](#), [core::resolution::res_11bit](#),
[core::resolution::res_12bit](#), [core::resolution::res_13bit](#), [core::resolution::res_14bit](#), [core::resolution::res_15bit](#),
[core::resolution::res_16bit](#) }
- enum [core::referenceVoltage](#) : uint8_t { [core::referenceVoltage::AREF](#) =0, [core::referenceVoltage::AVCC](#),
[core::referenceVoltage::internal](#) }
- enum [core::clockPrescaler](#) : uint8_t {
[core::clockPrescaler::PS_2](#) = 1, [core::clockPrescaler::PS_4](#), [core::clockPrescaler::PS_8](#), [core::clockPrescaler::PS_16](#),
[core::clockPrescaler::PS_32](#), [core::clockPrescaler::PS_64](#), [core::clockPrescaler::PS_128](#) }
- enum [core::autoTriggerSource](#) : uint8_t {
[core::autoTriggerSource::freeRunning](#), [core::autoTriggerSource::analogComparator](#), [core::autoTriggerSource::extInterrupt](#),
[core::autoTriggerSource::timer0Compare](#),
[core::autoTriggerSource::timer0Overflow](#), [core::autoTriggerSource::timer1CompareB](#), [core::autoTriggerSource::timer1Overflow](#),
[core::autoTriggerSource::timer1Capture](#) }

7.3.1 Detailed Description

Header file of the ADC class.

Basic class for abstraction of the Analog to Digital Converter.

Usage example: `#include "ADC.h" #include "USART0.h"`

```
#define TRANSMIT_BUFFER_SIZE 7
```

```
int main(void) {
```

```
Init
```

instantiate the USART0 object `io::USART0` &myUSART0 = `io::USART0::getInstance()`; transmit data buffer char `l_data2Send[TRANSMIT_BUFFER_SIZE]`;

instantiate the ADC object `core::ADConverter` &myADC = `core::ADConverter::getInstance()`;

select analog input `myADC.selectAnalogInput(io::Pin(0,io::PortC))`;

variable to hold conversion result `uint16_t l_conversionResult = 0`;

enable and start conversion `myADC.start()`;

```
----- Event loop ----- // while (1) {
```

```
    myADC.getConversionResult(&l_conversionResult, core::resolution::RES_16bit);

    if (myADC.conversionComplete())
    {
        l_data2Send[0] = '0' + (l_conversionResult / 10000);
        l_data2Send[1] = '0' + ((l_conversionResult / 1000) % 10);
        l_data2Send[2] = '0' + ((l_conversionResult / 100) % 10);
        l_data2Send[3] = '0' + ((l_conversionResult / 10) % 10);
        l_data2Send[4] = '0' + (l_conversionResult % 10);
        l_data2Send[5] = '\n';
        l_data2Send[6] = '\r';

        if (myUSART0.ready2Send())
        {
            myUSART0.sendFrame(reinterpret_cast<uint8_t*>(l_data2Send), TRANSMIT_BUFFER_SIZE);
        }
    }
}
return 0;
}
```

```
uint16_t value = 12345; char lo = value & 0xFF; char hi = value >> 8;
```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [ADC.h](#).

7.4 ADC.h

```

00001
00078 #ifndef ADC_H
00079 #define ADC_H
00080 #include "ha_base.h"
00081 #include "Pin.h"
00082
00083
00084 namespace core
00085 {
00086
00087 enum class resolution : uint8_t {
00088     res_8bit=0,
00089     res_9bit,
00090     res_10bit,
00091     res_11bit,
00092     res_12bit,
00093     res_13bit,
00094     res_14bit,
00095     res_15bit,
00096     res_16bit
00097 };
00098
00099
00100 enum class referenceVoltage : uint8_t {
00101     AREF=0,
00102     AVCC,
00103     internal
00104 };
00105
00106
00107
00108 enum class clockPrescaler : uint8_t {
00109     PS_2 = 1,
00110     PS_4,
00111     PS_8,
00112     PS_16,
00113     PS_32,
00114     PS_64,
00115     PS_128
00116 };
00117
00118 enum class autoTriggerSource : uint8_t {
00119     freeRunning,
00120     analogComparator,
00121     extInterrupt,
00122     timer0Compare,
00123     timer0Overflow,
00124     timer1CompareB,
00125     timer1Overflow,
00126     timer1Capture
00127 };
00128
00129 class ADConverter
00130 {
00131 public:
00132
00133     static ADConverter& getInstance(const referenceVoltage& ar_refVoltage = referenceVoltage::AVCC,
00134                                     const clockPrescaler& ar_clockPrescaler = clockPrescaler::PS_128,
00135                                     const autoTriggerSource& ar_autoTriggerSource =
00136                                         autoTriggerSource::freeRunning,
00137                                     const io::Pin &ar_pin = io::Pin(0,io::PortC));
00138
00139     void start();
00140
00141     void stop();
00142
00143     void selectReferenceVoltage(const referenceVoltage& ar_refVoltage);
00144
00145     void selectAnalogInput(io::Pin a_pin);
00146
00147     void selectClockPrescaler(const clockPrescaler& ar_clockPrescaler);
00148
00149     void enableConversionCompleteInterrupt(const uint8_t a_enable);
00150
00151     void enableAutoTrigger(const uint8_t a_enable);
00152
00153     void selectAutoTriggerSource(const autoTriggerSource& ar_autoTriggerSource);
00154
00155     uint8_t conversionComplete();
00156
00157     void getConversionResult(uint16_t *ap_resultData, const resolution& ar_resolution =
00158         resolution::res_10bit);
00159

```

```

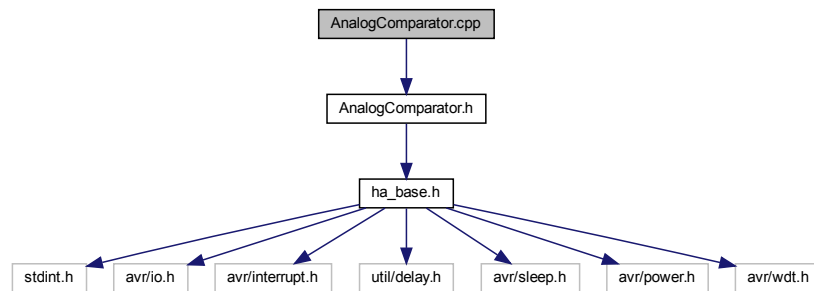
00160     static void conversionCompleteServiceRoutine() __asm__(STR(ADC_CONVERSION_COMPLETE_INTERRUPT))
    __attribute__((__signal__, __used__, __externally_visible__));
00161
00162
00163 protected:
00164
00165
00166
00167 private:
00168
00169     ADConverter(const referenceVoltage& ar_refVoltage,
00170                const clockPrescaler& ar_clockPrescaler,
00171                const autoTriggerSource &ar_autoTriggerSource,
00172                const io::Pin &ar_pin);
00173
00174     ~ADConverter();
00175
00176     ADConverter(const ADConverter&);
00177
00178     const ADConverter& operator=(const ADConverter&);
00179
00180
00181     static volatile uint16_t *mp_conversionResult;
00182     static uint8_t m_resolution;
00183     static volatile uint8_t m_conversionComplete;
00184 };
00185
00186 #endif

```

7.5 AnalogComparator.cpp File Reference

```
#include "AnalogComparator.h"
```

Include dependency graph for AnalogComparator.cpp:



7.6 AnalogComparator.cpp

```

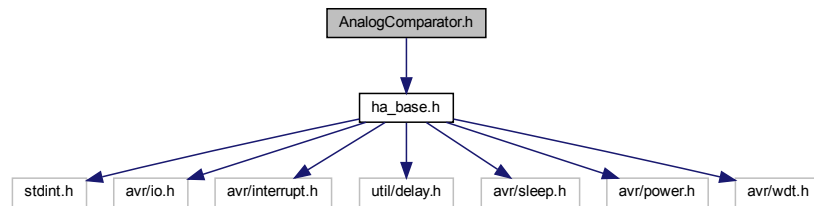
00001 #include "AnalogComparator.h"
00002
00003

```

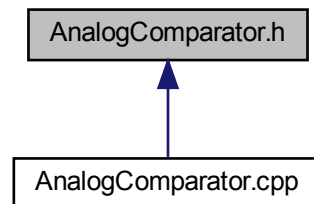
7.7 AnalogComparator.h File Reference

```
#include "ha_base.h"
```

Include dependency graph for AnalogComparator.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::AnalogComparator](#)

Namespaces

- [core](#)

Macros

- #define [ANALOG_COMARATOR_H](#)

7.7.1 Macro Definition Documentation

7.7.1.1 ANALOG_COMARATOR_H

```
#define ANALOG_COMARATOR_H
```

Definition at line 13 of file [AnalogComparator.h](#).

7.8 AnalogComparator.h

```

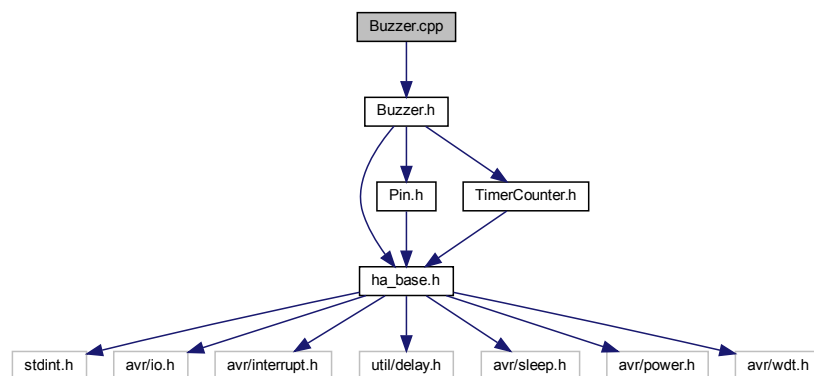
00001
00012 #ifndef ANALOG_COMPARATOR_H
00013 #define ANALOG_COMARATOR_H
00014 #include "ha_base.h"
00015
00016
00017
00018 namespace core
00019 {
00020
00021
00022
00023
00024 class AnalogComparator
00025 {
00026
00027 public:
00028
00029
00030
00031
00032 protected:
00033
00034 private:
00035
00036
00037
00038 };
00039
00040 }
00041
00042
00043 #endif

```

7.9 Buzzer.cpp File Reference

```
#include "Buzzer.h"
```

Include dependency graph for Buzzer.cpp:



7.10 Buzzer.cpp

```

00001 #include "Buzzer.h"
00002
00003
00004 component::Buzzer::Buzzer(const io::Pin &ar_pin)
00005     : m_pin(ar_pin)
00006 {
00007     m_pin.toOutput();

```

```

00008
00009 }
00010
00011 component::Buzzer::~Buzzer()
00012 {
00013
00014 }
00015
00016
00017
00018 void component::Buzzer::buzz(const uint16_t &ar_period_us , const uint16_t &ar_duration_ms)
00019 {
00020     uint32_t l_duration_us = ar_duration_ms*1000UL;
00021
00022     for (uint32_t i = 0; i < l_duration_us; i += ar_period_us)
00023     {
00024         /* For loop with variable delay selects the pitch */
00025         // _delay_us() needs a constant defined at compile time
00026         for (uint16_t j = 0; j < ar_period_us; j++)
00027         {
00028             _delay_us(1);
00029         }
00030         m_pin.toggle();
00031     }
00032     m_pin.setLow();
00033 }
00034 }
00035
00036

```

7.11 Buzzer.h File Reference

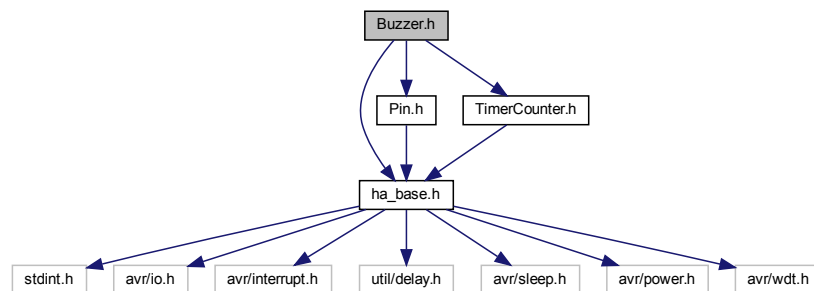
Header file of the Buzzer class.

```

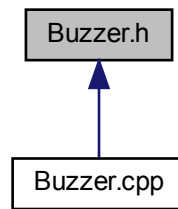
#include "ha_base.h"
#include "Pin.h"
#include "TimerCounter.h"

```

Include dependency graph for Buzzer.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [component::Buzzer](#)

Namespaces

- [component](#)

7.11.1 Detailed Description

Header file of the Buzzer class.

Usage example (test): `#include "Buzzer.h" #include "TimerCounter0.h" #include "buzzer_pitches_8bit.h"`

```
#define BUZZER 6
```

```
int main(void) {
```

```
    Init instantiate the Buzzer object component::Buzzer Buzzer(io::Pin(BUZZER,io::PortD));
```

```
    instantiate the TimerCounter0 object core::TimerCounter0 &myTimerCounter0 = core::TimerCounter0::getInstance();
```

```
    notes in the melody: const uint16_t notes[] = {C2, E2, G2, C3};
```

```
    for (uint8_t i = 0; i < sizeof (notes)/sizeof (uint16_t); i++)
    {
```

```
        Buzzer.buzz(notes[i],200);
```

```
    }
```

```
    _delay_ms(1000);
    _delay_ms(1000);
    _delay_ms(1000);
```

```
    for (uint8_t i = 0; i < sizeof (notes)/sizeof (uint16_t); i++)
    {
```

```
        Buzzer.buzz(myTimerCounter0,notes[i],200);
```

```
    }
```

```

----- Event loop ----- // while (1) {

}
return 0;

}

```

Basic class for IO abstraction of Pin and Port

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [Buzzer.h](#).

7.12 Buzzer.h

```

00001
00058 #ifndef BUZZER_H
00059 #define BUZZER_H
00060 #include "ha_base.h"
00061 #include "Pin.h"
00062 #include "TimerCounter.h"
00063
00064 namespace component
00065 {
00066
00067
00068
00069 class Buzzer
00070 {
00071
00072 public:
00073
00074     Buzzer(const io::Pin &ar_pin);
00075
00076     ~Buzzer();
00077
00078     void buzz(const uint16_t &ar_period_us , const uint16_t &ar_duration_ms);
00079
00080     template<typename TC>
00081     void buzz(TC &ar_timerCounter,
00082               const uint16_t &ar_period_us,
00083               uint16_t &ar_duration_ms,
00084               const core::channel &ar_channel=core::channel::A,
00085               const core::clockSource &ar_clockSource= core::clockSource::PS_64
00086               )
00087     {
00088         ar_timerCounter.selectOperationMode(core::operationMode::CTC_OCR);
00089         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::toggle);
00090         ar_timerCounter.setCounter(0);
00091         ar_timerCounter.setOutputCompareRegister(ar_channel, ar_period_us);
00092         // start timer
00093         ar_timerCounter.start();
00094         // wait for the pitch duration
00095         while (ar_duration_ms) {
00096             _delay_ms(1);
00097             ar_duration_ms--;
00098         }
00099         // no buzz
00100         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::normal);
00101         ar_timerCounter.stop();
00102     }
00103
00104
00105 protected:
00106
00107 private:
00108
00109     io::Pin m_pin;
00110 };
00111
00112 };
00113
00114
00115
00116 #endif

```

7.13 buzzer_pitches_16bit.h File Reference

Macros

- #define [C0](#) 25000
- #define [Cx0](#) 23597
- #define [D0](#) 22272
- #define [Dx0](#) 21022
- #define [E0](#) 19843
- #define [F0](#) 18729
- #define [Fx0](#) 17678
- #define [G0](#) 16685
- #define [Gx0](#) 15749
- #define [A0](#) 14865
- #define [Ax0](#) 14031
- #define [B0](#) 13243
- #define [C1](#) 12500
- #define [Cx1](#) 11798
- #define [D1](#) 11136
- #define [Dx1](#) 10511
- #define [E1](#) 9921
- #define [F1](#) 9364
- #define [Fx1](#) 8839
- #define [G1](#) 8343
- #define [Gx1](#) 7875
- #define [A1](#) 7433
- #define [Ax1](#) 7015
- #define [B1](#) 6622
- #define [C2](#) 6250
- #define [Cx2](#) 5899
- #define [D2](#) 5568
- #define [Dx2](#) 5256
- #define [E2](#) 4961
- #define [F2](#) 4682
- #define [Fx2](#) 4419
- #define [G2](#) 4171
- #define [Gx2](#) 3937
- #define [A2](#) 3716
- #define [Ax2](#) 3508
- #define [B2](#) 3311
- #define [C3](#) 3125
- #define [Cx3](#) 2950
- #define [D3](#) 2784
- #define [Dx3](#) 2628
- #define [E3](#) 2480
- #define [F3](#) 2341
- #define [Fx3](#) 2210
- #define [G3](#) 2086
- #define [Gx3](#) 1969
- #define [A3](#) 1858
- #define [Ax3](#) 1754
- #define [B3](#) 1655
- #define [C4](#) 1562
- #define [Cx4](#) 1474

- `#define D4` 1392
- `#define Dx4` 1313
- `#define E4` 1240
- `#define F4` 1170
- `#define Fx4` 1105
- `#define G4` 1043
- `#define Gx4` 984
- `#define A4` 929
- `#define Ax4` 877
- `#define B4` 827
- `#define C5` 781
- `#define Cx5` 737
- `#define D5` 696
- `#define Dx5` 657
- `#define E5` 620
- `#define F5` 585
- `#define Fx5` 552
- `#define G5` 521
- `#define Gx5` 492
- `#define A5` 464
- `#define Ax5` 438
- `#define B5` 414
- `#define C6` 390
- `#define Cx6` 368
- `#define D6` 347
- `#define Dx6` 328
- `#define E6` 310
- `#define F6` 292
- `#define Fx6` 276
- `#define G6` 260
- `#define Gx6` 246
- `#define A6` 232
- `#define Ax6` 219
- `#define B6` 207
- `#define C7` 195
- `#define Cx7` 184
- `#define D7` 174
- `#define Dx7` 164
- `#define E7` 155
- `#define F7` 146
- `#define Fx7` 138
- `#define G7` 130
- `#define Gx7` 123
- `#define A7` 116
- `#define Ax7` 109
- `#define B7` 103

7.13.1 Macro Definition Documentation

7.13.1.1 A0

```
#define A0 14865
```

Definition at line 21 of file [buzzer_pitches_16bit.h](#).

7.13.1.2 A1

```
#define A1 7433
```

Definition at line 33 of file [buzzer_pitches_16bit.h](#).

7.13.1.3 A2

```
#define A2 3716
```

Definition at line 45 of file [buzzer_pitches_16bit.h](#).

7.13.1.4 A3

```
#define A3 1858
```

Definition at line 57 of file [buzzer_pitches_16bit.h](#).

7.13.1.5 A4

```
#define A4 929
```

Definition at line 69 of file [buzzer_pitches_16bit.h](#).

7.13.1.6 A5

```
#define A5 464
```

Definition at line 81 of file [buzzer_pitches_16bit.h](#).

7.13.1.7 A6

```
#define A6 232
```

Definition at line 93 of file [buzzer_pitches_16bit.h](#).

7.13.1.8 A7

```
#define A7 116
```

Definition at line 105 of file [buzzer_pitches_16bit.h](#).

7.13.1.9 Ax0

```
#define Ax0 14031
```

Definition at line 22 of file [buzzer_pitches_16bit.h](#).

7.13.1.10 Ax1

```
#define Ax1 7015
```

Definition at line 34 of file [buzzer_pitches_16bit.h](#).

7.13.1.11 Ax2

```
#define Ax2 3508
```

Definition at line 46 of file [buzzer_pitches_16bit.h](#).

7.13.1.12 Ax3

```
#define Ax3 1754
```

Definition at line 58 of file [buzzer_pitches_16bit.h](#).

7.13.1.13 Ax4

```
#define Ax4 877
```

Definition at line 70 of file [buzzer_pitches_16bit.h](#).

7.13.1.14 Ax5

```
#define Ax5 438
```

Definition at line 82 of file [buzzer_pitches_16bit.h](#).

7.13.1.15 Ax6

```
#define Ax6 219
```

Definition at line 94 of file [buzzer_pitches_16bit.h](#).

7.13.1.16 Ax7

```
#define Ax7 109
```

Definition at line 106 of file [buzzer_pitches_16bit.h](#).

7.13.1.17 B0

```
#define B0 13243
```

Definition at line 23 of file [buzzer_pitches_16bit.h](#).

7.13.1.18 B1

```
#define B1 6622
```

Definition at line 35 of file [buzzer_pitches_16bit.h](#).

7.13.1.19 B2

```
#define B2 3311
```

Definition at line 47 of file [buzzer_pitches_16bit.h](#).

7.13.1.20 B3

```
#define B3 1655
```

Definition at line 59 of file [buzzer_pitches_16bit.h](#).

7.13.1.21 B4

```
#define B4 827
```

Definition at line 71 of file [buzzer_pitches_16bit.h](#).

7.13.1.22 B5

```
#define B5 414
```

Definition at line 83 of file [buzzer_pitches_16bit.h](#).

7.13.1.23 B6

```
#define B6 207
```

Definition at line 95 of file [buzzer_pitches_16bit.h](#).

7.13.1.24 B7

```
#define B7 103
```

Definition at line 107 of file [buzzer_pitches_16bit.h](#).

7.13.1.25 C0

```
#define C0 25000
```

Definition at line 12 of file [buzzer_pitches_16bit.h](#).

7.13.1.26 C1

```
#define C1 12500
```

Definition at line 24 of file [buzzer_pitches_16bit.h](#).

7.13.1.27 C2

```
#define C2 6250
```

Definition at line 36 of file [buzzer_pitches_16bit.h](#).

7.13.1.28 C3

```
#define C3 3125
```

Definition at line 48 of file [buzzer_pitches_16bit.h](#).

7.13.1.29 C4

```
#define C4 1562
```

Definition at line 60 of file [buzzer_pitches_16bit.h](#).

7.13.1.30 C5

```
#define C5 781
```

Definition at line 72 of file [buzzer_pitches_16bit.h](#).

7.13.1.31 C6

```
#define C6 390
```

Definition at line 84 of file [buzzer_pitches_16bit.h](#).

7.13.1.32 C7

```
#define C7 195
```

Definition at line 96 of file [buzzer_pitches_16bit.h](#).

7.13.1.33 Cx0

```
#define Cx0 23597
```

Definition at line 13 of file [buzzer_pitches_16bit.h](#).

7.13.1.34 Cx1

```
#define Cx1 11798
```

Definition at line 25 of file [buzzer_pitches_16bit.h](#).

7.13.1.35 Cx2

```
#define Cx2 5899
```

Definition at line 37 of file [buzzer_pitches_16bit.h](#).

7.13.1.36 Cx3

```
#define Cx3 2950
```

Definition at line 49 of file [buzzer_pitches_16bit.h](#).

7.13.1.37 Cx4

```
#define Cx4 1474
```

Definition at line 61 of file [buzzer_pitches_16bit.h](#).

7.13.1.38 Cx5

```
#define Cx5 737
```

Definition at line 73 of file [buzzer_pitches_16bit.h](#).

7.13.1.39 Cx6

```
#define Cx6 368
```

Definition at line 85 of file [buzzer_pitches_16bit.h](#).

7.13.1.40 Cx7

```
#define Cx7 184
```

Definition at line 97 of file [buzzer_pitches_16bit.h](#).

7.13.1.41 D0

```
#define D0 22272
```

Definition at line 14 of file [buzzer_pitches_16bit.h](#).

7.13.1.42 D1

```
#define D1 11136
```

Definition at line 26 of file [buzzer_pitches_16bit.h](#).

7.13.1.43 D2

```
#define D2 5568
```

Definition at line 38 of file [buzzer_pitches_16bit.h](#).

7.13.1.44 D3

```
#define D3 2784
```

Definition at line 50 of file [buzzer_pitches_16bit.h](#).

7.13.1.45 D4

```
#define D4 1392
```

Definition at line 62 of file [buzzer_pitches_16bit.h](#).

7.13.1.46 D5

```
#define D5 696
```

Definition at line 74 of file [buzzer_pitches_16bit.h](#).

7.13.1.47 D6

```
#define D6 347
```

Definition at line 86 of file [buzzer_pitches_16bit.h](#).

7.13.1.48 D7

```
#define D7 174
```

Definition at line 98 of file [buzzer_pitches_16bit.h](#).

7.13.1.49 Dx0

```
#define Dx0 21022
```

Definition at line 15 of file [buzzer_pitches_16bit.h](#).

7.13.1.50 Dx1

```
#define Dx1 10511
```

Definition at line 27 of file [buzzer_pitches_16bit.h](#).

7.13.1.51 Dx2

```
#define Dx2 5256
```

Definition at line 39 of file [buzzer_pitches_16bit.h](#).

7.13.1.52 Dx3

```
#define Dx3 2628
```

Definition at line 51 of file [buzzer_pitches_16bit.h](#).

7.13.1.53 Dx4

```
#define Dx4 1313
```

Definition at line 63 of file [buzzer_pitches_16bit.h](#).

7.13.1.54 Dx5

```
#define Dx5 657
```

Definition at line 75 of file [buzzer_pitches_16bit.h](#).

7.13.1.55 Dx6

```
#define Dx6 328
```

Definition at line 87 of file [buzzer_pitches_16bit.h](#).

7.13.1.56 Dx7

```
#define Dx7 164
```

Definition at line 99 of file [buzzer_pitches_16bit.h](#).

7.13.1.57 E0

```
#define E0 19843
```

Definition at line 16 of file [buzzer_pitches_16bit.h](#).

7.13.1.58 E1

```
#define E1 9921
```

Definition at line 28 of file [buzzer_pitches_16bit.h](#).

7.13.1.59 E2

```
#define E2 4961
```

Definition at line 40 of file [buzzer_pitches_16bit.h](#).

7.13.1.60 E3

```
#define E3 2480
```

Definition at line 52 of file [buzzer_pitches_16bit.h](#).

7.13.1.61 E4

```
#define E4 1240
```

Definition at line 64 of file [buzzer_pitches_16bit.h](#).

7.13.1.62 E5

```
#define E5 620
```

Definition at line 76 of file [buzzer_pitches_16bit.h](#).

7.13.1.63 E6

```
#define E6 310
```

Definition at line 88 of file [buzzer_pitches_16bit.h](#).

7.13.1.64 E7

```
#define E7 155
```

Definition at line 100 of file [buzzer_pitches_16bit.h](#).

7.13.1.65 F0

```
#define F0 18729
```

Definition at line 17 of file [buzzer_pitches_16bit.h](#).

7.13.1.66 F1

```
#define F1 9364
```

Definition at line 29 of file [buzzer_pitches_16bit.h](#).

7.13.1.67 F2

```
#define F2 4682
```

Definition at line 41 of file [buzzer_pitches_16bit.h](#).

7.13.1.68 F3

```
#define F3 2341
```

Definition at line 53 of file [buzzer_pitches_16bit.h](#).

7.13.1.69 F4

```
#define F4 1170
```

Definition at line 65 of file [buzzer_pitches_16bit.h](#).

7.13.1.70 F5

```
#define F5 585
```

Definition at line 77 of file [buzzer_pitches_16bit.h](#).

7.13.1.71 F6

```
#define F6 292
```

Definition at line 89 of file [buzzer_pitches_16bit.h](#).

7.13.1.72 F7

```
#define F7 146
```

Definition at line 101 of file [buzzer_pitches_16bit.h](#).

7.13.1.73 Fx0

```
#define Fx0 17678
```

Definition at line 18 of file [buzzer_pitches_16bit.h](#).

7.13.1.74 Fx1

```
#define Fx1 8839
```

Definition at line 30 of file [buzzer_pitches_16bit.h](#).

7.13.1.75 Fx2

```
#define Fx2 4419
```

Definition at line 42 of file [buzzer_pitches_16bit.h](#).

7.13.1.76 Fx3

```
#define Fx3 2210
```

Definition at line 54 of file [buzzer_pitches_16bit.h](#).

7.13.1.77 Fx4

```
#define Fx4 1105
```

Definition at line 66 of file [buzzer_pitches_16bit.h](#).

7.13.1.78 Fx5

```
#define Fx5 552
```

Definition at line 78 of file [buzzer_pitches_16bit.h](#).

7.13.1.79 Fx6

```
#define Fx6 276
```

Definition at line 90 of file [buzzer_pitches_16bit.h](#).

7.13.1.80 Fx7

```
#define Fx7 138
```

Definition at line 102 of file [buzzer_pitches_16bit.h](#).

7.13.1.81 G0

```
#define G0 16685
```

Definition at line 19 of file [buzzer_pitches_16bit.h](#).

7.13.1.82 G1

```
#define G1 8343
```

Definition at line 31 of file [buzzer_pitches_16bit.h](#).

7.13.1.83 G2

```
#define G2 4171
```

Definition at line 43 of file [buzzer_pitches_16bit.h](#).

7.13.1.84 G3

```
#define G3 2086
```

Definition at line 55 of file [buzzer_pitches_16bit.h](#).

7.13.1.85 G4

```
#define G4 1043
```

Definition at line 67 of file [buzzer_pitches_16bit.h](#).

7.13.1.86 G5

```
#define G5 521
```

Definition at line 79 of file [buzzer_pitches_16bit.h](#).

7.13.1.87 G6

```
#define G6 260
```

Definition at line 91 of file [buzzer_pitches_16bit.h](#).

7.13.1.88 G7

```
#define G7 130
```

Definition at line 103 of file [buzzer_pitches_16bit.h](#).

7.13.1.89 Gx0

```
#define Gx0 15749
```

Definition at line 20 of file [buzzer_pitches_16bit.h](#).

7.13.1.90 Gx1

```
#define Gx1 7875
```

Definition at line 32 of file [buzzer_pitches_16bit.h](#).

7.13.1.91 Gx2

```
#define Gx2 3937
```

Definition at line 44 of file [buzzer_pitches_16bit.h](#).

7.13.1.92 Gx3

```
#define Gx3 1969
```

Definition at line 56 of file [buzzer_pitches_16bit.h](#).

7.13.1.93 Gx4

```
#define Gx4 984
```

Definition at line 68 of file [buzzer_pitches_16bit.h](#).

7.13.1.94 Gx5

```
#define Gx5 492
```

Definition at line 80 of file [buzzer_pitches_16bit.h](#).

7.13.1.95 Gx6

```
#define Gx6 246
```

Definition at line 92 of file [buzzer_pitches_16bit.h](#).

7.13.1.96 Gx7

```
#define Gx7 123
```

Definition at line 104 of file [buzzer_pitches_16bit.h](#).

7.14 buzzer_pitches_16bit.h

```
00001 /* Scale in the key of 1/25000 */
00002 /*
00003     These are 1/2 periods (us) -- if you delay this long,
00004     then toggle the speaker pin, you'll get approximate
00005     pitches.
00006
00007     This is the 16-bit version. The pitches get less accurate
00008     as they get higher.
00009 */
00010 */
00011
00012 #define C0      25000 // freq = 1000000/ (2*25000) = 20hz
00013 #define Cx0     23597
00014 #define D0      22272
00015 #define Dx0     21022
00016 #define E0      19843
00017 #define F0      18729
00018 #define Fx0     17678
00019 #define G0      16685
00020 #define Gx0     15749
00021 #define A0      14865
00022 #define Ax0     14031
00023 #define B0      13243
00024 #define C1      12500
00025 #define Cx1     11798
00026 #define D1      11136
00027 #define Dx1     10511
00028 #define E1       9921
00029 #define F1       9364
00030 #define Fx1     8839
00031 #define G1       8343
00032 #define Gx1     7875
00033 #define A1       7433
00034 #define Ax1     7015
00035 #define B1       6622
00036 #define C2       6250
00037 #define Cx2     5899
00038 #define D2       5568
00039 #define Dx2     5256
00040 #define E2       4961
00041 #define F2       4682
00042 #define Fx2     4419
00043 #define G2       4171
00044 #define Gx2     3937
00045 #define A2       3716
00046 #define Ax2     3508
00047 #define B2       3311
00048 #define C3       3125
00049 #define Cx3     2950
00050 #define D3       2784
00051 #define Dx3     2628
00052 #define E3       2480
00053 #define F3       2341
00054 #define Fx3     2210
00055 #define G3       2086
00056 #define Gx3     1969
00057 #define A3       1858
00058 #define Ax3     1754
00059 #define B3       1655
00060 #define C4       1562
00061 #define Cx4     1474
00062 #define D4       1392
00063 #define Dx4     1313
00064 #define E4       1240
00065 #define F4       1170
00066 #define Fx4     1105
00067 #define G4       1043
00068 #define Gx4     984
00069 #define A4       929
00070 #define Ax4     877
00071 #define B4       827
00072 #define C5       781
00073 #define Cx5     737
00074 #define D5       696
00075 #define Dx5     657
00076 #define E5       620
00077 #define F5       585
00078 #define Fx5     552
00079 #define G5       521
00080 #define Gx5     492
00081 #define A5       464
00082 #define Ax5     438
00083 #define B5       414
00084 #define C6       390
00085 #define Cx6     368
```

```
00086 #define D6      347
00087 #define Dx6      328
00088 #define E6       310
00089 #define F6       292
00090 #define Fx6      276
00091 #define G6       260
00092 #define Gx6      246
00093 #define A6       232
00094 #define Ax6      219
00095 #define B6       207
00096 #define C7       195
00097 #define Cx7      184
00098 #define D7       174
00099 #define Dx7      164
00100 #define E7       155
00101 #define F7       146
00102 #define Fx7      138
00103 #define G7       130
00104 #define Gx7      123
00105 #define A7       116
00106 #define Ax7      109
00107 #define B7       103 // freq = 1000000/ (2*103) = 4.85 khz
```

7.15 buzzer_pitches_8bit.h File Reference

Macros

- #define Gx0 252
- #define A0 238
- #define Ax0 224
- #define B0 212
- #define C1 200
- #define Cx0 189
- #define D1 178
- #define Dx0 168
- #define E1 159
- #define F1 150
- #define Fx1 141
- #define G1 133
- #define Gx1 126
- #define A1 119
- #define Ax1 112
- #define B1 106
- #define C2 100
- #define Cx2 94
- #define D2 89
- #define Dx2 84
- #define E2 79
- #define F2 75
- #define Fx2 71
- #define G2 67
- #define Gx2 63
- #define A2 59
- #define Ax2 56
- #define B2 53
- #define C3 50
- #define Cx3 47
- #define D3 44
- #define Dx3 42
- #define E3 40
- #define F3 37
- #define Fx3 35
- #define G3 33

7.15.1 Macro Definition Documentation

7.15.1.1 A0

```
#define A0 238
```

Definition at line 14 of file [buzzer_pitches_8bit.h](#).

7.15.1.2 A1

```
#define A1 119
```

Definition at line 26 of file [buzzer_pitches_8bit.h](#).

7.15.1.3 A2

```
#define A2 59
```

Definition at line 38 of file [buzzer_pitches_8bit.h](#).

7.15.1.4 Ax0

```
#define Ax0 224
```

Definition at line 15 of file [buzzer_pitches_8bit.h](#).

7.15.1.5 Ax1

```
#define Ax1 112
```

Definition at line 27 of file [buzzer_pitches_8bit.h](#).

7.15.1.6 Ax2

```
#define Ax2 56
```

Definition at line 39 of file [buzzer_pitches_8bit.h](#).

7.15.1.7 B0

```
#define B0 212
```

Definition at line 16 of file [buzzer_pitches_8bit.h](#).

7.15.1.8 B1

```
#define B1 106
```

Definition at line 28 of file [buzzer_pitches_8bit.h](#).

7.15.1.9 B2

```
#define B2 53
```

Definition at line 40 of file [buzzer_pitches_8bit.h](#).

7.15.1.10 C1

```
#define C1 200
```

Definition at line 17 of file [buzzer_pitches_8bit.h](#).

7.15.1.11 C2

```
#define C2 100
```

Definition at line 29 of file [buzzer_pitches_8bit.h](#).

7.15.1.12 C3

```
#define C3 50
```

Definition at line 41 of file [buzzer_pitches_8bit.h](#).

7.15.1.13 Cx0

```
#define Cx0 189
```

Definition at line 18 of file [buzzer_pitches_8bit.h](#).

7.15.1.14 Cx2

```
#define Cx2 94
```

Definition at line 30 of file [buzzer_pitches_8bit.h](#).

7.15.1.15 Cx3

```
#define Cx3 47
```

Definition at line 42 of file [buzzer_pitches_8bit.h](#).

7.15.1.16 D1

```
#define D1 178
```

Definition at line 19 of file [buzzer_pitches_8bit.h](#).

7.15.1.17 D2

```
#define D2 89
```

Definition at line 31 of file [buzzer_pitches_8bit.h](#).

7.15.1.18 D3

```
#define D3 44
```

Definition at line 43 of file [buzzer_pitches_8bit.h](#).

7.15.1.19 Dx0

```
#define Dx0 168
```

Definition at line 20 of file [buzzer_pitches_8bit.h](#).

7.15.1.20 Dx2

```
#define Dx2 84
```

Definition at line 32 of file [buzzer_pitches_8bit.h](#).

7.15.1.21 Dx3

```
#define Dx3 42
```

Definition at line 44 of file [buzzer_pitches_8bit.h](#).

7.15.1.22 E1

```
#define E1 159
```

Definition at line 21 of file [buzzer_pitches_8bit.h](#).

7.15.1.23 E2

```
#define E2 79
```

Definition at line 33 of file [buzzer_pitches_8bit.h](#).

7.15.1.24 E3

```
#define E3 40
```

Definition at line 45 of file [buzzer_pitches_8bit.h](#).

7.15.1.25 F1

```
#define F1 150
```

Definition at line 22 of file [buzzer_pitches_8bit.h](#).

7.15.1.26 F2

```
#define F2 75
```

Definition at line 34 of file [buzzer_pitches_8bit.h](#).

7.15.1.27 F3

```
#define F3 37
```

Definition at line 46 of file [buzzer_pitches_8bit.h](#).

7.15.1.28 Fx1

```
#define Fx1 141
```

Definition at line 23 of file [buzzer_pitches_8bit.h](#).

7.15.1.29 Fx2

```
#define Fx2 71
```

Definition at line 35 of file [buzzer_pitches_8bit.h](#).

7.15.1.30 Fx3

```
#define Fx3 35
```

Definition at line 47 of file [buzzer_pitches_8bit.h](#).

7.15.1.31 G1

```
#define G1 133
```

Definition at line 24 of file [buzzer_pitches_8bit.h](#).

7.15.1.32 G2

```
#define G2 67
```

Definition at line 36 of file [buzzer_pitches_8bit.h](#).

7.15.1.33 G3

```
#define G3 33
```

Definition at line 48 of file [buzzer_pitches_8bit.h](#).

7.15.1.34 Gx0

```
#define Gx0 252
```

Definition at line 13 of file [buzzer_pitches_8bit.h](#).

7.15.1.35 Gx1

```
#define Gx1 126
```

Definition at line 25 of file [buzzer_pitches_8bit.h](#).

7.15.1.36 Gx2

```
#define Gx2 63
```

Definition at line 37 of file [buzzer_pitches_8bit.h](#).

7.16 buzzer_pitches_8bit.h

```
00001 /* Scale in the key of 1/200 */
00002
00003 /*
00004     These are 1/2 periods (us) -- if you delay this long,
00005     then toggle the speaker pin, you'll get approximate
00006     pitches.
00007
00008     This is the 8-bit version. The pitches get less accurate
00009     as they get higher.
00010
00011 */
00012
00013 #define Gx0 252 // freq = 1000000/ (2*252) = 1.98 khz
00014 #define A0 238
00015 #define Ax0 224
00016 #define B0 212
00017 #define C1 200
00018 #define Cx0 189
00019 #define D1 178
00020 #define Dx0 168
00021 #define E1 159
00022 #define F1 150
00023 #define Fx1 141
00024 #define G1 133
00025 #define Gx1 126
00026 #define A1 119
00027 #define Ax1 112
00028 #define B1 106
00029 #define C2 100
00030 #define Cx2 94
00031 #define D2 89
00032 #define Dx2 84
00033 #define E2 79
00034 #define F2 75
00035 #define Fx2 71
00036 #define G2 67
00037 #define Gx2 63
00038 #define A2 59
00039 #define Ax2 56
00040 #define B2 53
00041 #define C3 50
00042 #define Cx3 47
00043 #define D3 44
00044 #define Dx3 42
00045 #define E3 40
00046 #define F3 37
00047 #define Fx3 35
00048 #define G3 33 // freq = 1000000/ (2*33) = 15.15 khz
```

7.17 CMakeCXXCompilerId.cpp File Reference

Macros

- #define [COMPILER_ID](#) ""
- #define [STRINGIFY_HELPER\(X\)](#) #X
- #define [STRINGIFY\(X\)](#) [STRINGIFY_HELPER\(X\)](#)
- #define [PLATFORM_ID](#)
- #define [ARCHITECTURE_ID](#)
- #define [DEC\(n\)](#)
- #define [HEX\(n\)](#)
- #define [CXX_STD](#) __cplusplus

Functions

- int [main](#) (int argc, char *argv[])

Variables

- char const * [info_compiler](#) = "INFO" ":" "compiler[" COMPILER_ID "]"
- char const * [info_platform](#) = "INFO" ":" "platform[" PLATFORM_ID "]"
- char const * [info_arch](#) = "INFO" ":" "arch[" ARCHITECTURE_ID "]"
- const char * [info_language_dialect_default](#)

7.17.1 Macro Definition Documentation

7.17.1.1 ARCHITECTURE_ID

```
#define ARCHITECTURE_ID
```

Definition at line [513](#) of file [CMakeCXXCompilerId.cpp](#).

7.17.1.2 COMPILER_ID

```
#define COMPILER_ID ""
```

Definition at line [308](#) of file [CMakeCXXCompilerId.cpp](#).

7.17.1.3 CXX_STD

```
#define CXX_STD __cplusplus
```

Definition at line [596](#) of file [CMakeCXXCompilerId.cpp](#).

7.17.1.4 DEC

```
#define DEC(  
    n )
```

Value:

```
('0' + ((n) / 10000000) % 10), \
('0' + ((n) / 1000000) % 10), \
('0' + ((n) / 100000) % 10), \
('0' + ((n) / 10000) % 10), \
('0' + ((n) / 1000) % 10), \
('0' + ((n) / 100) % 10), \
('0' + ((n) / 10) % 10), \
('0' + ((n) % 10))
```

Definition at line [517](#) of file [CMakeCXXCompilerId.cpp](#).

7.17.1.5 HEX

```
#define HEX(  
    n )
```

Value:

```
('0' + ((n)>>28 & 0xF)), \  
( '0' + ((n)>>24 & 0xF)), \  
( '0' + ((n)>>20 & 0xF)), \  
( '0' + ((n)>>16 & 0xF)), \  
( '0' + ((n)>>12 & 0xF)), \  
( '0' + ((n)>>8  & 0xF)), \  
( '0' + ((n)>>4  & 0xF)), \  
( '0' + ((n)    & 0xF))
```

Definition at line 528 of file [CMakeCXXCompilerId.cpp](#).

7.17.1.6 PLATFORM_ID

```
#define PLATFORM_ID
```

Definition at line 430 of file [CMakeCXXCompilerId.cpp](#).

7.17.1.7 STRINGIFY

```
#define STRINGIFY(  
    X )  STRINGIFY_HELPER(X)
```

Definition at line 329 of file [CMakeCXXCompilerId.cpp](#).

7.17.1.8 STRINGIFY_HELPER

```
#define STRINGIFY_HELPER(  
    X )  #X
```

Definition at line 328 of file [CMakeCXXCompilerId.cpp](#).

7.17.2 Function Documentation

7.17.2.1 main()

```
int main (
    int argc,
    char * argv[] )
```

Definition at line 615 of file [CMakeCXXCompilerId.cpp](#).

```
00616 {
00617     int require = 0;
00618     require += info\_compiler[argc];
00619     require += info\_platform[argc];
00620     #ifdef COMPILER_VERSION_MAJOR
00621     require += info\_version[argc];
00622 #endif
00623     #ifdef COMPILER_VERSION_INTERNAL
00624     require += info\_version\_internal[argc];
00625 #endif
00626     #ifdef SIMULATE_ID
00627     require += info\_simulate[argc];
00628 #endif
00629     #ifdef SIMULATE_VERSION_MAJOR
00630     require += info\_simulate\_version[argc];
00631 #endif
00632     #if defined(__CRAYXE) || defined(__CRAYXC)
00633     require += info\_cray[argc];
00634 #endif
00635     require += info\_language\_dialect\_default[argc];
00636     (void)argv;
00637     return require;
00638 }
```

References [info_compiler](#), [info_language_dialect_default](#), and [info_platform](#).

7.17.3 Variable Documentation

7.17.3.1 info_arch

```
char const* info_arch = "INFO" ":" "arch[" ARCHITECTURE_ID "]"
```

Definition at line 588 of file [CMakeCXXCompilerId.cpp](#).

7.17.3.2 info_compiler

```
char const* info_compiler = "INFO" ":" "compiler[" COMPILER_ID "]"
```

Definition at line 315 of file [CMakeCXXCompilerId.cpp](#).

Referenced by [main\(\)](#).

7.17.3.3 info_language_dialect_default

```
const char* info_language_dialect_default
```

Initial value:

```
= "INFO" ":" "dialect_default["
  "98"
"]"
```

Definition at line 599 of file [CMakeCXXCompilerId.cpp](#).

Referenced by [main\(\)](#).

7.17.3.4 info_platform

```
char const* info_platform = "INFO" ":" "platform[" PLATFORM_ID "]"
```

Definition at line 587 of file [CMakeCXXCompilerId.cpp](#).

Referenced by [main\(\)](#).

7.18 CMakeCXXCompilerId.cpp

```
00001 /* This source file must have a .cpp extension so that all C++ compilers
00002      recognize the extension without flags. Borland does not know .cxx for
00003      example. */
00004 #ifndef __cplusplus
00005 # error "A C compiler has been selected for C++."
00006 #endif
00007
00008
00009 /* Version number components: V=Version, R=Revision, P=Patch
00010      Version date components: YYYY=Year, MM=Month, DD=Day */
00011
00012 #if defined(__COMO__)
00013 # define COMPILER_ID "Comeau"
00014 /* __COMO_VERSION__ = VRR */
00015 # define COMPILER_VERSION_MAJOR DEC(__COMO_VERSION__ / 100)
00016 # define COMPILER_VERSION_MINOR DEC(__COMO_VERSION__ % 100)
00017
00018 #elif defined(__INTEL_COMPILER) || defined(__ICC)
00019 # define COMPILER_ID "Intel"
00020 # if defined(_MSC_VER)
00021 #   define SIMULATE_ID "MSVC"
00022 # endif
00023 /* __INTEL_COMPILER = VRP */
00024 # define COMPILER_VERSION_MAJOR DEC(__INTEL_COMPILER/100)
00025 # define COMPILER_VERSION_MINOR DEC(__INTEL_COMPILER/10 % 10)
00026 # if defined(__INTEL_COMPILER_UPDATE)
00027 #   define COMPILER_VERSION_PATCH DEC(__INTEL_COMPILER_UPDATE)
00028 # else
00029 #   define COMPILER_VERSION_PATCH DEC(__INTEL_COMPILER % 10)
00030 # endif
00031 # if defined(__INTEL_COMPILER_BUILD_DATE)
00032 /* __INTEL_COMPILER_BUILD_DATE = YYYYMMDD */
00033 #   define COMPILER_VERSION_TWEAK DEC(__INTEL_COMPILER_BUILD_DATE)
00034 # endif
00035 # if defined(_MSC_VER)
00036 /* _MSC_VER = VVRR */
00037 #   define SIMULATE_VERSION_MAJOR DEC(_MSC_VER / 100)
00038 #   define SIMULATE_VERSION_MINOR DEC(_MSC_VER % 100)
00039 # endif
00040
00041 #elif defined(__PATHCC__)
00042 # define COMPILER_ID "PathScale"
00043 # define COMPILER_VERSION_MAJOR DEC(__PATHCC__)
00044 # define COMPILER_VERSION_MINOR DEC(__PATHCC_MINOR__)
00045 # if defined(__PATHCC_PATCHLEVEL__)
00046 #   define COMPILER_VERSION_PATCH DEC(__PATHCC_PATCHLEVEL__)
```

```

00047 # endif
00048
00049 #elif defined(__BORLANDC__) && defined(__CODEGEARC_VERSION__)
00050 # define COMPILER_ID "Embarcadero"
00051 # define COMPILER_VERSION_MAJOR HEX(__CODEGEARC_VERSION__»24 & 0x00FF)
00052 # define COMPILER_VERSION_MINOR HEX(__CODEGEARC_VERSION__»16 & 0x00FF)
00053 # define COMPILER_VERSION_PATCH DEC(__CODEGEARC_VERSION__ & 0xFFFF)
00054
00055 #elif defined(__BORLANDC__)
00056 # define COMPILER_ID "Borland"
00057 /* __BORLANDC__ = 0xVRR */
00058 # define COMPILER_VERSION_MAJOR HEX(__BORLANDC__»8)
00059 # define COMPILER_VERSION_MINOR HEX(__BORLANDC__ & 0xFF)
00060
00061 #elif defined(__WATCOMC__) && __WATCOMC__ < 1200
00062 # define COMPILER_ID "Watcom"
00063 /* __WATCOMC__ = VVRR */
00064 # define COMPILER_VERSION_MAJOR DEC(__WATCOMC__ / 100)
00065 # define COMPILER_VERSION_MINOR DEC((__WATCOMC__ / 10) % 10)
00066 # if (__WATCOMC__ % 10) > 0
00067 # define COMPILER_VERSION_PATCH DEC(__WATCOMC__ % 10)
00068 # endif
00069
00070 #elif defined(__WATCOMC__)
00071 # define COMPILER_ID "OpenWatcom"
00072 /* __WATCOMC__ = VVRP + 1100 */
00073 # define COMPILER_VERSION_MAJOR DEC((__WATCOMC__ - 1100) / 100)
00074 # define COMPILER_VERSION_MINOR DEC((__WATCOMC__ / 10) % 10)
00075 # if (__WATCOMC__ % 10) > 0
00076 # define COMPILER_VERSION_PATCH DEC(__WATCOMC__ % 10)
00077 # endif
00078
00079 #elif defined(__SUNPRO_CC)
00080 # define COMPILER_ID "SunPro"
00081 # if __SUNPRO_CC >= 0x5100
00082 /* __SUNPRO_CC = 0xVRRP */
00083 # define COMPILER_VERSION_MAJOR HEX(__SUNPRO_CC»12)
00084 # define COMPILER_VERSION_MINOR HEX(__SUNPRO_CC»4 & 0xFF)
00085 # define COMPILER_VERSION_PATCH HEX(__SUNPRO_CC & 0xF)
00086 # else
00087 /* __SUNPRO_CC = 0xVRP */
00088 # define COMPILER_VERSION_MAJOR HEX(__SUNPRO_CC»8)
00089 # define COMPILER_VERSION_MINOR HEX(__SUNPRO_CC»4 & 0xF)
00090 # define COMPILER_VERSION_PATCH HEX(__SUNPRO_CC & 0xF)
00091 # endif
00092
00093 #elif defined(__HP_aCC)
00094 # define COMPILER_ID "HP"
00095 /* __HP_aCC = VVRRPP */
00096 # define COMPILER_VERSION_MAJOR DEC(__HP_aCC/10000)
00097 # define COMPILER_VERSION_MINOR DEC(__HP_aCC/100 % 100)
00098 # define COMPILER_VERSION_PATCH DEC(__HP_aCC % 100)
00099
00100 #elif defined(__DECCXX)
00101 # define COMPILER_ID "Compaq"
00102 /* __DECCXX_VER = VVRRTPPPP */
00103 # define COMPILER_VERSION_MAJOR DEC(__DECCXX_VER/10000000)
00104 # define COMPILER_VERSION_MINOR DEC(__DECCXX_VER/100000 % 100)
00105 # define COMPILER_VERSION_PATCH DEC(__DECCXX_VER % 10000)
00106
00107 #elif defined(__IBMCPP__) && defined(__COMPILER_VER__)
00108 # define COMPILER_ID "zOS"
00109 # if defined(__ibmxl__)
00110 # define COMPILER_VERSION_MAJOR DEC(__ibmxl_version__)
00111 # define COMPILER_VERSION_MINOR DEC(__ibmxl_release__)
00112 # define COMPILER_VERSION_PATCH DEC(__ibmxl_modification__)
00113 # define COMPILER_VERSION_TWEAK DEC(__ibmxl_ptf_fix_level__)
00114 # else
00115 /* __IBMCPP__ = VRP */
00116 # define COMPILER_VERSION_MAJOR DEC(__IBMCPP__/100)
00117 # define COMPILER_VERSION_MINOR DEC(__IBMCPP__/10 % 10)
00118 # define COMPILER_VERSION_PATCH DEC(__IBMCPP__ % 10)
00119 # endif
00120
00121
00122 #elif defined(__ibmxl__) || (defined(__IBMCPP__) && !defined(__COMPILER_VER__) && __IBMCPP__ >= 800)
00123 # define COMPILER_ID "XL"
00124 # if defined(__ibmxl__)
00125 # define COMPILER_VERSION_MAJOR DEC(__ibmxl_version__)
00126 # define COMPILER_VERSION_MINOR DEC(__ibmxl_release__)
00127 # define COMPILER_VERSION_PATCH DEC(__ibmxl_modification__)
00128 # define COMPILER_VERSION_TWEAK DEC(__ibmxl_ptf_fix_level__)
00129 # else
00130 /* __IBMCPP__ = VRP */
00131 # define COMPILER_VERSION_MAJOR DEC(__IBMCPP__/100)
00132 # define COMPILER_VERSION_MINOR DEC(__IBMCPP__/10 % 10)
00133 # define COMPILER_VERSION_PATCH DEC(__IBMCPP__ % 10)

```

```

00134 # endif
00135
00136
00137 #elif defined(__IBMCPP__) && !defined(__COMPILER_VER__) && __IBMCPP__ < 800
00138 # define COMPILER_ID "VisualAge"
00139 # if defined(__ibmxl__)
00140 #   define COMPILER_VERSION_MAJOR DEC(__ibmxl_version__)
00141 #   define COMPILER_VERSION_MINOR DEC(__ibmxl_release__)
00142 #   define COMPILER_VERSION_PATCH DEC(__ibmxl_modification__)
00143 #   define COMPILER_VERSION_TWEAK DEC(__ibmxl_ptf_fix_level__)
00144 # else
00145 /* __IBMCPP__ = VRP */
00146 #   define COMPILER_VERSION_MAJOR DEC(__IBMCPP__/100)
00147 #   define COMPILER_VERSION_MINOR DEC(__IBMCPP__/10 % 10)
00148 #   define COMPILER_VERSION_PATCH DEC(__IBMCPP__ % 10)
00149 # endif
00150
00151
00152 #elif defined(__PGI)
00153 # define COMPILER_ID "PGI"
00154 # define COMPILER_VERSION_MAJOR DEC(__PGIC__)
00155 # define COMPILER_VERSION_MINOR DEC(__PGIC_MINOR__)
00156 # if defined(__PGIC_PATCHLEVEL__)
00157 #   define COMPILER_VERSION_PATCH DEC(__PGIC_PATCHLEVEL__)
00158 # endif
00159
00160 #elif defined(__CRAYC)
00161 # define COMPILER_ID "Cray"
00162 # define COMPILER_VERSION_MAJOR DEC(_RELEASE_MAJOR)
00163 # define COMPILER_VERSION_MINOR DEC(_RELEASE_MINOR)
00164
00165 #elif defined(__TI_COMPILER_VERSION__)
00166 # define COMPILER_ID "TI"
00167 /* __TI_COMPILER_VERSION__ = VVRRRRPPP */
00168 # define COMPILER_VERSION_MAJOR DEC(__TI_COMPILER_VERSION__/1000000)
00169 # define COMPILER_VERSION_MINOR DEC(__TI_COMPILER_VERSION__/1000 % 1000)
00170 # define COMPILER_VERSION_PATCH DEC(__TI_COMPILER_VERSION__ % 1000)
00171
00172 #elif defined(__FUJITSU) || defined(__FCC_VERSION) || defined(__fcc_version)
00173 # define COMPILER_ID "Fujitsu"
00174
00175 #elif defined(__ghs__)
00176 # define COMPILER_ID "GHS"
00177 /* __GHS_VERSION_NUMBER = VVVVRP */
00178 # ifdef __GHS_VERSION_NUMBER
00179 #   define COMPILER_VERSION_MAJOR DEC(__GHS_VERSION_NUMBER / 100)
00180 #   define COMPILER_VERSION_MINOR DEC(__GHS_VERSION_NUMBER / 10 % 10)
00181 #   define COMPILER_VERSION_PATCH DEC(__GHS_VERSION_NUMBER % 10)
00182 # endif
00183
00184 #elif defined(__SCO_VERSION__)
00185 # define COMPILER_ID "SCO"
00186
00187 #elif defined(__clang__) && defined(__apple_build_version__)
00188 # define COMPILER_ID "AppleClang"
00189 # if defined(_MSC_VER)
00190 #   define SIMULATE_ID "MSVC"
00191 # endif
00192 # define COMPILER_VERSION_MAJOR DEC(__clang_major__)
00193 # define COMPILER_VERSION_MINOR DEC(__clang_minor__)
00194 # define COMPILER_VERSION_PATCH DEC(__clang_patchlevel__)
00195 # if defined(_MSC_VER)
00196 /* _MSC_VER = VVRR */
00197 #   define SIMULATE_VERSION_MAJOR DEC(_MSC_VER / 100)
00198 #   define SIMULATE_VERSION_MINOR DEC(_MSC_VER % 100)
00199 # endif
00200 # define COMPILER_VERSION_TWEAK DEC(__apple_build_version__)
00201
00202 #elif defined(__clang__)
00203 # define COMPILER_ID "Clang"
00204 # if defined(_MSC_VER)
00205 #   define SIMULATE_ID "MSVC"
00206 # endif
00207 # define COMPILER_VERSION_MAJOR DEC(__clang_major__)
00208 # define COMPILER_VERSION_MINOR DEC(__clang_minor__)
00209 # define COMPILER_VERSION_PATCH DEC(__clang_patchlevel__)
00210 # if defined(_MSC_VER)
00211 /* _MSC_VER = VVRR */
00212 #   define SIMULATE_VERSION_MAJOR DEC(_MSC_VER / 100)
00213 #   define SIMULATE_VERSION_MINOR DEC(_MSC_VER % 100)
00214 # endif
00215
00216 #elif defined(__GNUC__) || defined(__GNUG__)
00217 # define COMPILER_ID "GNU"
00218 # if defined(__GNUC__)
00219 #   define COMPILER_VERSION_MAJOR DEC(__GNUC__)
00220 # else

```

```

00221 # define COMPILER_VERSION_MAJOR DEC(__GNUG__)
00222 # endif
00223 # if defined(__GNUC_MINOR__)
00224 #   define COMPILER_VERSION_MINOR DEC(__GNUC_MINOR__)
00225 # endif
00226 # if defined(__GNUC_PATCHLEVEL__)
00227 #   define COMPILER_VERSION_PATCH DEC(__GNUC_PATCHLEVEL__)
00228 # endif
00229
00230 #elif defined(_MSC_VER)
00231 #   define COMPILER_ID "MSVC"
00232 #   /* _MSC_VER = VVRR */
00233 #   define COMPILER_VERSION_MAJOR DEC(_MSC_VER / 100)
00234 #   define COMPILER_VERSION_MINOR DEC(_MSC_VER % 100)
00235 #   if defined(_MSC_FULL_VER)
00236 #       if _MSC_VER >= 1400
00237 #           /* _MSC_FULL_VER = VVRRPPPP */
00238 #           define COMPILER_VERSION_PATCH DEC(_MSC_FULL_VER % 100000)
00239 #       else
00240 #           /* _MSC_FULL_VER = VVRRPPPP */
00241 #           define COMPILER_VERSION_PATCH DEC(_MSC_FULL_VER % 10000)
00242 #       endif
00243 #   endif
00244 #   if defined(_MSC_BUILD)
00245 #       define COMPILER_VERSION_TWEAK DEC(_MSC_BUILD)
00246 #   endif
00247
00248 #elif defined(__VISUALDSPVERSION__) || defined(__ADSPBLACKFIN__) || defined(__ADSPTS__) ||
    defined(__ADSP21000__)
00249 #   define COMPILER_ID "ADSP"
00250 #if defined(__VISUALDSPVERSION__)
00251 #   /* __VISUALDSPVERSION__ = 0xVVRRPP00 */
00252 #   define COMPILER_VERSION_MAJOR HEX(__VISUALDSPVERSION__>24)
00253 #   define COMPILER_VERSION_MINOR HEX(__VISUALDSPVERSION__>16 & 0xFF)
00254 #   define COMPILER_VERSION_PATCH HEX(__VISUALDSPVERSION__>8 & 0xFF)
00255 #endif
00256
00257 #elif defined(__IAR_SYSTEMS_ICC__) || defined(__IAR_SYSTEMS_ICC)
00258 #   define COMPILER_ID "IAR"
00259 #   if defined(__VER__) && defined(__ICARM__)
00260 #       define COMPILER_VERSION_MAJOR DEC((__VER__) / 1000000)
00261 #       define COMPILER_VERSION_MINOR DEC(((__VER__) / 1000) % 1000)
00262 #       define COMPILER_VERSION_PATCH DEC((__VER__) % 1000)
00263 #       define COMPILER_VERSION_INTERNAL DEC(__IAR_SYSTEMS_ICC__)
00264 #   elif defined(__VER__) && defined(__ICCAVR__)
00265 #       define COMPILER_VERSION_MAJOR DEC((__VER__) / 100)
00266 #       define COMPILER_VERSION_MINOR DEC((__VER__) - (((__VER__) / 100)*100))
00267 #       define COMPILER_VERSION_PATCH DEC(__SUBVERSION__)
00268 #       define COMPILER_VERSION_INTERNAL DEC(__IAR_SYSTEMS_ICC__)
00269 #   endif
00270
00271 #elif defined(__ARMCC_VERSION)
00272 #   define COMPILER_ID "ARMCC"
00273 #   if __ARMCC_VERSION >= 1000000
00274 #       /* __ARMCC_VERSION = VRRPPPP */
00275 #       define COMPILER_VERSION_MAJOR DEC(__ARMCC_VERSION/1000000)
00276 #       define COMPILER_VERSION_MINOR DEC(__ARMCC_VERSION/10000 % 100)
00277 #       define COMPILER_VERSION_PATCH DEC(__ARMCC_VERSION % 10000)
00278 #   else
00279 #       /* __ARMCC_VERSION = VRPPPP */
00280 #       define COMPILER_VERSION_MAJOR DEC(__ARMCC_VERSION/100000)
00281 #       define COMPILER_VERSION_MINOR DEC(__ARMCC_VERSION/10000 % 10)
00282 #       define COMPILER_VERSION_PATCH DEC(__ARMCC_VERSION % 10000)
00283 #   endif
00284
00285
00286 #elif defined(_SGI_COMPILER_VERSION) || defined(_COMPILER_VERSION)
00287 #   define COMPILER_ID "MIPSpro"
00288 #   if defined(_SGI_COMPILER_VERSION)
00289 #       /* _SGI_COMPILER_VERSION = VRP */
00290 #       define COMPILER_VERSION_MAJOR DEC(_SGI_COMPILER_VERSION/100)
00291 #       define COMPILER_VERSION_MINOR DEC(_SGI_COMPILER_VERSION/10 % 10)
00292 #       define COMPILER_VERSION_PATCH DEC(_SGI_COMPILER_VERSION % 10)
00293 #   else
00294 #       /* _COMPILER_VERSION = VRP */
00295 #       define COMPILER_VERSION_MAJOR DEC(_COMPILER_VERSION/100)
00296 #       define COMPILER_VERSION_MINOR DEC(_COMPILER_VERSION/10 % 10)
00297 #       define COMPILER_VERSION_PATCH DEC(_COMPILER_VERSION % 10)
00298 #   endif
00299
00300
00301 /* These compilers are either not known or too old to define an
00302 identification macro. Try to identify the platform and guess that
00303 it is the native compiler. */
00304 #elif defined(__hpux) || defined(__hpua)
00305 #   define COMPILER_ID "HP"
00306

```

```

00307 #else /* unknown compiler */
00308 # define COMPILER_ID ""
00309 #endif
00310
00311 /* Construct the string literal in pieces to prevent the source from
00312    getting matched. Store it in a pointer rather than an array
00313    because some compilers will just produce instructions to fill the
00314    array rather than assigning a pointer to a static array. */
00315 char const* info_compiler = "INFO" ":" "compiler[" COMPILER_ID "]";
00316 #ifdef SIMULATE_ID
00317 char const* info_simulate = "INFO" ":" "simulate[" SIMULATE_ID "]";
00318 #endif
00319
00320 #ifdef __QNXNTO__
00321 char const* qnxnto = "INFO" ":" "qnxnto[]";
00322 #endif
00323
00324 #if defined(__CRAYXE) || defined(__CRAYXC)
00325 char const* info_cray = "INFO" ":" "compiler_wrapper[CrayPrgEnv]";
00326 #endif
00327
00328 #define STRINGIFY_HELPER(X) #X
00329 #define STRINGIFY(X) STRINGIFY_HELPER(X)
00330
00331 /* Identify known platforms by name. */
00332 #if defined(__linux) || defined(__linux__) || defined(linux)
00333 # define PLATFORM_ID "Linux"
00334
00335 #elif defined(__CYGWIN__)
00336 # define PLATFORM_ID "Cygwin"
00337
00338 #elif defined(__MINGW32__)
00339 # define PLATFORM_ID "MinGW"
00340
00341 #elif defined(__APPLE__)
00342 # define PLATFORM_ID "Darwin"
00343
00344 #elif defined(__WIN32) || defined(__WIN32__) || defined(WIN32)
00345 # define PLATFORM_ID "Windows"
00346
00347 #elif defined(__FreeBSD__) || defined(__FreeBSD)
00348 # define PLATFORM_ID "FreeBSD"
00349
00350 #elif defined(__NetBSD__) || defined(__NetBSD)
00351 # define PLATFORM_ID "NetBSD"
00352
00353 #elif defined(__OpenBSD__) || defined(__OPENBSD)
00354 # define PLATFORM_ID "OpenBSD"
00355
00356 #elif defined(__sun) || defined(sun)
00357 # define PLATFORM_ID "SunOS"
00358
00359 #elif defined(_AIX) || defined(__AIX) || defined(__AIX__) || defined(__aix) || defined(__aix__)
00360 # define PLATFORM_ID "AIX"
00361
00362 #elif defined(__hpux) || defined(__hpux__)
00363 # define PLATFORM_ID "HP-UX"
00364
00365 #elif defined(__HAIKU__)
00366 # define PLATFORM_ID "Haiku"
00367
00368 #elif defined(__BeOS) || defined(__BEOS__) || defined(_BEOS)
00369 # define PLATFORM_ID "BeOS"
00370
00371 #elif defined(__QNX__) || defined(__QNXNTO__)
00372 # define PLATFORM_ID "QNX"
00373
00374 #elif defined(__tru64) || defined(_tru64) || defined(__TRU64__)
00375 # define PLATFORM_ID "Tru64"
00376
00377 #elif defined(__riscos) || defined(__riscos__)
00378 # define PLATFORM_ID "RISCos"
00379
00380 #elif defined(__sinix) || defined(__sinix__) || defined(__SINIX__)
00381 # define PLATFORM_ID "SINIX"
00382
00383 #elif defined(__UNIX_SV__)
00384 # define PLATFORM_ID "UNIX_SV"
00385
00386 #elif defined(__bsdos__)
00387 # define PLATFORM_ID "BSDOS"
00388
00389 #elif defined(_MPRAS) || defined(MPRAS)
00390 # define PLATFORM_ID "MP-RAS"
00391
00392 #elif defined(__osf) || defined(__osf__)
00393 # define PLATFORM_ID "OSF1"

```

```
00394
00395 #elif defined(__SCO_SV) || defined(SCO_SV) || defined(sco_sv)
00396 # define PLATFORM_ID "SCO_SV"
00397
00398 #elif defined(__ultrix) || defined(__ultrix__) || defined(ULTRIX)
00399 # define PLATFORM_ID "ULTRIX"
00400
00401 #elif defined(__XENIX__) || defined(_XENIX) || defined(XENIX)
00402 # define PLATFORM_ID "Xenix"
00403
00404 #elif defined(__WATCOMC__)
00405 # if defined(__LINUX__)
00406 #   define PLATFORM_ID "Linux"
00407
00408 # elif defined(__DOS__)
00409 #   define PLATFORM_ID "DOS"
00410
00411 # elif defined(__OS2__)
00412 #   define PLATFORM_ID "OS2"
00413
00414 # elif defined(__WINDOWS__)
00415 #   define PLATFORM_ID "Windows3x"
00416
00417 # else /* unknown platform */
00418 #   define PLATFORM_ID
00419 # endif
00420
00421 #elif defined(__INTEGRITY)
00422 # if defined(INT_178B)
00423 #   define PLATFORM_ID "Integrity178"
00424
00425 # else /* regular Integrity */
00426 #   define PLATFORM_ID "Integrity"
00427 # endif
00428
00429 #else /* unknown platform */
00430 # define PLATFORM_ID
00431
00432 #endif
00433
00434 /* For windows compilers MSVC and Intel we can determine
00435    the architecture of the compiler being used. This is because
00436    the compilers do not have flags that can change the architecture,
00437    but rather depend on which compiler is being used
00438 */
00439 #if defined(_WIN32) && defined(_MSC_VER)
00440 # if defined(_M_IA64)
00441 #   define ARCHITECTURE_ID "IA64"
00442
00443 # elif defined(_M_X64) || defined(_M_AMD64)
00444 #   define ARCHITECTURE_ID "x64"
00445
00446 # elif defined(_M_IX86)
00447 #   define ARCHITECTURE_ID "X86"
00448
00449 # elif defined(_M_ARM64)
00450 #   define ARCHITECTURE_ID "ARM64"
00451
00452 # elif defined(_M_ARM)
00453 #   if _M_ARM == 4
00454 #     define ARCHITECTURE_ID "ARMV4I"
00455 #   elif _M_ARM == 5
00456 #     define ARCHITECTURE_ID "ARMV5I"
00457 #   else
00458 #     define ARCHITECTURE_ID "ARMV" STRINGIFY(_M_ARM)
00459 #   endif
00460
00461 # elif defined(_M_MIPS)
00462 #   define ARCHITECTURE_ID "MIPS"
00463
00464 # elif defined(_M_SH)
00465 #   define ARCHITECTURE_ID "SHx"
00466
00467 # else /* unknown architecture */
00468 #   define ARCHITECTURE_ID ""
00469 # endif
00470
00471 #elif defined(__WATCOMC__)
00472 # if defined(_M_I86)
00473 #   define ARCHITECTURE_ID "I86"
00474
00475 # elif defined(_M_IX86)
00476 #   define ARCHITECTURE_ID "X86"
00477
00478 # else /* unknown architecture */
00479 #   define ARCHITECTURE_ID ""
00480 # endif
```



```

00481
00482 #elif defined(__IAR_SYSTEMS_ICC__) || defined(__IAR_SYSTEMS_ICC)
00483 # if defined(__ICCARM__)
00484 #   define ARCHITECTURE_ID "ARM"
00485
00486 # elif defined(__ICCAVR__)
00487 #   define ARCHITECTURE_ID "AVR"
00488
00489 # else /* unknown architecture */
00490 #   define ARCHITECTURE_ID ""
00491 # endif
00492
00493 #elif defined(__ghs__)
00494 # if defined(__PPC64__)
00495 #   define ARCHITECTURE_ID "PPC64"
00496
00497 # elif defined(__ppc__)
00498 #   define ARCHITECTURE_ID "PPC"
00499
00500 # elif defined(__ARM__)
00501 #   define ARCHITECTURE_ID "ARM"
00502
00503 # elif defined(__x86_64__)
00504 #   define ARCHITECTURE_ID "x64"
00505
00506 # elif defined(__i386__)
00507 #   define ARCHITECTURE_ID "X86"
00508
00509 # else /* unknown architecture */
00510 #   define ARCHITECTURE_ID ""
00511 # endif
00512 #else
00513 #   define ARCHITECTURE_ID
00514 #endif
00515
00516 /* Convert integer to decimal digit literals. */
00517 #define DEC(n) \
00518   ('0' + ((n) / 10000000) % 10), \
00519   ('0' + ((n) / 1000000) % 10), \
00520   ('0' + ((n) / 100000) % 10), \
00521   ('0' + ((n) / 10000) % 10), \
00522   ('0' + ((n) / 1000) % 10), \
00523   ('0' + ((n) / 100) % 10), \
00524   ('0' + ((n) / 10) % 10), \
00525   ('0' + (n) % 10)
00526
00527 /* Convert integer to hex digit literals. */
00528 #define HEX(n) \
00529   ('0' + ((n) >> 28 & 0xF)), \
00530   ('0' + ((n) >> 24 & 0xF)), \
00531   ('0' + ((n) >> 20 & 0xF)), \
00532   ('0' + ((n) >> 16 & 0xF)), \
00533   ('0' + ((n) >> 12 & 0xF)), \
00534   ('0' + ((n) >> 8 & 0xF)), \
00535   ('0' + ((n) >> 4 & 0xF)), \
00536   ('0' + (n) & 0xF)
00537
00538 /* Construct a string literal encoding the version number components. */
00539 #ifdef COMPILER_VERSION_MAJOR
00540 char const info_version[] = {
00541   'I', 'N', 'F', 'O', ':',
00542   'C', 'O', 'M', 'P', 'I', 'L', 'E', 'R', '_', 'V', 'E', 'R', 'S', 'I', 'O', 'N', '[',
00543   COMPILER_VERSION_MAJOR,
00544   #ifdef COMPILER_VERSION_MINOR
00545   '.', COMPILER_VERSION_MINOR,
00546   #ifdef COMPILER_VERSION_PATCH
00547   '.', COMPILER_VERSION_PATCH,
00548   #ifdef COMPILER_VERSION_TWEAK
00549   '.', COMPILER_VERSION_TWEAK,
00550   #endif
00551   #endif
00552   #endif
00553   ']', '\0'};
00554 #endif
00555
00556 /* Construct a string literal encoding the internal version number. */
00557 #ifdef COMPILER_VERSION_INTERNAL
00558 char const info_version_internal[] = {
00559   'I', 'N', 'F', 'O', ':',
00560   'C', 'O', 'M', 'P', 'I', 'L', 'E', 'R', '_', 'V', 'E', 'R', 'S', 'I', 'O', 'N', '_',
00561   'I', 'N', 'T', 'E', 'R', 'N', 'A', 'L', '[',
00562   COMPILER_VERSION_INTERNAL, ']', '\0'};
00563 #endif
00564
00565 /* Construct a string literal encoding the version number components. */
00566 #ifdef SIMULATE_VERSION_MAJOR
00567 char const info_simulate_version[] = {

```

```

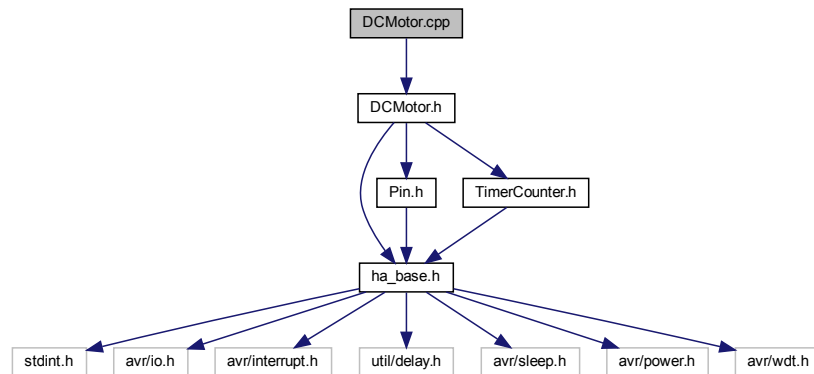
00568 'I', 'N', 'F', 'O', ':',
00569 's', 'i', 'm', 'u', 'l', 'a', 't', 'e', '_', 'v', 'e', 'r', 's', 'i', 'o', 'n', '[',
00570 SIMULATE_VERSION_MAJOR,
00571 # ifdef SIMULATE_VERSION_MINOR
00572 ' ', SIMULATE_VERSION_MINOR,
00573 # ifdef SIMULATE_VERSION_PATCH
00574 ' ', SIMULATE_VERSION_PATCH,
00575 # ifdef SIMULATE_VERSION_TWEAK
00576 ' ', SIMULATE_VERSION_TWEAK,
00577 # endif
00578 # endif
00579 # endif
00580 ']', '\0'};
00581 #endif
00582
00583 /* Construct the string literal in pieces to prevent the source from
00584    getting matched. Store it in a pointer rather than an array
00585    because some compilers will just produce instructions to fill the
00586    array rather than assigning a pointer to a static array. */
00587 char const* info_platform = "INFO" ":" "platform[" PLATFORM_ID " ]";
00588 char const* info_arch = "INFO" ":" "arch[" ARCHITECTURE_ID " ]";
00589
00590
00591
00592
00593 #if defined(_MSC_VER) && defined(_MSVC_LANG)
00594 #define CXX_STD _MSVC_LANG
00595 #else
00596 #define CXX_STD __cplusplus
00597 #endif
00598
00599 const char* info_language_dialect_default = "INFO" ":" "dialect_default["
00600 #if CXX_STD > 201703L
00601 "20"
00602 #elif CXX_STD >= 201703L
00603 "17"
00604 #elif CXX_STD >= 201402L
00605 "14"
00606 #elif CXX_STD >= 201103L
00607 "11"
00608 #else
00609 "98"
00610 #endif
00611 " ]";
00612
00613 /*-----*/
00614
00615 int main(int argc, char* argv[])
00616 {
00617     int require = 0;
00618     require += info_compiler[argc];
00619     require += info_platform[argc];
00620     #ifdef COMPILER_VERSION_MAJOR
00621     require += info_version[argc];
00622     #endif
00623     #ifdef COMPILER_VERSION_INTERNAL
00624     require += info_version_internal[argc];
00625     #endif
00626     #ifdef SIMULATE_ID
00627     require += info_simulate[argc];
00628     #endif
00629     #ifdef SIMULATE_VERSION_MAJOR
00630     require += info_simulate_version[argc];
00631     #endif
00632     #if defined(__CRAYXE) || defined(__CRAYXC)
00633     require += info_cray[argc];
00634     #endif
00635     require += info_language_dialect_default[argc];
00636     (void)argv;
00637     return require;
00638 }

```

7.19 DCMotor.cpp File Reference

```
#include "DCMotor.h"
```

Include dependency graph for DCMotor.cpp:



7.20 DCMotor.cpp

```

00001 #include "DCMotor.h"
00002
00003 component::DCMotor::DCMotor(const io::Pin &ar_pin)
00004     : m_pin(ar_pin)
00005 {
00006     m_pin.toOutput();
00007 }
00008
00009
00010
00011 component::DCMotor::~DCMotor()
00012 {
00013 }
00014
00015
00016 void component::DCMotor::on()
00017 {
00018     m_pin.setHigh();
00019 }
00020
00021 void component::DCMotor::off()
00022 {
00023     m_pin.setLow();
00024 }
00025
00026 void component::DCMotor::toggle()
00027 {
00028     m_pin.toggle();
00029 }
00030 }
  
```

7.21 DCMotor.h File Reference

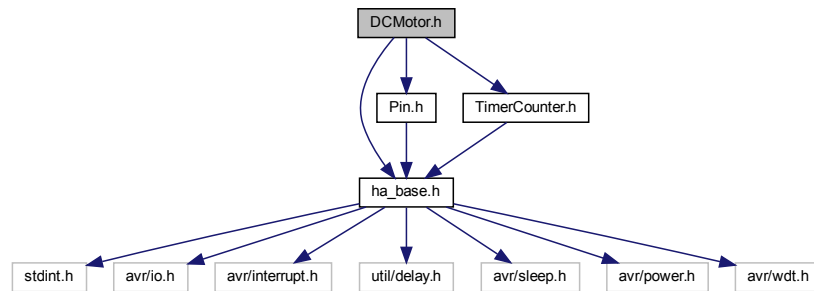
Header file of the DCMotor class.

```

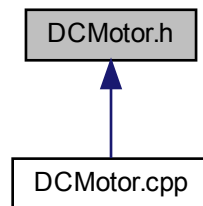
#include "ha_base.h"
#include "Pin.h"
  
```

```
#include "TimerCounter.h"
```

Include dependency graph for DCMotor.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [component::DCMotor](#)

Namespaces

- [component](#)

7.21.1 Detailed Description

Header file of the DCMotor class.

Usage example (test): `#include "MCU.h" #include "TimerCounter0.h" #include "DCMotor.h"`

```
#define DCMOTOR_NUMBER 6
```

```
int main(void) {
```

Init initialize MCU `core::MCU::init();`

instantiate the TimerCounter0 object `core::TimerCounter0` &myTimerCounter0 = `core::TimerCounter0::getInstance();`
`myTimerCounter0.selectClockSource(core::clockSource::PS_1024);`

instantiate a DCMotor object `component::DCMotor` myDCMotor(`io::Pin(DCMOTOR_NUMBER,io::PortD)`);

`myDCMotor.connect(myTimerCounter0);`

`myDCMotor.spin(myTimerCounter0,0); _delay_ms(5000);`

`myDCMotor.spin(myTimerCounter0,75); _delay_ms(5000);`

`myDCMotor.spin(myTimerCounter0,190); _delay_ms(5000);`

`myDCMotor.spin(myTimerCounter0,200); _delay_ms(5000);`

`myDCMotor.disconnect(myTimerCounter0);`

Mainloop while (1) {

} return 0; } Usage example (H Bridge):

`#include "MCU.h" #include "TimerCounter0.h" #include "DCMotor.h"`

`#define DCMOTOR_NUMBER 6 #define DCMOTOR_BACKWARD 0 #define DCMOTOR_FORWARD 1`

`int main(void) {`

Init initialize MCU `core::MCU::init();`

instantiate the TimerCounter0 object `core::TimerCounter0` &myTimerCounter0 = `core::TimerCounter0::getInstance();`
`myTimerCounter0.selectClockSource(core::clockSource::PS_256);`

instantiate a DCMotor object `component::DCMotor` myDCMotor(`io::Pin(DCMOTOR_NUMBER,io::PortD)`);

instantiate direction pins objects

`io::Pin` myPinForward = `io::Pin(DCMOTOR_FORWARD,io::PortB)`; myPinForward.toOutput();

`io::Pin` myPinBackward = `io::Pin(DCMOTOR_BACKWARD,io::PortB)`; myPinBackward.toOutput();

`myDCMotor.connect(myTimerCounter0);`

`myPinForward.setHigh(); myPinBackward.setLow(); myDCMotor.spin(myTimerCounter0,30); _delay_ms(5000);`

`myPinForward.setLow(); myPinBackward.setHigh(); myDCMotor.spin(myTimerCounter0,30); _delay_ms(5000);`

`myDCMotor.disconnect(myTimerCounter0);`

Mainloop while (1) {

} return 0; }

Basic class for IO abstraction of Pin and Port

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file `DCMotor.h`.

7.22 DCMotor.h

```

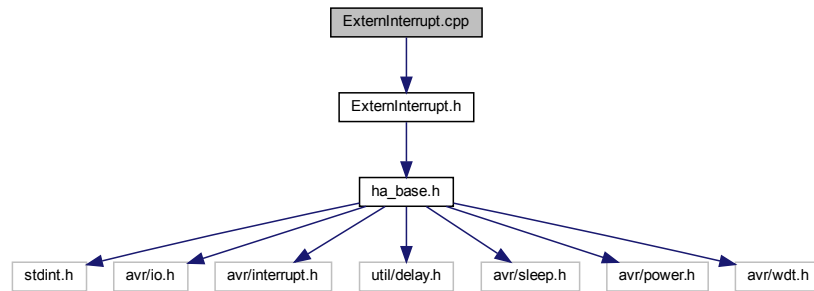
00001
00117 #ifndef DCMOTOR_H
00118 #define DCMOTOR_H
00119 #include "ha_base.h"
00120 #include "Pin.h"
00121 #include "TimerCounter.h"
00122
00123 namespace component
00124 {
00125
00126 class DCMotor
00127 {
00128 public:
00129     DCMotor(const io::Pin &ar_pin);
00130
00131     ~DCMotor();
00132
00133     void on();
00134     void off();
00135     void toggle();
00136
00137     template<typename TC>
00138     void spin(TC &ar_timerCounter,
00139              //const uint8_t &ar_dir,
00140              const uint16_t &ar_speed,
00141              const core::channel &ar_channel=core::channel::A)
00142     {
00143         ar_timerCounter.setOutputCompareRegister(ar_channel, ar_speed);
00144         ar_timerCounter.start();
00145     }
00146
00147     template<typename TC>
00148     void stop(TC &ar_timerCounter)
00149     {
00150         ar_timerCounter.stop();
00151     }
00152
00153     template<typename TC>
00154     void connect(TC &ar_timerCounter,
00155                 const core::channel &ar_channel=core::channel::A)
00156     {
00157         ar_timerCounter.selectOperationMode(core::operationMode::fast_PWM);
00158         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::clear);
00159         ar_timerCounter.setCounter(0);
00160     }
00161
00162     template<typename TC>
00163     void disconnect(TC &ar_timerCounter,
00164                    const core::channel &ar_channel=core::channel::A)
00165     {
00166         ar_timerCounter.selectCompareOutputMode(ar_channel, core::compareOutputMode::normal);
00167         ar_timerCounter.stop();
00168     }
00169
00170 private:
00171     io::Pin m_pin;
00172 };
00173
00174 #endif // DCMOTOR_H

```

7.23 ExternInterrupt.cpp File Reference

```
#include "ExternInterrupt.h"
```

Include dependency graph for ExternInterrupt.cpp:



7.24 ExternInterrupt.cpp

```

00001 #include "ExternInterrupt.h"
00002
00003 core::ExternInterrupt& core::ExternInterrupt::getInstance()
00004 {
00005     static ExternInterrupt l_instance;
00006     return l_instance;
00007 }
00008
00009
00010
00011 core::ExternInterrupt::ExternInterrupt()
00012 {
00013     sei();
00014 }
00015
00016
00017 core::ExternInterrupt::~ExternInterrupt()
00018 {
00019 }
00020
00021
00022 void core::ExternInterrupt::setInt0SenseControl(const senseControl& ar_senseControl)
00023 {
00024     EXT_INT_SET_INT0_SENSE_CONTROL(static_cast<uint8_t>(ar_senseControl));
00025 }
00026
00027
00028 void core::ExternInterrupt::setInt1SenseControl(const senseControl& ar_senseControl)
00029 {
00030     EXT_INT_SET_INT1_SENSE_CONTROL(static_cast<uint8_t>(ar_senseControl));
00031 }
00032
00033
00034 void core::ExternInterrupt::enableInt0(const uint8_t a_enable)
00035 {
00036     if (a_enable) {
00037         EXT_INT_ENABLE_INT0;
00038     } else {
00039         EXT_INT_DISABLE_INT0;
00040     }
00041 }
00042
00043
00044
00045 void core::ExternInterrupt::enableInt1(const uint8_t a_enable)
00046 {
00047     if (a_enable) {
00048         EXT_INT_ENABLE_INT1;
00049     } else {
00050         EXT_INT_DISABLE_INT1;
00051     }
00052 }
00053
00054
00055
00056 void core::ExternInterrupt::enablePinChange(const pinChangePort& ar_pinChangePort, const uint8_t
a_enable)

```

```

00057 {
00058     if (a_enable) {
00059         EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT(static_cast<uint8_t>(ar_pinChangePort));
00060     } else {
00061         EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT(static_cast<uint8_t>(ar_pinChangePort));
00062     }
00063 }
00064
00065 }
00066
00067 void core::ExternInterrupt::enablePinChangeMaskPortB(const uint8_t a_pinNumber, const uint8_t
a_enable)
00068 {
00069     if (a_enable) {
00070         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(a_pinNumber);
00071     } else {
00072         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(a_pinNumber);
00073     }
00074 }
00075
00076 }
00077
00078
00079 void core::ExternInterrupt::enablePinChangeMaskPortC(const uint8_t a_pinNumber, const uint8_t
a_enable)
00080 {
00081     if (a_enable) {
00082         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(a_pinNumber);
00083     } else {
00084         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(a_pinNumber);
00085     }
00086 }
00087
00088 }
00089
00090 void core::ExternInterrupt::enablePinChangeMaskPortD(const uint8_t a_pinNumber, const uint8_t
a_enable)
00091 {
00092     if (a_enable) {
00093         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(a_pinNumber);
00094     } else {
00095         EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(a_pinNumber);
00096     }
00097 }
00098 }

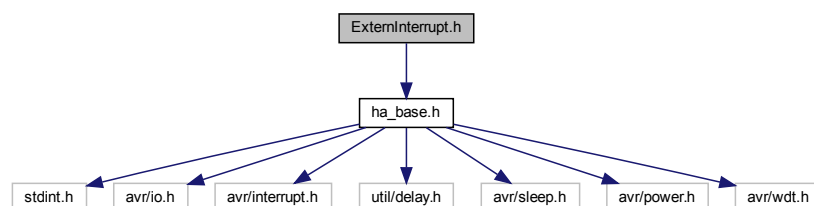
```

7.25 ExternInterrupt.h File Reference

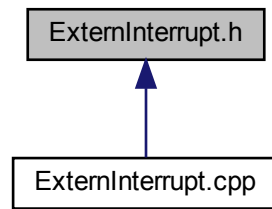
Header file of the ExternInterrupt class.

```
#include "ha_base.h"
```

Include dependency graph for ExternInterrupt.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::ExternInterrupt](#)

Namespaces

- [core](#)

Enumerations

- enum [core::senseControl](#) : `uint8_t` { [core::senseControl::lowLevel](#) =0, [core::senseControl::logicalChange](#), [core::senseControl::fallingEdge](#), [core::senseControl::risingEdge](#) }
- enum [core::pinChangePort](#) : `uint8_t` { [core::pinChangePort::PCINTB](#) =0, [core::pinChangePort::PCINTC](#), [core::pinChangePort::PCINTD](#) }

7.25.1 Detailed Description

Header file of the ExternInterrupt class.

class to handle externally triggered interrupts.

Usage example (external interrupt):

```
#include "PushButton.h" #include "Led.h" #include "ExternInterrupt.h"
```

```
#define PUSHBUTTON_NUMBER 2 #define MAIN_LED_NUMBER 0 #define INTERRUPT_LED_NUMBER 1 #define DELAYTIME 1000
```

```
instantiate a Led object declaration of global variables (shut up warning) extern component::Led MainLed; extern component::Led InterruptLed; component::Led MainLed(io::Pin(MAIN_LED_NUMBER,io::PortB)); component::Led InterruptLed(io::Pin(INTERRUPT_LED_NUMBER,io::PortB));
```

```
instantiate a Led object declaration of global variable (shut up warning) extern component::PushButton PushButton; component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortD));
```

```
int main(void) {
```

Init

```

instantiate the external interrupt manager core::ExternInterrupt &myExternInterrupt = core::ExternInterrupt::getInstance();
myExternInterrupt.enableInt0(1); myExternInterrupt.setInt0SenseControl(core::senseControl::logicalChange);

```

Mainloop while (1) {

```

MainLed.toggle(); _delay_ms(DELAYTIME);

```

```

} return 0; }

```

```

void core::ExternInterrupt::Int0ServiceRoutine() { if (PushButton.isPressed()) { InterruptLed.on(); } else { InterruptLed.off(); }
}

```

Usage example (pin change interrupt):

```

#include "PushButton.h" #include "Led.h" #include "ExternInterrupt.h"

```

```

#define PUSHBUTTON_1_NUMBER 2 #define PUSHBUTTON_2_NUMBER 3 #define MAIN_LED_NUMBER 0
#define INTERRUPT_LED_1_NUMBER 1 #define INTERRUPT_LED_2_NUMBER 2 #define DELAYTIME 1000

```

```

instantiate a Led objects declaration of global variables (shut up warning) extern component::Led MainLed; extern component::Led InterruptLed1; extern component::Led InterruptLed2; component::Led MainLed(io::Pin(MAIN_LED_NUMBER,io::PortB)); component::Led InterruptLed1(io::Pin(INTERRUPT_LED_1_NUMBER,io::PortB)); component::Led InterruptLed2(io::Pin(INTERRUPT_LED_2_NUMBER,io::PortB));

```

```

instantiate a PushButton objects declaration of global variable (shut up warning) extern component::PushButton PushButton1; extern component::PushButton PushButton2; component::PushButton PushButton1(io::Pin(PUSHBUTTON_1_NUMBER,io::PortD)); component::PushButton PushButton2(io::Pin(PUSHBUTTON_2_NUMBER,io::PortB));

```

```

int main(void) {

```

Init

```

instantiate the external interrupt manager core::ExternInterrupt &myExternInterrupt = core::ExternInterrupt::getInstance();
myExternInterrupt.enablePinChange(core::pinChangePort::PCINTD,1); myExternInterrupt.enablePinChange(core::pinChangePort::PCINTB,1); myExternInterrupt.enablePinChangeMaskPortD(PUSHBUTTON_1_NUMBER,1);
myExternInterrupt.enablePinChangeMaskPortB(PUSHBUTTON_2_NUMBER,1);

```

Mainloop while (1) {

```

MainLed.toggle(); _delay_ms(DELAYTIME);

```

```

} return 0; }

```

```

void core::ExternInterrupt::pinChangePortDServiceRoutine() { if (PushButton1.isPressed()) { InterruptLed1.on();

```

```

} else { InterruptLed1.off();

```

```

} } void core::ExternInterrupt::pinChangePortBServiceRoutine() { if (PushButton2.isPressed()) { InterruptLed2.on();
} else { InterruptLed2.off(); }

```

```

}

```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file `ExternInterrupt.h`.

7.26 ExternInterrupt.h

```

00001
00140 #ifndef EXTERN_INTERRUPTS_H
00141 #define EXTERN_INTERRUPTS_H
00142 #include "ha_base.h"
00143
00144
00145
00146 namespace core
00147 {
00148
00149 enum class senseControl : uint8_t {
00150     lowLevel=0,
00151     logicalChange,
00152     fallingEdge,
00153     risingEdge
00154 };
00155
00156 enum class pinChangePort : uint8_t {
00157     PCINTB=0,
00158     PCINTC,
00159     PCINTD,
00160 };
00161
00162 class ExternInterrupt
00163 {
00164
00165 public:
00166
00167     static ExternInterrupt& getInstance();
00168
00169     void setInt0SenseControl(const senseControl& ar_senseControl);
00170
00171     void setInt1SenseControl(const senseControl& ar_senseControl);
00172
00173     void enableInt0(const uint8_t a_enable);
00174
00175     void enableInt1(const uint8_t a_enable);
00176
00177     void enablePinChange(const pinChangePort& ar_pinChangePort, const uint8_t a_enable);
00178
00179     void enablePinChangeMaskPortB(const uint8_t a_pinNumber, const uint8_t a_enable);
00180
00181     void enablePinChangeMaskPortC(const uint8_t a_pinNumber, const uint8_t a_enable);
00182
00183     void enablePinChangeMaskPortD(const uint8_t a_pinNumber, const uint8_t a_enable);
00184
00185     static void Int0ServiceRoutine() __asm__(STR(EXT_INT_INT0_INTERRUPT)) __attribute__((__signal__,
00186         __used__, __externally_visible__));
00187
00188     static void Int1ServiceRoutine() __asm__(STR(EXT_INT_INT1_INTERRUPT)) __attribute__((__signal__,
00189         __used__, __externally_visible__));
00190
00191     static void pinChangePortBServiceRoutine() __asm__(STR(EXT_INT_PIN_CHANGE_PORTB_INTERRUPT))
00192         __attribute__((__signal__, __used__, __externally_visible__));
00193
00194     static void pinChangePortCServiceRoutine() __asm__(STR(EXT_INT_PIN_CHANGE_PORTC_INTERRUPT))
00195         __attribute__((__signal__, __used__, __externally_visible__));
00196
00197     static void pinChangePortDServiceRoutine() __asm__(STR(EXT_INT_PIN_CHANGE_PORTD_INTERRUPT))
00198         __attribute__((__signal__, __used__, __externally_visible__));
00199
00200 protected:
00201
00202 private:
00203
00204     ExternInterrupt();
00205
00206     ~ExternInterrupt();
00207
00208     ExternInterrupt(const ExternInterrupt&);
00209
00210     const ExternInterrupt& operator=(const ExternInterrupt&);
00211
00212 };
00213
00214 }
00215
00216
00217
00218
00219
00220 #endif

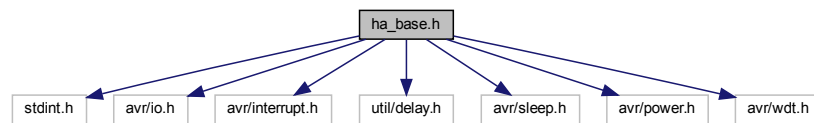
```

7.27 ha_base.h File Reference

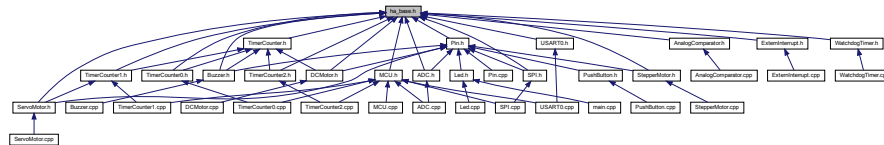
Base header file for the basic hardware abstraction macros.

```
#include <stdint.h>
#include <avr/io.h>
#include <avr/interrupt.h>
#include <util/delay.h>
#include <avr/sleep.h>
#include <avr/power.h>
#include <avr/wdt.h>
```

Include dependency graph for ha_base.h:



This graph shows which files directly or indirectly include this file:



Macros

- #define STRx(s) #s
- #define STR(s) STRx(s)

7.27.1 Detailed Description

Base header file for the basic hardware abstraction macros.

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [ha_base.h](#).

7.27.2 Macro Definition Documentation

7.27.2.1 STR

```
#define STR(  
    s ) STRx(s)
```

Definition at line 16 of file [ha_base.h](#).

7.27.2.2 STRx

```
#define STRx(  
    s ) #s
```

Definition at line 15 of file [ha_base.h](#).

7.28 ha_base.h

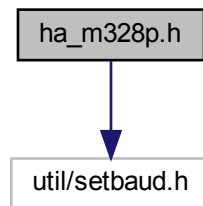
```
00001  
00009 #ifndef HABASE_H  
00010 #define HABASE_H  
00011  
00012 /*  
00013  * Helper construct to get interrupt numbers from names  
00014  */  
00015 #define STRx(s) #s  
00016 #define STR(s) STRx(s)  
00017  
00018 /*  
00019  * Any class needs these includes from avr-libc  
00020  */  
00021 #include <stdint.h>  
00022 #include <avr/io.h>  
00023 #include <avr/interrupt.h>  
00024 #include <util/delay.h>  
00025 #include <avr/sleep.h>  
00026 #include <avr/power.h>  
00027 #include <avr/wdt.h>  
00028  
00029  
00030 /*  
00031  * include hardware abstraction the Atmega328p  
00032  */  
00033 #if defined(__AVR_ATmega328P__)  
00034  
00035     #include "ha_m328p.h"  
00036     #include "utils_m328p.h"  
00037  
00038 #endif  
00039  
00040  
00041 #endif
```

7.29 ha_m328p.h File Reference

Header file for the hardware abstraction macros of the Atmega328p.

```
#include <util/setbaud.h>
```

Include dependency graph for ha_m328p.h:



Macros

- `#define PUSHBUTTON_DEBOUNCE_TIME_US 1000`
- `#define PUSHBUTTON_SAMPLING 12`
- `#define USART0_SET_BAUDRATE_HIGH_REGISTER UBRR0H = UBRRH_VALUE`
- `#define USART0_SET_BAUDRATE_LOW_REGISTER UBRR0L = UBRRL_VALUE`
- `#define USART0_ENABLE_ASYNC_TRANSMISSION_MODE UCSR0C &= ~((1 << UMSEL01) | (1 << UMSEL00))`
- `#define USART0_ENABLE_SYNC_TRANSMISSION_MODE UCSR0C = (UCSR0C & ~(1 << UMSEL01)) | (1 << UMSEL00)`
- `#define USART0_ENABLE_MASTER_SPI_MODE UCSR0C |= (1 << UMSEL01) | (1 << UMSEL00)`
- `#define USART0_ENABLE_DOUBLE_SPEED_MODE`
- `#define USART0_DISABLE_DOUBLE_SPEED_MODE`
- `#define USART0_DISABLE_DOUBLE_SPEED_MODE UCSR0A &= ~(1 << U2X0)`
- `#define USART0_ENABLE_EVEN_PARITY_MODE UCSR0C = (1 << UPM01) | (UCSR0C & ~(1 << UPM00))`
- `#define USART0_ENABLE_ODD_PARITY_MODE UCSR0C |= ((1 << UPM01) | (1 << UPM00))`
- `#define USART0_DISABLE_PARITY_MODE UCSR0C &= ~((1 << UPM01) | (1 << UPM00))`
- `#define USART0_SET_ONE_STOP_BIT UCSR0C &= ~(1 << USBS0)`
- `#define USART0_SET_TWO_STOP_BITS UCSR0C |= (1 << USBS0)`
- `#define USART0_SET_9BIT_FRAME_SIZE`
- `#define USART0_SET_8BIT_FRAME_SIZE`
- `#define USART0_SET_7BIT_FRAME_SIZE`
- `#define USART0_SET_6BIT_FRAME_SIZE`
- `#define USART0_SET_5BIT_FRAME_SIZE`
- `#define USART0_ENABLE_TRANSMITTER UCSR0B |= 1 << TXEN0`
- `#define USART0_DISABLE_TRANSMITTER UCSR0B &= ~(1 << TXEN0)`
- `#define USART0_ENABLE_RECEIVER UCSR0B |= 1 << RXEN0`
- `#define USART0_DISABLE_RECEIVER UCSR0B &= ~(1 << RXEN0)`
- `#define USART0_CONTROL_STATUS_REGISTER UCSR0A`
- `#define USART0_DATA_REGISTER UDR0`
- `#define USART0_FRAME_ERROR FE0`

- #define `USART0_DATA_OVERRUN` DOR0
- #define `USART0_PARITY_ERROR` UPE0
- #define `USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT` UCSR0B |= 1 << UDRIE0
- #define `USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT` UCSR0B &= ~(1 << UDRIE0)
- #define `USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT` UCSR0B |= 1 << RXCIE0
- #define `USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT` UCSR0B &= ~(1 << RXCIE0)
- #define `USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT` UCSR0B |= 1 << TXCIE0
- #define `USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT` UCSR0B &= ~(1 << TXCIE0)
- #define `USART0_RECEIVE_COMPLETE_INTERRUPT` USART_RX_vect
- #define `USART0_TRANSMIT_COMPLETE_INTERRUPT` USART_TX_vect
- #define `USART0_DATA_REGISTER_EMPTY_INTERRUPT` USART_UDRE_vect
- #define `ADC_SELECT_REF_VOLTAGE`(refVoltage) ADMUX &= 0x3F; ADMUX |= refVoltage << 6
- #define `ADC_ADJUST_RESULT_LEFT` ADMUX |= 1 << ADLAR
- #define `ADC_ADJUST_RESULT_RIGHT` ADMUX &= ~(1 << ADLAR)
- #define `ADC_SELECT_ANALOG_INPUT`(pinNumber) ADMUX &= 0xF0; ADMUX |= pinNumber
- #define `ADC_DISABLE_DIGITAL_INPUT_REGISTER`(pinNumber) DIDR0 &= 0xC0; DIDR0 |= pinNumber
- #define `ADC_ENABLE` ADCSRA |= 1 << ADEN
- #define `ADC_DISABLE` ADCSRA &= ~(1 << ADEN)
- #define `ADC_START_CONVERSION` ADCSRA |= 1 << ADSC
- #define `ADC_STOP_CONVERSION` ADCSRA &= ~(1 << ADSC)
- #define `ADC_ENABLE_AUTOTRIGGER` ADCSRA |= 1 << ADIF
- #define `ADC_DISABLE_AUTOTRIGGER` ADCSRA &= ~(1 << ADIF)
- #define `ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT` ADCSRA |= 1 << ADIF
- #define `ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT` ADCSRA &= ~(1 << ADIF)
- #define `ADC_SELECT_CLOCK_PRESCALER`(clockPrescaler) ADCSRA &= 0xF8; ADCSRA |= clockPrescaler
- #define `ADC_SELECT_AUTO_TRIGGER_SOURCE`(triggerSource) ADCSRB &= 0xF8; ADCSRB |= triggerSource
- #define `ADC_CONVERSION_COMPLETE_INTERRUPT` ADC_vect
- #define `EXT_INT_SET_INT0_SENSE_CONTROL`(senseControl) EICRA &= 0xFC; EICRA |= senseControl
- #define `EXT_INT_SET_INT1_SENSE_CONTROL`(senseControl) EICRA &= 0xF3; EICRA |= senseControl
- #define `EXT_INT_ENABLE_INT0` EIMSK |= 1 << INT0
- #define `EXT_INT_DISABLE_INT0` EIMSK &= ~(1 << INT0)
- #define `EXT_INT_ENABLE_INT1` EIMSK |= 1 << INT1
- #define `EXT_INT_DISABLE_INT1` EIMSK &= ~(1 << INT1)
- #define `EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT`(pinChangePort) PCICR |= 1 << pinChangePort
- #define `EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT`(pinChangePort) PCICR &= ~(1 << pinChangePort)
- #define `EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB`(pinChangePin) PCMSK0 |= 1 << pinChangePin
- #define `EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTB`(pinChangePin) PCMSK0 &= ~(1 << pinChangePin)
- #define `EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC`(pinChangePin) PCMSK1 |= 1 << pinChangePin
- #define `EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTC`(pinChangePin) PCMSK1 &= ~(1 << pinChangePin)
- #define `EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD`(pinChangePin) PCMSK2 |= 1 << pinChangePin
- #define `EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTD`(pinChangePin) PCMSK2 &= ~(1 << pinChangePin)
- #define `EXT_INT_INT0_INTERRUPT` INT0_vect
- #define `EXT_INT_INT1_INTERRUPT` INT1_vect
- #define `EXT_INT_PIN_CHANGE_PORTB_INTERRUPT` PCINT0_vect
- #define `EXT_INT_PIN_CHANGE_PORTC_INTERRUPT` PCINT1_vect
- #define `EXT_INT_PIN_CHANGE_PORTD_INTERRUPT` PCINT2_vect

- `#define TIMER0_STOP TCCR0B &= 0xF8`
- `#define TIMER1_STOP TCCR1B &= 0xF8`
- `#define TIMER2_STOP TCCR2B &= 0xF8`
- `#define TIMER0_SELECT_CLOCK_SOURCE(clockSource) TCCR0B &= 0xF8; TCCR0B |= clockSource`
- `#define TIMER1_SELECT_CLOCK_SOURCE(clockSource) TCCR1B &= 0xF8; TCCR1B |= clockSource`
- `#define TIMER2_SELECT_CLOCK_SOURCE(clockSource) TCCR2B &= 0xF8; TCCR2B |= clockSource`
- `#define TIMER0_SELECT_OPERATION_MODE(operationMode) TCCR0A &= 0xFC; TCCR0A |= (operationMode & 3); TCCR0B &= 0xF7; TCCR0B |= (operationMode & 12) << 1`
- `#define TIMER1_SELECT_OPERATION_MODE(operationMode) TCCR1A &= 0xFC; TCCR1A |= (operationMode & 3); TCCR1B &= 0xE7; TCCR1B |= (operationMode & 12) << 1`
- `#define TIMER2_SELECT_OPERATION_MODE(operationMode) TCCR2A &= 0xFC; TCCR2A |= (operationMode & 3); TCCR2B &= 0xF7; TCCR2B |= (operationMode & 12) << 1`
- `#define TIMER0_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR0A &= 0x3F; TCCR0A |= compareOutputMode << 6`
- `#define TIMER0_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR0A &= 0xCF; TCCR0A |= compareOutputMode << 4`
- `#define TIMER1_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR1A &= 0x3F; TCCR1A |= compareOutputMode << 6`
- `#define TIMER1_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR1A &= 0xCF; TCCR1A |= compareOutputMode << 4`
- `#define TIMER2_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR2A &= 0x3F; TCCR2A |= compareOutputMode << 6`
- `#define TIMER2_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR2A &= 0xCF; TCCR2A |= compareOutputMode << 4`
- `#define TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 |= 1 << OCIE0A`
- `#define TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 &= ~(1 << OCIE0A)`
- `#define TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 |= 1 << OCIE0B`
- `#define TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 &= ~(1 << OCIE0B)`
- `#define TIMER0_ENABLE_OVERFLOW_INTERRUPT TIMSK0 |= 1 << TOIE0`
- `#define TIMER0_DISABLE_OVERFLOW_INTERRUPT TIMSK0 &= ~(1 << TOIE0)`
- `#define TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 |= 1 << OCIE1A`
- `#define TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 &= ~(1 << OCIE1A)`
- `#define TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 |= 1 << OCIE1B`
- `#define TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 &= ~(1 << OCIE1B)`
- `#define TIMER1_ENABLE_OVERFLOW_INTERRUPT TIMSK1 |= 1 << TOIE1`
- `#define TIMER1_DISABLE_OVERFLOW_INTERRUPT TIMSK1 &= ~(1 << TOIE1)`
- `#define TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 |= 1 << ICIE1`
- `#define TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 &= ~(1 << ICIE1)`
- `#define TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 |= 1 << OCIE2A`
- `#define TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 &= ~(1 << OCIE2A)`
- `#define TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 |= 1 << OCIE2B`
- `#define TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 &= ~(1 << OCIE2B)`
- `#define TIMER2_ENABLE_OVERFLOW_INTERRUPT TIMSK2 |= 1 << TOIE2`
- `#define TIMER2_DISABLE_OVERFLOW_INTERRUPT TIMSK2 &= ~(1 << TOIE2)`
- `#define TIMER0_COM_CHANNEL_A_INTERRUPT TIMER0_COMPA_vect`
- `#define TIMER0_COM_CHANNEL_B_INTERRUPT TIMER0_COMPB_vect`
- `#define TIMER0_OVERFLOW_INTERRUPT TIMER0_OVF_vect`
- `#define TIMER1_COM_CHANNEL_A_INTERRUPT TIMER1_COMPA_vect`
- `#define TIMER1_COM_CHANNEL_B_INTERRUPT TIMER1_COMPB_vect`
- `#define TIMER1_OVERFLOW_INTERRUPT TIMER1_OVF_vect`
- `#define TIMER1_INPUT_CAPTURE_INTERRUPT TIMER1_CAPT_vect`
- `#define TIMER2_COM_CHANNEL_A_INTERRUPT TIMER2_COMPA_vect`
- `#define TIMER2_COM_CHANNEL_B_INTERRUPT TIMER2_COMPB_vect`
- `#define TIMER2_OVERFLOW_INTERRUPT TIMER2_OVF_vect`

- #define [WATCHDOG_SELECT_TIMEOUT](#)(timeOut) WDTCSR |= (1<<WDCE) | (1<<WDE); WDTCSR = (0<<WDIE) | (0<<WDE) | timeOut;
- #define [WATCHDOG_START](#)(operationMode, timeOut) MCUSR &= ~(1<<WDRF); WDTCSR |= (1<<WDCE) | (1<<WDE); WDTCSR = operationMode | timeOut;
- #define [WATCHDOG_STOP](#) MCUSR &= ~(1<<WDRF); WDTCSR |= (1<<WDCE) | (1<<WDE); WDTCSR = 0x00;
- #define [WATCHDOG_TIMEOUT_INTERRUPT](#) WDT_vect
- #define [MCU_SELECT_SLEEP_MODE](#)(sleepMode) SMCR &= 0xF1; SMCR |= sleepMode << 1
- #define [MCU_SLEEP_ENABLE](#) SMCR |= 1 << SE
- #define [MCU_SLEEP_DISABLE](#) SMCR &= ~(1 << SE)
- #define [MCU_TWI_ENABLE](#) PRR &= ~(1 << PRTWI)
- #define [MCU_TWI_DISABLE](#) PRR |= 1 << PRTWI
- #define [MCU_TIMER2_ENABLE](#) PRR &= ~(1 << PRTIM2)
- #define [MCU_TIMER2_DISABLE](#) PRR |= 1 << PRTIM2
- #define [MCU_TIMER1_ENABLE](#) PRR &= ~(1 << PRTIM1)
- #define [MCU_TIMER1_DISABLE](#) PRR |= 1 << PRTIM1
- #define [MCU_TIMER0_ENABLE](#) PRR &= ~(1 << PRTIM0)
- #define [MCU_TIMER0_DISABLE](#) PRR |= 1 << PRTIM0
- #define [MCU_SPI_ENABLE](#) PRR &= ~(1 << PRSPI)
- #define [MCU_SPI_DISABLE](#) PRR |= 1 << PRSPI
- #define [MCU_USART0_ENABLE](#) PRR &= ~(1 << PRUSART0)
- #define [MCU_USART0_DISABLE](#) PRR |= 1 << PRUSART0
- #define [MCU_ADC_ENABLE](#) PRR &= ~(1 << PRADC)
- #define [MCU_ADC_DISABLE](#) PRR |= 1 << PRADC
- #define [MCU_BOD_DISABLE](#) MCUCR |= (1<<BODSE) | (1<<BODS); MCUCR &= ~(1<<BODSE);
- #define [SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT](#)(pulseWidth, clockPrescaler) ((F_CPU/1000000UL) * (pulseWidth/ clockPrescaler))
- #define [SERVOMOTOR_TIMER_ANGLE_COUNT](#)(angle, out_min, out_mid, out_max) (((out_min*(angle - 90L))*(angle - 180L))/16200L + (angle*out_max*(angle - 90L))/16200L - (angle*out_mid*(angle - 180L))/8100L))
- #define [SPI_ENABLE](#) SPCR |= 1 << SPE
- #define [SPI_DISABLE](#) SPCR &= ~(1 << SPE)
- #define [SPI_SELECT_MASTER_MODE](#) SPCR |= 1 << MSTR
- #define [SPI_SELECT_SLAVE_MODE](#) SPCR &= ~(1 << MSTR)
- #define [SPI_SELECT_DATA_MODE](#)(dataMode) SPCR &= 0xF3; SPCR |= dataMode << 2
- #define [SPI_SELECT_CLOCK_PRESCALER](#)(clockPrescaler) SPCR &= 0xFC; SPCR |= (clockPrescaler & 3); SPSR &= 0xFE; SPSR |= (clockPrescaler & 4) >> 2
- #define [SPI_SELECT_DATA_ORDER](#)(dataOrder) SPCR &= 0xDF; SPCR |= dataOrder << 5
- #define [SPI_WRITE_COLLISION](#) WCOL
- #define [SPI_TRANSFER_COMPLETE](#) SPIF
- #define [SPI_MASTER_MODE](#) MSTR
- #define [SPI_CONTROL_REGISTER](#) SPCR
- #define [SPI_DATA_REGISTER](#) SPDR
- #define [SPI_STATUS_REGISTER](#) SPSR
- #define [SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT](#) SPCR |= 1 << SPIE
- #define [SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT](#) SPCR &= ~(1 << SPIE)
- #define [SPI_TRANSFER_COMPLETE_INTERRUPT](#) SPI_STC_vect

7.29.1 Detailed Description

Header file for the hardware abstraction macros of the Atmega328p.

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [ha_m328p.h](#).

7.29.2 Macro Definition Documentation

7.29.2.1 ADC_ADJUST_RESULT_LEFT

```
#define ADC_ADJUST_RESULT_LEFT ADMUX |= 1 << ADLAR
```

Definition at line 126 of file [ha_m328p.h](#).

7.29.2.2 ADC_ADJUST_RESULT_RIGHT

```
#define ADC_ADJUST_RESULT_RIGHT ADMUX &= ~(1 << ADLAR)
```

Definition at line 127 of file [ha_m328p.h](#).

7.29.2.3 ADC_CONVERSION_COMPLETE_INTERRUPT

```
#define ADC_CONVERSION_COMPLETE_INTERRUPT ADC_vect
```

Definition at line 151 of file [ha_m328p.h](#).

7.29.2.4 ADC_DISABLE

```
#define ADC_DISABLE ADCSRA &= ~(1 << ADEN)
```

Definition at line 134 of file [ha_m328p.h](#).

7.29.2.5 ADC_DISABLE_AUTOTRIGGER

```
#define ADC_DISABLE_AUTOTRIGGER ADCSRA &= ~(1 << ADATE)
```

Definition at line 140 of file [ha_m328p.h](#).

7.29.2.6 ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT

```
#define ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT ADCSRA &= ~(1 << ADIE)
```

Definition at line 143 of file [ha_m328p.h](#).

7.29.2.7 ADC_DISABLE_DIGITAL_INPUT_REGISTER

```
#define ADC_DISABLE_DIGITAL_INPUT_REGISTER(  
    pinNumber ) DIDR0 &= 0xC0; DIDR0 |= pinNumber
```

Definition at line 130 of file [ha_m328p.h](#).

7.29.2.8 ADC_ENABLE

```
#define ADC_ENABLE ADCSRA |= 1 << ADEN
```

Definition at line 133 of file [ha_m328p.h](#).

7.29.2.9 ADC_ENABLE_AUTOTRIGGER

```
#define ADC_ENABLE_AUTOTRIGGER ADCSRA |= 1 << ADATE
```

Definition at line 139 of file [ha_m328p.h](#).

7.29.2.10 ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT

```
#define ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT ADCSRA |= 1 << ADIE
```

Definition at line 142 of file [ha_m328p.h](#).

7.29.2.11 ADC_SELECT_ANALOG_INPUT

```
#define ADC_SELECT_ANALOG_INPUT(  
    pinNumber ) ADMUX &= 0xF0; ADMUX |= pinNumber
```

Definition at line 129 of file [ha_m328p.h](#).

7.29.2.12 ADC_SELECT_AUTO_TRIGGER_SOURCE

```
#define ADC_SELECT_AUTO_TRIGGER_SOURCE(  
    triggerSource ) ADCSRB &= 0xF8; ADCSRB |= triggerSource
```

Definition at line 148 of file [ha_m328p.h](#).

7.29.2.13 ADC_SELECT_CLOCK_PRESCALER

```
#define ADC_SELECT_CLOCK_PRESCALER(  
    clockPrescaler ) ADCSRA &= 0xF8; ADCSRA |= clockPrescaler
```

Definition at line 145 of file [ha_m328p.h](#).

7.29.2.14 ADC_SELECT_REF_VOLTAGE

```
#define ADC_SELECT_REF_VOLTAGE(  
    refVoltage ) ADMUX &= 0x3F; ADMUX |= refVoltage << 6
```

Definition at line 124 of file [ha_m328p.h](#).

7.29.2.15 ADC_START_CONVERSION

```
#define ADC_START_CONVERSION ADCSRA |= 1 << ADSC
```

Definition at line 136 of file [ha_m328p.h](#).

7.29.2.16 ADC_STOP_CONVERSION

```
#define ADC_STOP_CONVERSION ADCSRA &= ~(1 << ADSC)
```

Definition at line 137 of file [ha_m328p.h](#).

7.29.2.17 EXT_INT_DISABLE_INT0

```
#define EXT_INT_DISABLE_INT0 EIMSK &= ~(1 << INT0)
```

Definition at line 159 of file [ha_m328p.h](#).

7.29.2.18 EXT_INT_DISABLE_INT1

```
#define EXT_INT_DISABLE_INT1 EIMSK &= ~(1 << INT1)
```

Definition at line 162 of file [ha_m328p.h](#).

7.29.2.19 EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT

```
#define EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT(  
    pinChangePort ) PCICR &= ~(1 << pinChangePort)
```

Definition at line 166 of file [ha_m328p.h](#).

7.29.2.20 EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTB

```
#define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTB(  
    pinChangePin ) PCMSK0 &= ~(1 << pinChangePin)
```

Definition at line 170 of file [ha_m328p.h](#).

7.29.2.21 EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTC

```
#define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTC(  
    pinChangePin ) PCMSK1 &= ~(1 << pinChangePin)
```

Definition at line 173 of file [ha_m328p.h](#).

7.29.2.22 EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTD

```
#define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTD(  
    pinChangePin ) PCMSK2 &= ~(1 << pinChangePin)
```

Definition at line 176 of file [ha_m328p.h](#).

7.29.2.23 EXT_INT_ENABLE_INT0

```
#define EXT_INT_ENABLE_INT0 EIMSK |= 1 << INT0
```

Definition at line 158 of file [ha_m328p.h](#).

7.29.2.24 EXT_INT_ENABLE_INT1

```
#define EXT_INT_ENABLE_INT1 EIMSK |= 1 << INT1
```

Definition at line 161 of file [ha_m328p.h](#).

7.29.2.25 EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT

```
#define EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT(  
    pinChangePort ) PCICR |= 1 << pinChangePort
```

Definition at line 165 of file [ha_m328p.h](#).

7.29.2.26 EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB

```
#define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(  
    pinChangePin ) PCMSK0 |= 1 << pinChangePin
```

Definition at line 169 of file [ha_m328p.h](#).

7.29.2.27 EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC

```
#define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(  
    pinChangePin ) PCMSK1 |= 1 << pinChangePin
```

Definition at line 172 of file [ha_m328p.h](#).

7.29.2.28 EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD

```
#define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(  
    pinChangePin ) PCMSK2 |= 1 << pinChangePin
```

Definition at line 175 of file [ha_m328p.h](#).

7.29.2.29 EXT_INT_INT0_INTERRUPT

```
#define EXT_INT_INT0_INTERRUPT INT0_vect
```

Definition at line 179 of file [ha_m328p.h](#).

7.29.2.30 EXT_INT_INT1_INTERRUPT

```
#define EXT_INT_INT1_INTERRUPT INT1_vect
```

Definition at line 180 of file [ha_m328p.h](#).

7.29.2.31 EXT_INT_PIN_CHANGE_PORTB_INTERRUPT

```
#define EXT_INT_PIN_CHANGE_PORTB_INTERRUPT PCINT0_vect
```

Definition at line 182 of file [ha_m328p.h](#).

7.29.2.32 EXT_INT_PIN_CHANGE_PORTC_INTERRUPT

```
#define EXT_INT_PIN_CHANGE_PORTC_INTERRUPT PCINT1_vect
```

Definition at line 183 of file [ha_m328p.h](#).

7.29.2.33 EXT_INT_PIN_CHANGE_PORTD_INTERRUPT

```
#define EXT_INT_PIN_CHANGE_PORTD_INTERRUPT PCINT2_vect
```

Definition at line 184 of file [ha_m328p.h](#).

7.29.2.34 EXT_INT_SET_INT0_SENSE_CONTROL

```
#define EXT_INT_SET_INT0_SENSE_CONTROL(  
    senseControl ) EICRA &= 0xFC; EICRA |= senseControl
```

Definition at line 155 of file [ha_m328p.h](#).

7.29.2.35 EXT_INT_SET_INT1_SENSE_CONTROL

```
#define EXT_INT_SET_INT1_SENSE_CONTROL(  
    senseControl ) EICRA &= 0xF3; EICRA |= senseControl
```

Definition at line 156 of file [ha_m328p.h](#).

7.29.2.36 MCU_ADC_DISABLE

```
#define MCU_ADC_DISABLE PRR |= 1 << PRADC
```

Definition at line 286 of file [ha_m328p.h](#).

7.29.2.37 MCU_ADC_ENABLE

```
#define MCU_ADC_ENABLE PRR &= ~(1 << PRADC)
```

Definition at line 285 of file [ha_m328p.h](#).

7.29.2.38 MCU_BOD_DISABLE

```
#define MCU_BOD_DISABLE MCUCR |= (1<<BODSE) | (1<<BODS); MCUCR &= ~(1<<BODSE);
```

Definition at line 288 of file [ha_m328p.h](#).

7.29.2.39 MCU_SELECT_SLEEP_MODE

```
#define MCU_SELECT_SLEEP_MODE(  
    sleepMode ) SMCR &= 0xF1; SMCR |= sleepMode << 1
```

Definition at line 262 of file [ha_m328p.h](#).

7.29.2.40 MCU_SLEEP_DISABLE

```
#define MCU_SLEEP_DISABLE SMCR &= ~(1 << SE)
```

Definition at line 265 of file [ha_m328p.h](#).

7.29.2.41 MCU_SLEEP_ENABLE

```
#define MCU_SLEEP_ENABLE SMCR |= 1 << SE
```

Definition at line 264 of file [ha_m328p.h](#).

7.29.2.42 MCU_SPI_DISABLE

```
#define MCU_SPI_DISABLE PRR |= 1 << PRSPI
```

Definition at line 280 of file [ha_m328p.h](#).

7.29.2.43 MCU_SPI_ENABLE

```
#define MCU_SPI_ENABLE PRR &= ~(1 << PRSPI)
```

Definition at line 279 of file [ha_m328p.h](#).

7.29.2.44 MCU_TIMER0_DISABLE

```
#define MCU_TIMER0_DISABLE PRR |= 1 << PRTIM0
```

Definition at line 277 of file [ha_m328p.h](#).

7.29.2.45 MCU_TIMER0_ENABLE

```
#define MCU_TIMER0_ENABLE PRR &= ~(1 << PRTIM0)
```

Definition at line 276 of file [ha_m328p.h](#).

7.29.2.46 MCU_TIMER1_DISABLE

```
#define MCU_TIMER1_DISABLE PRR |= 1 << PRTIM1
```

Definition at line 274 of file [ha_m328p.h](#).

7.29.2.47 MCU_TIMER1_ENABLE

```
#define MCU_TIMER1_ENABLE PRR &= ~(1 << PRTIM1)
```

Definition at line 273 of file [ha_m328p.h](#).

7.29.2.48 MCU_TIMER2_DISABLE

```
#define MCU_TIMER2_DISABLE PRR |= 1 << PRTIM2
```

Definition at line 271 of file [ha_m328p.h](#).

7.29.2.49 MCU_TIMER2_ENABLE

```
#define MCU_TIMER2_ENABLE PRR &= ~(1 << PRTIM2)
```

Definition at line 270 of file [ha_m328p.h](#).

7.29.2.50 MCU_TWI_DISABLE

```
#define MCU_TWI_DISABLE PRR |= 1 << PRTWI
```

Definition at line 268 of file [ha_m328p.h](#).

7.29.2.51 MCU_TWI_ENABLE

```
#define MCU_TWI_ENABLE PRR &= ~(1 << PRTWI)
```

Definition at line 267 of file [ha_m328p.h](#).

7.29.2.52 MCU_USART0_DISABLE

```
#define MCU_USART0_DISABLE PRR |= 1 << PRUSART0
```

Definition at line 283 of file [ha_m328p.h](#).

7.29.2.53 MCU_USART0_ENABLE

```
#define MCU_USART0_ENABLE PRR &= ~(1 << PRUSART0)
```

Definition at line 282 of file [ha_m328p.h](#).

7.29.2.54 PUSHBUTTON_DEBOUNCE_TIME_US

```
#define PUSHBUTTON_DEBOUNCE_TIME_US 1000
```

Definition at line 16 of file [ha_m328p.h](#).

7.29.2.55 PUSHBUTTON_SAMPLING

```
#define PUSHBUTTON_SAMPLING 12
```

Definition at line 17 of file [ha_m328p.h](#).

7.29.2.56 SERVOMOTOR_TIMER_ANGLE_COUNT

```
#define SERVOMOTOR_TIMER_ANGLE_COUNT(  
    angle,  
    out_min,  
    out_mid,  
    out_max ) (((out_min*(angle - 90L)*(angle - 180L))/16200L + (angle*out_max*(angle  
- 90L))/16200L - (angle*out_mid*(angle - 180L))/8100L))
```

Definition at line 295 of file [ha_m328p.h](#).

7.29.2.57 SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT

```
#define SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(  
    pulseWidth,  
    clockPrescaler ) ((F_CPU/1000000UL) * (pulseWidth/ clockPrescaler))
```

Definition at line 293 of file [ha_m328p.h](#).

7.29.2.58 SPI_CONTROL_REGISTER

```
#define SPI_CONTROL_REGISTER SPCR
```

Definition at line 313 of file [ha_m328p.h](#).

7.29.2.59 SPI_DATA_REGISTER

```
#define SPI_DATA_REGISTER SPDR
```

Definition at line 314 of file [ha_m328p.h](#).

7.29.2.60 SPI_DISABLE

```
#define SPI_DISABLE SPCR &= ~(1 << SPE)
```

Definition at line 300 of file [ha_m328p.h](#).

7.29.2.61 SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT

```
#define SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT SPCR &= ~(1 << SPIE)
```

Definition at line 318 of file [ha_m328p.h](#).

7.29.2.62 SPI_ENABLE

```
#define SPI_ENABLE SPCR |= 1 << SPE
```

Definition at line 299 of file [ha_m328p.h](#).

7.29.2.63 SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT

```
#define SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT SPCR |= 1 << SPIE
```

Definition at line 317 of file [ha_m328p.h](#).

7.29.2.64 SPI_MASTER_MODE

```
#define SPI_MASTER_MODE MSTR
```

Definition at line 312 of file [ha_m328p.h](#).

7.29.2.65 SPI_SELECT_CLOCK_PRESCALER

```
#define SPI_SELECT_CLOCK_PRESCALER(  
    clockPrescaler ) SPCR &= 0xFC; SPCR |= (clockPrescaler & 3); SPSR &= 0xFE; SPSR |=  
(clockPrescaler & 4) >> 2
```

Definition at line 306 of file [ha_m328p.h](#).

7.29.2.66 SPI_SELECT_DATA_MODE

```
#define SPI_SELECT_DATA_MODE(  
    dataMode ) SPCR &= 0xF3; SPCR |= dataMode << 2
```

Definition at line 305 of file [ha_m328p.h](#).

7.29.2.67 SPI_SELECT_DATA_ORDER

```
#define SPI_SELECT_DATA_ORDER(  
    dataOrder ) SPCR &= 0xDF; SPCR |= dataOrder << 5
```

Definition at line 307 of file [ha_m328p.h](#).

7.29.2.68 SPI_SELECT_MASTER_MODE

```
#define SPI_SELECT_MASTER_MODE SPCR |= 1 << MSTR
```

Definition at line 301 of file [ha_m328p.h](#).

7.29.2.69 SPI_SELECT_SLAVE_MODE

```
#define SPI_SELECT_SLAVE_MODE SPCR &= ~(1 << MSTR)
```

Definition at line 302 of file [ha_m328p.h](#).

7.29.2.70 SPI_STATUS_REGISTER

```
#define SPI_STATUS_REGISTER SPSR
```

Definition at line 315 of file [ha_m328p.h](#).

7.29.2.71 SPI_TRANSFER_COMPLETE

```
#define SPI_TRANSFER_COMPLETE SPIF
```

Definition at line 310 of file [ha_m328p.h](#).

7.29.2.72 SPI_TRANSFER_COMPLETE_INTERRUPT

```
#define SPI_TRANSFER_COMPLETE_INTERRUPT SPI_STC_vect
```

Definition at line 321 of file [ha_m328p.h](#).

7.29.2.73 SPI_WRITE_COLLISION

```
#define SPI_WRITE_COLLISION WCOL
```

Definition at line 309 of file [ha_m328p.h](#).

7.29.2.74 TIMER0_COM_CHANNEL_A_INTERRUPT

```
#define TIMER0_COM_CHANNEL_A_INTERRUPT TIMER0_COMPA_vect
```

Definition at line 239 of file [ha_m328p.h](#).

7.29.2.75 TIMER0_COM_CHANNEL_B_INTERRUPT

```
#define TIMER0_COM_CHANNEL_B_INTERRUPT TIMER0_COMPB_vect
```

Definition at line 240 of file [ha_m328p.h](#).

7.29.2.76 TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 &= ~(1 << OCIE0A)
```

Definition at line 210 of file [ha_m328p.h](#).

7.29.2.77 TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 &= ~(1 << OCIE0B)
```

Definition at line 213 of file [ha_m328p.h](#).

7.29.2.78 TIMER0_DISABLE_OVERFLOW_INTERRUPT

```
#define TIMER0_DISABLE_OVERFLOW_INTERRUPT TIMSK0 &= ~(1 << TOIE0)
```

Definition at line 216 of file [ha_m328p.h](#).

7.29.2.79 TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 |= 1 << OCIE0A
```

Definition at line 209 of file [ha_m328p.h](#).

7.29.2.80 TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 |= 1 << OCIE0B
```

Definition at line 212 of file [ha_m328p.h](#).

7.29.2.81 TIMER0_ENABLE_OVERFLOW_INTERRUPT

```
#define TIMER0_ENABLE_OVERFLOW_INTERRUPT TIMSK0 |= 1 << TOIE0
```

Definition at line 215 of file [ha_m328p.h](#).

7.29.2.82 TIMER0_OVERFLOW_INTERRUPT

```
#define TIMER0_OVERFLOW_INTERRUPT TIMER0_OVF_vect
```

Definition at line 241 of file [ha_m328p.h](#).

7.29.2.83 TIMER0_SELECT_CLOCK_SOURCE

```
#define TIMER0_SELECT_CLOCK_SOURCE(  
    clockSource ) TCCR0B &= 0xF8; TCCR0B |= clockSource
```

Definition at line 192 of file [ha_m328p.h](#).

7.29.2.84 TIMER0_SELECT_COM_CHANNEL_A

```
#define TIMER0_SELECT_COM_CHANNEL_A(  
    compareOutputMode ) TCCR0A &= 0x3F; TCCR0A |= compareOutputMode << 6
```

Definition at line 200 of file [ha_m328p.h](#).

7.29.2.85 TIMER0_SELECT_COM_CHANNEL_B

```
#define TIMER0_SELECT_COM_CHANNEL_B(  
    compareOutputMode ) TCCR0A &= 0xCF; TCCR0A |= compareOutputMode << 4
```

Definition at line 201 of file [ha_m328p.h](#).

7.29.2.86 TIMER0_SELECT_OPERATION_MODE

```
#define TIMER0_SELECT_OPERATION_MODE(  
    operationMode ) TCCR0A &= 0xFC; TCCR0A |= (operationMode & 3); TCCR0B &= 0xF7;  
TCCR0B |= (operationMode & 12) << 1
```

Definition at line 196 of file [ha_m328p.h](#).

7.29.2.87 TIMER0_STOP

```
#define TIMER0_STOP TCCR0B &= 0xF8
```

Definition at line 188 of file [ha_m328p.h](#).

7.29.2.88 TIMER1_COM_CHANNEL_A_INTERRUPT

```
#define TIMER1_COM_CHANNEL_A_INTERRUPT TIMER1_COMPA_vect
```

Definition at line 243 of file [ha_m328p.h](#).

7.29.2.89 TIMER1_COM_CHANNEL_B_INTERRUPT

```
#define TIMER1_COM_CHANNEL_B_INTERRUPT TIMER1_COMPB_vect
```

Definition at line 244 of file [ha_m328p.h](#).

7.29.2.90 TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 &= ~(1 << OCIE1A)
```

Definition at line 219 of file [ha_m328p.h](#).

7.29.2.91 TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 &= ~(1 << OCIE1B)
```

Definition at line 222 of file [ha_m328p.h](#).

7.29.2.92 TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT

```
#define TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 &= ~(1 << ICIE1)
```

Definition at line 228 of file [ha_m328p.h](#).

7.29.2.93 TIMER1_DISABLE_OVERFLOW_INTERRUPT

```
#define TIMER1_DISABLE_OVERFLOW_INTERRUPT TIMSK1 &= ~(1 << TOIE1)
```

Definition at line 225 of file [ha_m328p.h](#).

7.29.2.94 TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 |= 1 << OCIE1A
```

Definition at line 218 of file [ha_m328p.h](#).

7.29.2.95 TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 |= 1 << OCIE1B
```

Definition at line 221 of file [ha_m328p.h](#).

7.29.2.96 TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT

```
#define TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 |= 1 << ICIE1
```

Definition at line 227 of file [ha_m328p.h](#).

7.29.2.97 TIMER1_ENABLE_OVERFLOW_INTERRUPT

```
#define TIMER1_ENABLE_OVERFLOW_INTERRUPT TIMSK1 |= 1 << TOIE1
```

Definition at line 224 of file [ha_m328p.h](#).

7.29.2.98 TIMER1_INPUT_CAPTURE_INTERRUPT

```
#define TIMER1_INPUT_CAPTURE_INTERRUPT TIMER1_CAPT_vect
```

Definition at line 246 of file [ha_m328p.h](#).

7.29.2.99 TIMER1_OVERFLOW_INTERRUPT

```
#define TIMER1_OVERFLOW_INTERRUPT TIMER1_OVF_vect
```

Definition at line 245 of file [ha_m328p.h](#).

7.29.2.100 TIMER1_SELECT_CLOCK_SOURCE

```
#define TIMER1_SELECT_CLOCK_SOURCE(  
    clockSource ) TCCR1B &= 0xF8; TCCR1B |= clockSource
```

Definition at line 193 of file [ha_m328p.h](#).

7.29.2.101 TIMER1_SELECT_COM_CHANNEL_A

```
#define TIMER1_SELECT_COM_CHANNEL_A(  
    compareOutputMode ) TCCR1A &= 0x3F; TCCR1A |= compareOutputMode << 6
```

Definition at line 203 of file [ha_m328p.h](#).

7.29.2.102 TIMER1_SELECT_COM_CHANNEL_B

```
#define TIMER1_SELECT_COM_CHANNEL_B(  
    compareOutputMode ) TCCR1A &= 0xCF; TCCR1A |= compareOutputMode << 4
```

Definition at line 204 of file [ha_m328p.h](#).

7.29.2.103 TIMER1_SELECT_OPERATION_MODE

```
#define TIMER1_SELECT_OPERATION_MODE(  
    operationMode ) TCCR1A &= 0xFC; TCCR1A |= (operationMode & 3); TCCR1B &= 0xE7;  
TCCR1B |= (operationMode & 12) << 1
```

Definition at line 197 of file [ha_m328p.h](#).

7.29.2.104 TIMER1_STOP

```
#define TIMER1_STOP TCCR1B &= 0xF8
```

Definition at line 189 of file [ha_m328p.h](#).

7.29.2.105 TIMER2_COM_CHANNEL_A_INTERRUPT

```
#define TIMER2_COM_CHANNEL_A_INTERRUPT TIMER2_COMPA_vect
```

Definition at line 248 of file [ha_m328p.h](#).

7.29.2.106 TIMER2_COM_CHANNEL_B_INTERRUPT

```
#define TIMER2_COM_CHANNEL_B_INTERRUPT TIMER2_COMPB_vect
```

Definition at line 249 of file [ha_m328p.h](#).

7.29.2.107 TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 &= ~(1 << OCIE2A)
```

Definition at line 231 of file [ha_m328p.h](#).

7.29.2.108 TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 &= ~(1 << OCIE2B)
```

Definition at line 234 of file [ha_m328p.h](#).

7.29.2.109 TIMER2_DISABLE_OVERFLOW_INTERRUPT

```
#define TIMER2_DISABLE_OVERFLOW_INTERRUPT TIMSK2 &= ~(1 << TOIE2)
```

Definition at line 237 of file [ha_m328p.h](#).

7.29.2.110 TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT

```
#define TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 |= 1 << OCIE2A
```

Definition at line 230 of file [ha_m328p.h](#).

7.29.2.111 TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT

```
#define TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 |= 1 << OCIE2B
```

Definition at line 233 of file [ha_m328p.h](#).

7.29.2.112 TIMER2_ENABLE_OVERFLOW_INTERRUPT

```
#define TIMER2_ENABLE_OVERFLOW_INTERRUPT TIMSK2 |= 1 << TOIE2
```

Definition at line 236 of file [ha_m328p.h](#).

7.29.2.113 TIMER2_OVERFLOW_INTERRUPT

```
#define TIMER2_OVERFLOW_INTERRUPT TIMER2_OVF_vect
```

Definition at line 250 of file [ha_m328p.h](#).

7.29.2.114 TIMER2_SELECT_CLOCK_SOURCE

```
#define TIMER2_SELECT_CLOCK_SOURCE(  
    clockSource ) TCCR2B &= 0xF8; TCCR2B |= clockSource
```

Definition at line 194 of file [ha_m328p.h](#).

7.29.2.115 TIMER2_SELECT_COM_CHANNEL_A

```
#define TIMER2_SELECT_COM_CHANNEL_A(  
    compareOutputMode ) TCCR2A &= 0x3F; TCCR2A |= compareOutputMode << 6
```

Definition at line 206 of file [ha_m328p.h](#).

7.29.2.116 TIMER2_SELECT_COM_CHANNEL_B

```
#define TIMER2_SELECT_COM_CHANNEL_B(  
    compareOutputMode ) TCCR2A &= 0xCF; TCCR2A |= compareOutputMode << 4
```

Definition at line 207 of file [ha_m328p.h](#).

7.29.2.117 TIMER2_SELECT_OPERATION_MODE

```
#define TIMER2_SELECT_OPERATION_MODE(  
    operationMode ) TCCR2A &= 0xFC; TCCR2A |= (operationMode & 3); TCCR2B &= 0xF7;  
TCCR2B |= (operationMode & 12) << 1
```

Definition at line 198 of file [ha_m328p.h](#).

7.29.2.118 TIMER2_STOP

```
#define TIMER2_STOP TCCR2B &= 0xF8
```

Definition at line 190 of file [ha_m328p.h](#).

7.29.2.119 USART0_CONTROL_STATUS_REGISTER

```
#define USART0_CONTROL_STATUS_REGISTER UCSR0A
```

Definition at line 91 of file [ha_m328p.h](#).

7.29.2.120 USART0_DATA_OVERRUN

```
#define USART0_DATA_OVERRUN DOR0
```

Definition at line 99 of file [ha_m328p.h](#).

7.29.2.121 USART0_DATA_REGISTER

```
#define USART0_DATA_REGISTER UDR0
```

Definition at line 92 of file [ha_m328p.h](#).

7.29.2.122 USART0_DATA_REGISTER_EMPTY_INTERRUPT

```
#define USART0_DATA_REGISTER_EMPTY_INTERRUPT USART_UDRE_vect
```

Definition at line 119 of file [ha_m328p.h](#).

7.29.2.123 USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT

```
#define USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT UCSR0B &= ~(1 << UDRIE0)
```

Definition at line 105 of file [ha_m328p.h](#).

7.29.2.124 USART0_DISABLE_DOUBLE_SPEED_MODE [1/2]

```
#define USART0_DISABLE_DOUBLE_SPEED_MODE
```

Definition at line 40 of file [ha_m328p.h](#).

7.29.2.125 USART0_DISABLE_DOUBLE_SPEED_MODE [2/2]

```
#define USART0_DISABLE_DOUBLE_SPEED_MODE UCSRA &= ~(1 << U2X0)
```

Definition at line 40 of file [ha_m328p.h](#).

7.29.2.126 USART0_DISABLE_PARITY_MODE

```
#define USART0_DISABLE_PARITY_MODE UCSRC &= ~((1 << UPM01) | (1 << UPM00))
```

Definition at line 45 of file [ha_m328p.h](#).

7.29.2.127 USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT

```
#define USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT UCSRB &= ~(1 << RXCIE0)
```

Definition at line 108 of file [ha_m328p.h](#).

7.29.2.128 USART0_DISABLE_RECEIVER

```
#define USART0_DISABLE_RECEIVER UCSRB &= ~(1 << RXEN0)
```

Definition at line 87 of file [ha_m328p.h](#).

7.29.2.129 USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT

```
#define USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT UCSRB &= ~(1 << TXCIE0)
```

Definition at line 111 of file [ha_m328p.h](#).

7.29.2.130 USART0_DISABLE_TRANSMITTER

```
#define USART0_DISABLE_TRANSMITTER UCSRB &= ~(1 << TXEN0)
```

Definition at line 82 of file [ha_m328p.h](#).

7.29.2.131 USART0_ENABLE_ASYNC_TRANSMISSION_MODE

```
#define USART0_ENABLE_ASYNC_TRANSMISSION_MODE UCSRC &= ~( (1 << UMSEL01) | (1 << UMSEL00) )
```

Definition at line 26 of file [ha_m328p.h](#).

7.29.2.132 USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT

```
#define USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT UCSRB |= 1 << UDRIE0
```

Definition at line 104 of file [ha_m328p.h](#).

7.29.2.133 USART0_ENABLE_DOUBLE_SPEED_MODE

```
#define USART0_ENABLE_DOUBLE_SPEED_MODE
```

Definition at line 31 of file [ha_m328p.h](#).

7.29.2.134 USART0_ENABLE_EVEN_PARITY_MODE

```
#define USART0_ENABLE_EVEN_PARITY_MODE UCSRC = (1 << UPM01) | (UCSRC & ~(1 << UPM00))
```

Definition at line 43 of file [ha_m328p.h](#).

7.29.2.135 USART0_ENABLE_MASTER_SPI_MODE

```
#define USART0_ENABLE_MASTER_SPI_MODE UCSRC |= (1 << UMSEL01) | (1 << UMSEL00)
```

Definition at line 28 of file [ha_m328p.h](#).

7.29.2.136 USART0_ENABLE_ODD_PARITY_MODE

```
#define USART0_ENABLE_ODD_PARITY_MODE UCSR0C |= ((1 << UPM01) | (1 << UPM00))
```

Definition at line 44 of file [ha_m328p.h](#).

7.29.2.137 USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT

```
#define USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT UCSR0B |= 1 << RXCIE0
```

Definition at line 107 of file [ha_m328p.h](#).

7.29.2.138 USART0_ENABLE_RECEIVER

```
#define USART0_ENABLE_RECEIVER UCSR0B |= 1 << RXEN0
```

Definition at line 86 of file [ha_m328p.h](#).

7.29.2.139 USART0_ENABLE_SYNC_TRANSMISSION_MODE

```
#define USART0_ENABLE_SYNC_TRANSMISSION_MODE UCSR0C = (UCSR0C & ~(1 << UMSEL01)) | (1 << UMSEL00)
```

Definition at line 27 of file [ha_m328p.h](#).

7.29.2.140 USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT

```
#define USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT UCSR0B |= 1 << TXCIE0
```

Definition at line 110 of file [ha_m328p.h](#).

7.29.2.141 USART0_ENABLE_TRANSMITTER

```
#define USART0_ENABLE_TRANSMITTER UCSR0B |= 1 << TXEN0
```

Definition at line 81 of file [ha_m328p.h](#).

7.29.2.142 USART0_FRAME_ERROR

```
#define USART0_FRAME_ERROR FE0
```

Definition at line 97 of file [ha_m328p.h](#).

7.29.2.143 USART0_PARITY_ERROR

```
#define USART0_PARITY_ERROR UPE0
```

Definition at line 101 of file [ha_m328p.h](#).

7.29.2.144 USART0_RECEIVE_COMPLETE_INTERRUPT

```
#define USART0_RECEIVE_COMPLETE_INTERRUPT USART_RX_vect
```

Definition at line 115 of file [ha_m328p.h](#).

7.29.2.145 USART0_SET_5BIT_FRAME_SIZE

```
#define USART0_SET_5BIT_FRAME_SIZE
```

Value:

```
do { \
    UCSR0C &= ~( (1 << UCSZ01) | (1 << UCSZ00)); \
    UCSR0B &= ~(1 << UCSZ02); \
} while (0)
```

Definition at line 74 of file [ha_m328p.h](#).

7.29.2.146 USART0_SET_6BIT_FRAME_SIZE

```
#define USART0_SET_6BIT_FRAME_SIZE
```

Value:

```
do { \
    UCSR0C = (UCSR0C & ~(1 << UCSZ01)) | (1 << UCSZ00); \
    UCSR0B &= ~(1 << UCSZ02); \
} while (0)
```

Definition at line 69 of file [ha_m328p.h](#).

7.29.2.147 USART0_SET_7BIT_FRAME_SIZE

```
#define USART0_SET_7BIT_FRAME_SIZE
```

Value:

```
do { \
    UCSR0C = (1 « UCSZ01) | (UCSR0C & ~(1 « UCSZ00)); \
    UCSR0B &= ~(1 « UCSZ02); \
} while (0)
```

Definition at line 64 of file [ha_m328p.h](#).

7.29.2.148 USART0_SET_8BIT_FRAME_SIZE

```
#define USART0_SET_8BIT_FRAME_SIZE
```

Value:

```
do { \
    UCSR0C |= ((1 « UCSZ01) | (1 « UCSZ00)); \
    UCSR0B &= ~(1 « UCSZ02); \
} while (0)
```

Definition at line 58 of file [ha_m328p.h](#).

7.29.2.149 USART0_SET_9BIT_FRAME_SIZE

```
#define USART0_SET_9BIT_FRAME_SIZE
```

Value:

```
do { \
    UCSR0C |= ((1 « UCSZ01) | (1 « UCSZ00)); \
    UCSR0B |= (1 « UCSZ02); \
} while (0)
```

Definition at line 52 of file [ha_m328p.h](#).

7.29.2.150 USART0_SET_BAUDRATE_HIGH_REGISTER

```
#define USART0_SET_BAUDRATE_HIGH_REGISTER UBRR0H = UBRRH_VALUE
```

Definition at line 23 of file [ha_m328p.h](#).

7.29.2.151 USART0_SET_BAUDRATE_LOW_REGISTER

```
#define USART0_SET_BAUDRATE_LOW_REGISTER UBRR0L = UBRRL_VALUE
```

Definition at line 24 of file [ha_m328p.h](#).

7.29.2.152 USART0_SET_ONE_STOP_BIT

```
#define USART0_SET_ONE_STOP_BIT UCSR0C &= ~(1 << USBS0)
```

Definition at line 48 of file [ha_m328p.h](#).

7.29.2.153 USART0_SET_TWO_STOP_BITS

```
#define USART0_SET_TWO_STOP_BITS UCSR0C |= (1 << USBS0)
```

Definition at line 49 of file [ha_m328p.h](#).

7.29.2.154 USART0_TRANSMIT_COMPLETE_INTERRUPT

```
#define USART0_TRANSMIT_COMPLETE_INTERRUPT USART_TX_vect
```

Definition at line 117 of file [ha_m328p.h](#).

7.29.2.155 WATCHDOG_SELECT_TIMEOUT

```
#define WATCHDOG_SELECT_TIMEOUT(  
    timeOut ) WDTCR |= (1<<WDCE) | (1<<WDE); WDTCR = (0<<WDIE) | (0<<WDE) | time←  
Out;
```

Definition at line 254 of file [ha_m328p.h](#).

7.29.2.156 WATCHDOG_START

```
#define WATCHDOG_START(  
    operationMode,  
    timeOut ) MCUSR &= ~(1<<WDRF); WDTCR |= (1<<WDCE) | (1<<WDE); WDTCR = operation←  
Mode | timeOut;
```

Definition at line 255 of file [ha_m328p.h](#).

7.29.2.157 WATCHDOG_STOP

```
#define WATCHDOG_STOP MCUSR &= ~(1<<WDRF); WDTCR |= (1<<WDCE) | (1<<WDE); WDTCR = 0x00;
```

Definition at line 256 of file [ha_m328p.h](#).

7.29.2.158 WATCHDOG_TIMEOUT_INTERRUPT

```
#define WATCHDOG_TIMEOUT_INTERRUPT WDT_vect
```

Definition at line 257 of file [ha_m328p.h](#).

7.30 ha_m328p.h

```
00001
00008 #ifndef HAM329P_H
00009 #define HAM329P_H
00010
00011 #ifndef HABASE_H
00012     #error "don't use this file directly! Please include only ha_base.h!"
00013 #endif
00014
00015 // PushButton defines
00016 #define PUSHBUTTON_DEBOUNCE_TIME_US 1000 // microseconds to wait for next check
00017 #define PUSHBUTTON_SAMPLING 12 // number of times a push button must be pressed
00018
00019
00020 // USART defines
00021 #include <util/setbaud.h>
00022
00023 #define USART0_SET_BAUDRATE_HIGH_REGISTER UBRR0H = UBRRH_VALUE
00024 #define USART0_SET_BAUDRATE_LOW_REGISTER UBRR0L = UBRL_VALUE
00025
00026 #define USART0_ENABLE_ASYNC_TRANSMISSION_MODE UCSR0C &= ~(1 < UMSEL01) | (1 < UMSEL00)
00027 #define USART0_ENABLE_SYNC_TRANSMISSION_MODE UCSR0C = (UCSR0C & ~(1 < UMSEL01)) | (1 < UMSEL00)
00028 #define USART0_ENABLE_MASTER_SPI_MODE UCSR0C |= (1 < UMSEL01) | (1 < UMSEL00)
00029
00030
00031 #define USART0_ENABLE_DOUBLE_SPEED_MODE
00032 #define USART0_DISABLE_DOUBLE_SPEED_MODE
00033
00034 #if USE_2X
00035     #undef USART0_ENABLE_DOUBLE_SPEED_MODE
00036     #define USART0_ENABLE_DOUBLE_SPEED_MODE UCSR0A |= (1 < U2X0)
00037     #warning "double speed operation activated"
00038 #else
00039     #undef USART0_DISABLE_DOUBLE_SPEED_MODE
00040     #define USART0_DISABLE_DOUBLE_SPEED_MODE UCSR0A &= ~(1 < U2X0)
00041 #endif
00042
00043 #define USART0_ENABLE_EVEN_PARITY_MODE UCSR0C = (1 < UPM01) | (UCSR0C & ~(1 < UPM00))
00044 #define USART0_ENABLE_ODD_PARITY_MODE UCSR0C |= ((1 < UPM01) | (1 < UPM00))
00045 #define USART0_DISABLE_PARITY_MODE UCSR0C &= ~(1 < UPM01) | (1 < UPM00)
00046
00047
00048 #define USART0_SET_ONE_STOP_BIT UCSR0C &= ~(1 < USBS0)
00049 #define USART0_SET_TWO_STOP_BITS UCSR0C |= (1 < USBS0)
00050
00051
00052 #define USART0_SET_9BIT_FRAME_SIZE \
00053     do { \
00054         UCSR0C |= ((1 < UCSZ01) | (1 < UCSZ00)); \
00055         UCSR0B |= (1 < UCSZ02); \
00056     } while (0)
00057
00058 #define USART0_SET_8BIT_FRAME_SIZE \
00059     do { \
00060         UCSR0C |= ((1 < UCSZ01) | (1 < UCSZ00)); \
00061         UCSR0B &= ~(1 < UCSZ02); \
00062     } while (0)
00063
00064 #define USART0_SET_7BIT_FRAME_SIZE \
00065     do { \
00066         UCSR0C = (1 < UCSZ01) | (UCSR0C & ~(1 < UCSZ00)); \
00067         UCSR0B &= ~(1 < UCSZ02); \
00068     } while (0)
00069 #define USART0_SET_6BIT_FRAME_SIZE \
00070     do { \
00071         UCSR0C = (UCSR0C & ~(1 < UCSZ01)) | (1 < UCSZ00); \
00072         UCSR0B &= ~(1 < UCSZ02); \
00073     } while (0)
00074 #define USART0_SET_5BIT_FRAME_SIZE \
00075     do { \
00076         UCSR0C &= ~(1 < UCSZ01) | (1 < UCSZ00); \
00077         UCSR0B &= ~(1 < UCSZ02); \
00078     } while (0)
```

```

00079
00080
00081 #define USART0_ENABLE_TRANSMITTER UCSRB |= 1 < TXEN0
00082 #define USART0_DISABLE_TRANSMITTER UCSRB &= ~(1 < TXEN0)
00083
00084
00085
00086 #define USART0_ENABLE_RECEIVER UCSRB |= 1 < RXEN0
00087 #define USART0_DISABLE_RECEIVER UCSRB &= ~(1 < RXEN0)
00088
00089
00090
00091 #define USART0_CONTROL_STATUS_REGISTER UCSRA
00092 #define USART0_DATA_REGISTER UDRO
00093
00094
00095
00096
00097 #define USART0_FRAME_ERROR FE0
00098
00099 #define USART0_DATA_OVERRUN DOR0
00100
00101 #define USART0_PARITY_ERROR UPE0
00102
00103
00104 #define USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT UCSRB |= 1 < UDRIE0
00105 #define USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT UCSRB &= ~(1 < UDRIE0)
00106
00107 #define USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT UCSRB |= 1 < RXCIE0
00108 #define USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT UCSRB &= ~(1 < RXCIE0)
00109
00110 #define USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT UCSRB |= 1 < TXCIE0
00111 #define USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT UCSRB &= ~(1 < TXCIE0)
00112
00113
00114
00115 #define USART0_RECEIVE_COMPLETE_INTERRUPT USART_RX_vect
00116
00117 #define USART0_TRANSMIT_COMPLETE_INTERRUPT USART_TX_vect
00118
00119 #define USART0_DATA_REGISTER_EMPTY_INTERRUPT USART_UDRE_vect
00120
00121
00122 // ADC defines
00123
00124 #define ADC_SELECT_REF_VOLTAGE(refVoltage) ADMUX &= 0x3F; ADMUX |= refVoltage < 6
00125
00126 #define ADC_ADJUST_RESULT_LEFT ADMUX |= 1 < ADLAR
00127 #define ADC_ADJUST_RESULT_RIGHT ADMUX &= ~(1 < ADLAR)
00128
00129 #define ADC_SELECT_ANALOG_INPUT(pinNumber) ADMUX &= 0xF0; ADMUX |= pinNumber
00130 #define ADC_DISABLE_DIGITAL_INPUT_REGISTER(pinNumber) DIDR0 &= 0xC0; DIDR0 |= pinNumber
00131
00132
00133 #define ADC_ENABLE ADCSRA |= 1 < ADEN
00134 #define ADC_DISABLE ADCSRA &= ~(1 < ADEN)
00135
00136 #define ADC_START_CONVERSION ADCSRA |= 1 < ADSC
00137 #define ADC_STOP_CONVERSION ADCSRA &= ~(1 < ADSC)
00138
00139 #define ADC_ENABLE_AUTOTRIGGER ADCSRA |= 1 < ADATE
00140 #define ADC_DISABLE_AUTOTRIGGER ADCSRA &= ~(1 < ADATE)
00141
00142 #define ADC_ENABLE_CONVERSION_COMPLETE_INTERRUPT ADCSRA |= 1 < ADIE
00143 #define ADC_DISABLE_CONVERSION_COMPLETE_INTERRUPT ADCSRA &= ~(1 < ADIE)
00144
00145 #define ADC_SELECT_CLOCK_PRESCALER(clockPrescaler) ADCSRA &= 0xF8; ADCSRA |= clockPrescaler
00146
00147
00148 #define ADC_SELECT_AUTO_TRIGGER_SOURCE(triggerSource) ADCSRB &= 0xF8; ADCSRB |=
    triggerSource
00149
00150
00151 #define ADC_CONVERSION_COMPLETE_INTERRUPT ADC_vect
00152
00153 // Externally Triggered Interrupts defines
00154
00155 #define EXT_INT_SET_INT0_SENSE_CONTROL(senseControl) EICRA &= 0xFC; EICRA |= senseControl
00156 #define EXT_INT_SET_INT1_SENSE_CONTROL(senseControl) EICRA &= 0xF3; EICRA |= senseControl
00157
00158 #define EXT_INT_ENABLE_INT0 EIMSK |= 1 < INT0
00159 #define EXT_INT_DISABLE_INT0 EIMSK &= ~(1 < INT0)
00160
00161 #define EXT_INT_ENABLE_INT1 EIMSK |= 1 < INT1
00162 #define EXT_INT_DISABLE_INT1 EIMSK &= ~(1 < INT1)
00163
00164

```

```

00165 #define EXT_INT_ENABLE_PIN_CHANGE_INTERRUPT(pinChangePort)    PCICR |= 1 « pinChangePort
00166 #define EXT_INT_DISABLE_PIN_CHANGE_INTERRUPT(pinChangePort)    PCICR &= ~(1 « pinChangePort)
00167
00168
00169 #define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTB(pinChangePin)      PCMSK0 |= 1 « pinChangePin
00170 #define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTB(pinChangePin)    PCMSK0 &= ~(1 « pinChangePin)
00171
00172 #define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTC(pinChangePin)      PCMSK1 |= 1 « pinChangePin
00173 #define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTC(pinChangePin)    PCMSK1 &= ~(1 « pinChangePin)
00174
00175 #define EXT_INT_ENABLE_PIN_CHANGE_MASK_PORTD(pinChangePin)      PCMSK2 |= 1 « pinChangePin
00176 #define EXT_INT_DISABLE_PIN_CHANGE_MASK_PORTD(pinChangePin)    PCMSK2 &= ~(1 « pinChangePin)
00177
00178
00179 #define EXT_INT_INT0_INTERRUPT    INT0_vect
00180 #define EXT_INT_INT1_INTERRUPT    INT1_vect
00181
00182 #define EXT_INT_PIN_CHANGE_PORTB_INTERRUPT    PCINT0_vect
00183 #define EXT_INT_PIN_CHANGE_PORTC_INTERRUPT    PCINT1_vect
00184 #define EXT_INT_PIN_CHANGE_PORTD_INTERRUPT    PCINT2_vect
00185
00186 // Timers/Counters defines
00187
00188 #define TIMER0_STOP TCCR0B &= 0xF8
00189 #define TIMER1_STOP TCCR1B &= 0xF8
00190 #define TIMER2_STOP TCCR2B &= 0xF8
00191
00192 #define TIMER0_SELECT_CLOCK_SOURCE(clockSource) TCCR0B &= 0xF8; TCCR0B |= clockSource
00193 #define TIMER1_SELECT_CLOCK_SOURCE(clockSource) TCCR1B &= 0xF8; TCCR1B |= clockSource
00194 #define TIMER2_SELECT_CLOCK_SOURCE(clockSource) TCCR2B &= 0xF8; TCCR2B |= clockSource
00195
00196 #define TIMER0_SELECT_OPERATION_MODE(operationMode) TCCR0A &= 0xFC; TCCR0A |= (operationMode & 3);
00197 #define TIMER1_SELECT_OPERATION_MODE(operationMode) TCCR1A &= 0xFC; TCCR1A |= (operationMode & 3);
00198 #define TIMER2_SELECT_OPERATION_MODE(operationMode) TCCR2A &= 0xFC; TCCR2A |= (operationMode & 3);
00199 #define TCCR0B &= 0xF7; TCCR0B |= (operationMode & 12) « 1
00200 #define TCCR1B &= 0xE7; TCCR1B |= (operationMode & 12) « 1
00201 #define TCCR2B &= 0xF7; TCCR2B |= (operationMode & 12) « 1
00202
00203 #define TIMER0_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR0A &= 0x3F; TCCR0A |= compareOutputMode « 6
00204 #define TIMER0_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR0A &= 0xCF; TCCR0A |= compareOutputMode « 4
00205
00206 #define TIMER1_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR1A &= 0x3F; TCCR1A |= compareOutputMode « 6
00207 #define TIMER1_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR1A &= 0xCF; TCCR1A |= compareOutputMode « 4
00208
00209 #define TIMER2_SELECT_COM_CHANNEL_A(compareOutputMode) TCCR2A &= 0x3F; TCCR2A |= compareOutputMode « 6
00210 #define TIMER2_SELECT_COM_CHANNEL_B(compareOutputMode) TCCR2A &= 0xCF; TCCR2A |= compareOutputMode « 4
00211
00212 #define TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 |= 1 « OCIE0A
00213 #define TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK0 &= ~(1 « OCIE0A)
00214
00215 #define TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 |= 1 « OCIE0B
00216 #define TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK0 &= ~(1 « OCIE0B)
00217
00218 #define TIMER0_ENABLE_OVERFLOW_INTERRUPT TIMSK0 |= 1 « TOIE0
00219 #define TIMER0_DISABLE_OVERFLOW_INTERRUPT TIMSK0 &= ~(1 « TOIE0)
00220
00221 #define TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 |= 1 « OCIE1A
00222 #define TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK1 &= ~(1 « OCIE1A)
00223
00224 #define TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 |= 1 « OCIE1B
00225 #define TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK1 &= ~(1 « OCIE1B)
00226
00227 #define TIMER1_ENABLE_OVERFLOW_INTERRUPT TIMSK1 |= 1 « TOIE1
00228 #define TIMER1_DISABLE_OVERFLOW_INTERRUPT TIMSK1 &= ~(1 « TOIE1)
00229
00230 #define TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 |= 1 « ICIE1
00231 #define TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT TIMSK1 &= ~(1 « ICIE1)
00232
00233 #define TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 |= 1 « OCIE2A
00234 #define TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT TIMSK2 &= ~(1 « OCIE2A)
00235
00236 #define TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 |= 1 « OCIE2B
00237 #define TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT TIMSK2 &= ~(1 « OCIE2B)
00238
00239 #define TIMER2_ENABLE_OVERFLOW_INTERRUPT TIMSK2 |= 1 « TOIE2
00240 #define TIMER2_DISABLE_OVERFLOW_INTERRUPT TIMSK2 &= ~(1 « TOIE2)
00241
00242 #define TIMER0_COM_CHANNEL_A_INTERRUPT    TIMER0_COMPA_vect
00243 #define TIMER0_COM_CHANNEL_B_INTERRUPT    TIMER0_COMPB_vect
00244 #define TIMER0_OVERFLOW_INTERRUPT         TIMER0_OVF_vect
00245 #define TIMER1_COM_CHANNEL_A_INTERRUPT    TIMER1_COMPA_vect
00246 #define TIMER1_COM_CHANNEL_B_INTERRUPT    TIMER1_COMPB_vect
00247 #define TIMER1_OVERFLOW_INTERRUPT         TIMER1_OVF_vect
00248 #define TIMER1_INPUT_CAPTURE_INTERRUPT    TIMER1_CAPT_vect
00249 #define TIMER2_COM_CHANNEL_A_INTERRUPT    TIMER2_COMPA_vect

```

```

00249 #define    TIMER2_COM_CHANNEL_B_INTERRUPT    TIMER2_COMPB_vect
00250 #define    TIMER2_OVERFLOW_INTERRUPT    TIMER2_OVF_vect
00251
00252 // Watchdog Timer defines
00253
00254 #define WATCHDOG_SELECT_TIMEOUT(timeOut) WDTCSR |= (1<WDCE) | (1<WDE); WDTCSR = (0<WDIE) | (0<WDE) |
    timeOut;
00255 #define WATCHDOG_START(operationMode,timeOut) MCUSR &= ~(1<WDRF); WDTCSR |= (1<WDCE) | (1<WDE); WDTCSR
    = operationMode | timeOut;
00256 #define WATCHDOG_STOP MCUSR &= ~(1<WDRF); WDTCSR |= (1<WDCE) | (1<WDE); WDTCSR = 0x00;
00257 #define WATCHDOG_TIMEOUT_INTERRUPT    WDT_vect
00258
00259 // MCU defines
00260
00261
00262 #define MCU_SELECT_SLEEP_MODE(sleepMode) SMCR &= 0xF1; SMCR |= sleepMode << 1
00263
00264 #define MCU_SLEEP_ENABLE SMCR |= 1 << SE
00265 #define MCU_SLEEP_DISABLE SMCR &= ~(1 << SE)
00266
00267 #define MCU_TWI_ENABLE PRR &= ~(1 << PRTWI)
00268 #define MCU_TWI_DISABLE PRR |= 1 << PRTWI
00269
00270 #define MCU_TIMER2_ENABLE PRR &= ~(1 << PRTIM2)
00271 #define MCU_TIMER2_DISABLE PRR |= 1 << PRTIM2
00272
00273 #define MCU_TIMER1_ENABLE PRR &= ~(1 << PRTIM1)
00274 #define MCU_TIMER1_DISABLE PRR |= 1 << PRTIM1
00275
00276 #define MCU_TIMER0_ENABLE PRR &= ~(1 << PRTIM0)
00277 #define MCU_TIMER0_DISABLE PRR |= 1 << PRTIM0
00278
00279 #define MCU_SPI_ENABLE PRR &= ~(1 << PRSPI)
00280 #define MCU_SPI_DISABLE PRR |= 1 << PRSPI
00281
00282 #define MCU_USART0_ENABLE PRR &= ~(1 << PRUSART0)
00283 #define MCU_USART0_DISABLE PRR |= 1 << PRUSART0
00284
00285 #define MCU_ADC_ENABLE PRR &= ~(1 << PRADC)
00286 #define MCU_ADC_DISABLE PRR |= 1 << PRADC
00287
00288 #define MCU_BOD_DISABLE MCUCR |= (1<BODSE) | (1<BODS); MCUCR &= ~(1<BODSE);
00289
00290
00291 // ServoMotor defines
00292
00293 #define SERVO_MOTOR_TIMER_PULSE_WIDTH_COUNT(pulseWidth,clockPrescaler) ((F_CPU/1000000UL) *
    (pulseWidth/ clockPrescaler))
00294
00295 #define SERVO_MOTOR_TIMER_ANGLE_COUNT(angle,out_min,out_mid,out_max) (((out_min*(angle - 90L)*(angle -
    180L))/16200L + (angle*out_max*(angle - 90L))/16200L - (angle*out_mid*(angle - 180L))/8100L))
00296
00297 // SPI defines
00298
00299 #define    SPI_ENABLE                SPCR |= 1 << SPE
00300 #define    SPI_DISABLE                SPCR &= ~(1 << SPE)
00301 #define    SPI_SELECT_MASTER_MODE    SPCR |= 1 << MSTR
00302 #define    SPI_SELECT_SLAVE_MODE    SPCR &= ~(1 << MSTR)
00303
00304
00305 #define    SPI_SELECT_DATA_MODE(dataMode) SPCR &= 0xF3; SPCR |= dataMode << 2
00306 #define    SPI_SELECT_CLOCK_PRESCALER(clockPrescaler) SPCR &= 0xFC; SPCR |= (clockPrescaler & 3); SPSR
    &= 0xFE; SPSR |= (clockPrescaler & 4) >> 2
00307 #define    SPI_SELECT_DATA_ORDER(dataOrder) SPCR &= 0xDF; SPCR |= dataOrder << 5
00308
00309 #define    SPI_WRITE_COLLISION    WCOL
00310 #define    SPI_TRANSFER_COMPLETE    SPIF
00311
00312 #define    SPI_MASTER_MODE    MSTR
00313 #define    SPI_CONTROL_REGISTER    SPCR
00314 #define    SPI_DATA_REGISTER    SPDR
00315 #define    SPI_STATUS_REGISTER    SPSR
00316
00317 #define    SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT    SPCR |= 1 << SPIE
00318 #define    SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT    SPCR &= ~(1 << SPIE)
00319
00320
00321 #define    SPI_TRANSFER_COMPLETE_INTERRUPT    SPI_STC_vect
00322
00323 // StepperMotor defines
00324
00325
00326
00327
00328
00329
00330 #endif

```


00331

7.31 LCD.cpp File Reference

7.32 LCD.cpp

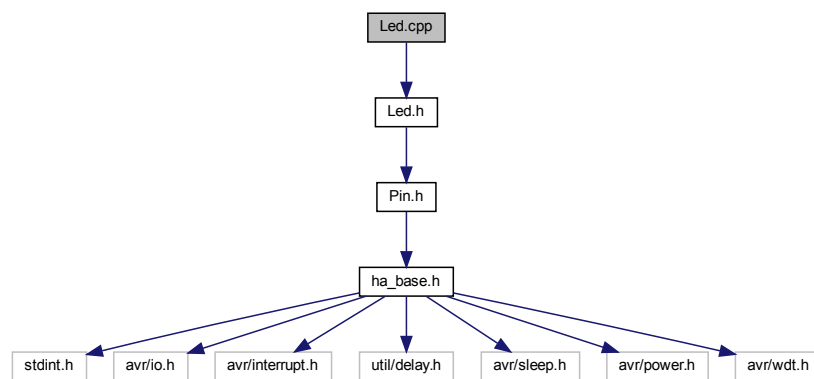
7.33 LCD.h File Reference

7.34 LCD.h

7.35 Led.cpp File Reference

```
#include "Led.h"
```

Include dependency graph for Led.cpp:



7.36 Led.cpp

```

00001 #include "Led.h"
00002
00003 component::Led::Led(const io::Pin &ar_pin)
00004     : m_pin(ar_pin)
00005 {
00006     m_pin.toOutput();
00007 }
00008
00009 component::Led::~Led()
00010 {
00011 }
00012 }
00013
00014
00015 void component::Led::on()
00016 {
00017     m_pin.setHigh();
00018 }
00019 }
00020
00021 void component::Led::off()

```

```

00022 {
00023     m_pin.setLow();
00024
00025 }
00026
00027
00028 void component::Led::toggle()
00029 {
00030     m_pin.toggle();
00031
00032 }
00033
00034 uint8_t component::Led::isOn()
00035 {
00036     return m_pin.isHigh();
00037 }
00038 }
00039
00040
00041 uint8_t component::Led::isOff()
00042 {
00043     return m_pin.isLow();
00044 }
00045 }
00046

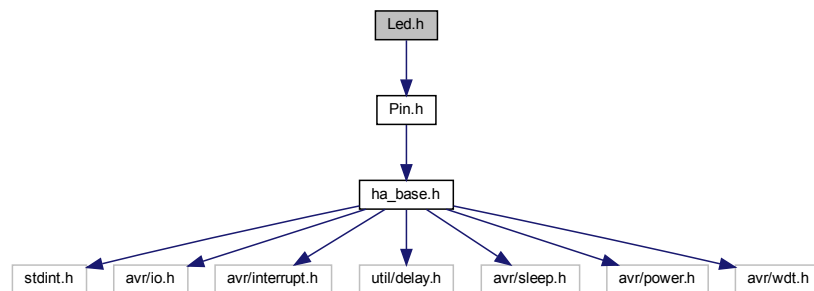
```

7.37 Led.h File Reference

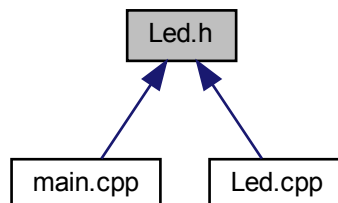
Header file of the Led class.

```
#include "Pin.h"
```

Include dependency graph for Led.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [component::Led](#)

Namespaces

- [component](#)

7.37.1 Detailed Description

Header file of the Led class.

class to control a Led.

Usage example (simple on/off example):

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [Led.h](#).

7.38 Led.h

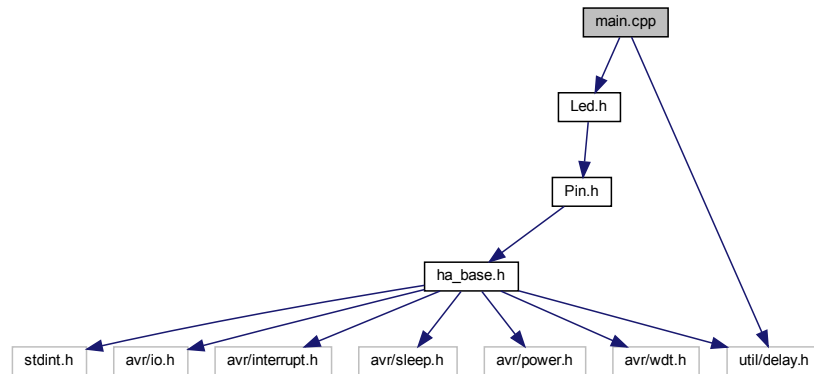
```
00001 #ifndef LED_H
00002 #define LED_H
00003 #include "Pin.h"
00004
00017 namespace component
00018 {
00019
00032 class Led
00033 {
00034
00035 public:
00042     Led(const io::Pin &ar_pin);
00046     ~Led();
00049     void on();
00052     void off();
00055     void toggle();
00058     uint8_t isOn();
00061     uint8_t isOff();
00062
00063 protected:
00064
00065 private:
00066
00067     io::Pin m_pin;
00071 };
00072
00073 }
00074
00075
00076 #endif
```

7.39 main.cpp File Reference

Demo example: Blink a Led.

```
#include "Led.h"
#include <util/delay.h>
```

Include dependency graph for main.cpp:



Macros

- `#define PIN_NUMBER 0`
Led pin number.
- `#define TIMEDELAY 500`
Time delay.

Functions

- `int main (void)`

7.39.1 Detailed Description

Demo example: Blink a Led.

Usage demonstration of the TahakomAVRLib in a simple blink a Led example. This example demonstrates the use of the Led and Pin abstraction objects.

- Compiler: gcc-avr
- Supported devices: The example compiles on the ATmega48P/88P/168P/328P AVR family

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2018

Definition in file [main.cpp](#).

7.39.2 Macro Definition Documentation

7.39.2.1 PIN_NUMBER

```
#define PIN_NUMBER 0
```

Led pin number.

Definition at line 19 of file [main.cpp](#).

7.39.2.2 TIMEDELAY

```
#define TIMEDELAY 500
```

Time delay.

Definition at line 20 of file [main.cpp](#).

7.39.3 Function Documentation

7.39.3.1 main()

```
int main (  
    void )
```

Definition at line 22 of file [main.cpp](#).

```
00022     {  
00023  
00024     // Init  
00025  
00026     // Instantiate a Led object  
00027     component::Led Led(io::Pin(PIN_NUMBER, io::PortB));  
00028  
00029     // Mainloop  
00030     while (1) {  
00031  
00032         Led.on();  
00033         _delay_ms(TIMEDELAY);  
00034  
00035         Led.off();  
00036         _delay_ms(TIMEDELAY);  
00037     }  
00038     return 0;  
00039 }
```

7.40 main.cpp

```

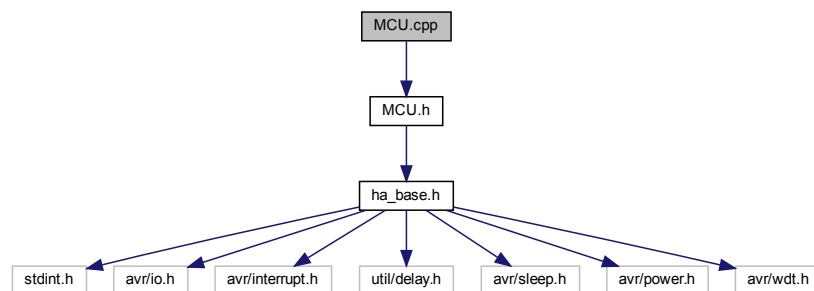
00001
00016 #include "Led.h"
00017 #include <util/delay.h>
00018
00019 #define PIN_NUMBER 0
00020 #define TIMEDELAY 500
00022 int main(void) {
00023
00024     // Init
00025
00026     // Instantiate a Led object
00027     component::Led Led(io::Pin(PIN_NUMBER,io::PortB));
00028
00029     // Mainloop
00030     while (1) {
00031
00032         Led.on();
00033         _delay_ms(TIMEDELAY);
00034
00035         Led.off();
00036         _delay_ms(TIMEDELAY);
00037     }
00038     return 0;
00039 }

```

7.41 MCU.cpp File Reference

```
#include "MCU.h"
```

Include dependency graph for MCU.cpp:



7.42 MCU.cpp

```

00001 #include "MCU.h"
00002
00003 void core::MCU::init()
00004 {
00005     enableUSART0(0);
00006     enableTimerCounter0(0);
00007     enableTimerCounter1(0);
00008     enableTimerCounter2(0);
00009     enableTWI(0);
00010     enableSPI(0);
00011     enableADC(0);
00012 }
00013
00014
00015 void core::MCU::selectSleepMode(const sleepMode &a_sleepMode)
00016 {
00017     MCU_SELECT_SLEEP_MODE(static_cast<uint8_t>(a_sleepMode));
00018 }
00019
00020

```

```

00021 void core::MCU::goToSleep(const BODMode &a_BODMode)
00022 {
00023     cli();
00024     switch (a_BODMode)
00025     {
00026         case core::BODMode::enabled:
00027         {
00028             sleepEnable(1);
00029             sei();
00030             sleep_cpu();
00031             sleepEnable(0);
00032             break;
00033         }
00034         case core::BODMode::disabled:
00035         {
00036             sleepEnable(1);
00037             disableBOD();
00038             sei();
00039             sleep_cpu();
00040             sleepEnable(0);
00041             break;
00042         }
00043     }
00044 }
00045 }
00046
00047 void core::MCU::sleepEnable(const uint8_t a_enable)
00048 {
00049     if (a_enable) {
00050         MCU_SLEEP_ENABLE;
00051     } else {
00052         MCU_SLEEP_DISABLE;
00053     }
00054 }
00055 }
00056
00057 void core::MCU::enableUSART0(const uint8_t a_enable)
00058 {
00059     if (a_enable) {
00060         MCU_USART0_ENABLE;
00061     } else {
00062         MCU_USART0_DISABLE;
00063     }
00064 }
00065 }
00066
00067 void core::MCU::enableTimerCounter0(const uint8_t a_enable)
00068 {
00069     if (a_enable) {
00070         MCU_TIMER0_ENABLE;
00071     } else {
00072         MCU_TIMER0_DISABLE;
00073     }
00074 }
00075 }
00076
00077 void core::MCU::enableTimerCounter1(const uint8_t a_enable)
00078 {
00079     if (a_enable) {
00080         MCU_TIMER1_ENABLE;
00081     } else {
00082         MCU_TIMER1_DISABLE;
00083     }
00084 }
00085 }
00086
00087 void core::MCU::enableTimerCounter2(const uint8_t a_enable)
00088 {
00089     if (a_enable) {
00090         MCU_TIMER2_ENABLE;
00091     } else {
00092         MCU_TIMER2_DISABLE;
00093     }
00094 }
00095 }
00096
00097 void core::MCU::enableTWI(const uint8_t a_enable)
00098 {
00099     if (a_enable) {
00100         MCU_TWI_ENABLE;
00101     } else {
00102         MCU_TWI_DISABLE;
00103     }
00104 }
00105 }
00106
00107 void core::MCU::enableSPI(const uint8_t a_enable)

```

```

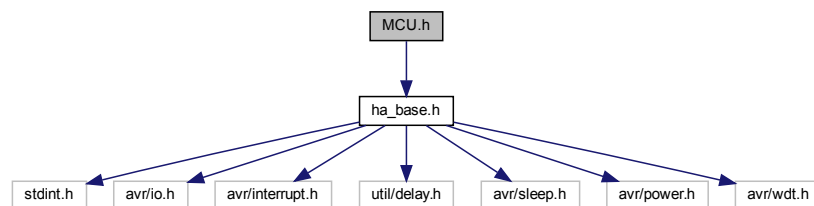
00108 {
00109     if (a_enable) {
00110         MCU_SPI_ENABLE;
00111     } else {
00112         MCU_SPI_DISABLE;
00113     }
00114 }
00115 }
00116
00117 void core::MCU::enableADC(const uint8_t a_enable)
00118 {
00119     if (a_enable) {
00120         MCU_ADC_ENABLE;
00121     } else {
00122         MCU_ADC_DISABLE;
00123     }
00124 }
00125
00126 void core::MCU::disableBOD()
00127 {
00128     MCU_BOD_DISABLE;
00129 }

```

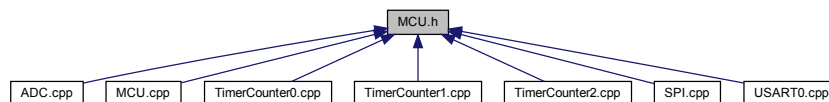
7.43 MCU.h File Reference

Header file of the MCU class.

```
#include "ha_base.h"
Include dependency graph for MCU.h:
```



This graph shows which files directly or indirectly include this file:



Classes

- class [core::MCU](#)

Namespaces

- [core](#)

Enumerations

- enum `core::BODMode` : `uint8_t` { `core::BODMode::enabled` =0, `core::BODMode::disabled` }
- enum `core::sleepMode` : `uint8_t` {
`core::sleepMode::idle` =0, `core::sleepMode::ADC_NoiseReduction`, `core::sleepMode::powerDown`, `core::sleepMode::powerSave`,
`core::sleepMode::standby` =6, `core::sleepMode::extendedStandby` }

7.43.1 Detailed Description

Header file of the MCU class.

Basic class abstraction of the MCU.

Usage example (test):

```
#include "PushButton.h" #include "Led.h" #include "ExternInterrupt.h" #include "MCU.h"

#define PUSHBUTTON_NUMBER 2 #define LED_NUMBER 0

int main(void) {

    Init initialize MCU core::MCU::init();

    instantiate a Led object component::Led Led(io::Pin(LED_NUMBER,io::PortB));

    instantiate a Led object component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortD));

    instantiate the external interrupt manager core::ExternInterrupt &myExternInterrupt = core::ExternInterrupt::getInstance();
    myExternInterrupt.enableInt0(1); myExternInterrupt.setInt0SenseControl(core::senseControl::logicalChange);

    set sleep mode core::MCU::selectSleepMode(core::sleepMode::powerDown);

    Mainloop while (1) {

        flash the LED for (uint8_t i=0;i<10;i++) { Led.on(); _delay_ms(100); Led.off(); _delay_ms(100); } _delay_ms(5000);
        Led.on(); _delay_ms(100); Led.off(); core::MCU::goToSleep(core::BODMode::enabled);

    } return 0; }

void core::ExternInterrupt::Int0ServiceRoutine() {

}
```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file `MCU.h`.

7.44 MCU.h

```

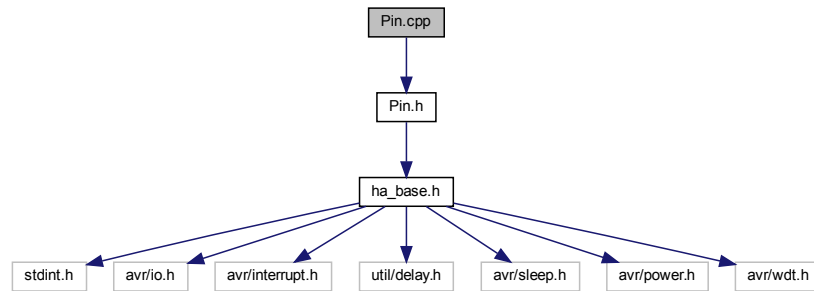
00001
00069 #ifndef MCU_H
00070 #define MCU_H
00071 #include "ha_base.h"
00072
00073
00074 namespace core
00075 {
00076
00077 enum class BODMode : uint8_t {
00078     enabled=0,
00079     disabled,
00080 };
00081
00082 enum class sleepMode : uint8_t {
00083     Idle=0,
00084     ADC_NoiseReduction,
00085     powerDown,
00086     powerSave,
00087     standby=6,
00088     extendedStandby,
00089 };
00090
00091 class MCU
00092 {
00093 public:
00094
00095     static void init();
00096
00097     static void selectSleepMode(const sleepMode &a_sleepMode);
00098
00099     static void goToSleep(const BODMode &a_BODMode);
00100
00101     static void sleepEnable(const uint8_t ar_enable);
00102
00103     static void enableUSART0(const uint8_t a_enable);
00104
00105     static void enableTimerCounter0(const uint8_t a_enable);
00106
00107     static void enableTimerCounter1(const uint8_t a_enable);
00108
00109     static void enableTimerCounter2(const uint8_t a_enable);
00110
00111     static void enableTWI(const uint8_t a_enable);
00112
00113     static void enableSPI(const uint8_t a_enable);
00114
00115     static void enableADC(const uint8_t a_enable);
00116
00117     static void disableBOD();
00118
00119
00120
00121
00122 protected:
00123
00124
00125
00126 private:
00127
00128
00129
00130
00131
00132
00133
00134
00135 };
00136
00137
00138
00139
00140
00141 }
00142 #endif

```

7.45 Pin.cpp File Reference

```
#include "Pin.h"
```

Include dependency graph for Pin.cpp:



7.46 Pin.cpp

```

00001 #include "Pin.h"
00002
00003
00004 io::Pin::Pin(const uint8_t a_pinNumber, const Port &mr_portName)
00005     : mr_portName(mr_portName), m_pinNumber(a_pinNumber)
00006 {
00007
00008 }
00009
00010
00011 io::Pin::~~Pin()
00012 {
00013 {
00014 }
00015 }
00016
00017 void io::Pin::toOutput()
00018 {
00019     *mr_portName.mp_ddrReg |= (1 << m_pinNumber);
00020 }
00021
00022 void io::Pin::toInput(const uint8_t &ar_useInternalPullUp)
00023 {
00024     if (ar_useInternalPullUp)
00025     {
00026         *mr_portName.mp_portReg |= (1 << m_pinNumber);
00027         *mr_portName.mp_ddrReg &= ~(1 << m_pinNumber);
00028     }
00029     else
00030     {
00031         *mr_portName.mp_portReg &= ~(1 << m_pinNumber);
00032         *mr_portName.mp_ddrReg &= ~(1 << m_pinNumber);
00033     }
00034 }
00035
00036
00037 }
00038
00039 void io::Pin::setLow()
00040 {
00041     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))
00042     {
00043         *mr_portName.mp_portReg &= ~(1 << m_pinNumber);
00044     }
00045 }
00046
00047 void io::Pin::setHigh()
00048 {
00049     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))
00050     {
00051         *mr_portName.mp_portReg |= (1 << m_pinNumber);
00052     }
00053 }
00054
00055 void io::Pin::toggle()
00056 {
00057     if (*mr_portName.mp_ddrReg & (1 << m_pinNumber))

```

```

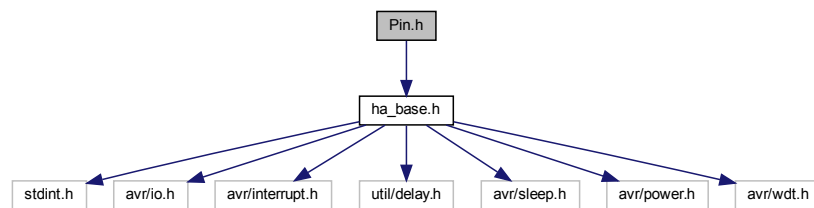
00058     {
00059         *mr_portName.mp_portReg ^= 1 << m_pinNumber;
00060     }
00061 }
00062
00063 uint8_t io::Pin::isHigh()
00064 {
00065     return *mr_portName.mp_pinReg & (1 << m_pinNumber);
00066 }
00067
00068 uint8_t io::Pin::isLow()
00069 {
00070     return !(*mr_portName.mp_pinReg & (1 << m_pinNumber));
00071 }
00072
00073 uint8_t io::Pin::getPinNumber()
00074 {
00075     return m_pinNumber;
00076 }

```

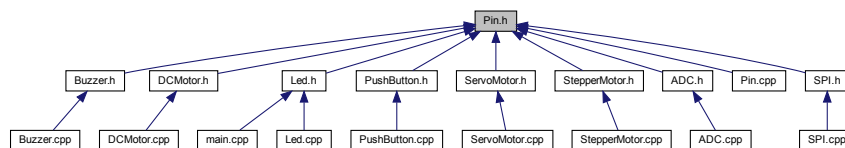
7.47 Pin.h File Reference

```
#include "ha_base.h"
```

Include dependency graph for Pin.h:



This graph shows which files directly or indirectly include this file:



Classes

- struct [io::Port](#)
Structure.
- class [io::Pin](#)

Namespaces

- [io](#)

Variables

- static `io::Port io::PortB` = { &DDRB, &PORTB, &PINB }
global static Port B object
- static `io::Port io::PortC` = { &DDRC, &PORTC, &PINC }
global static Port C object
- static `io::Port io::PortD` = { &DDRD, &PORTD, &PIND }
global static Port D object

7.48 Pin.h

```

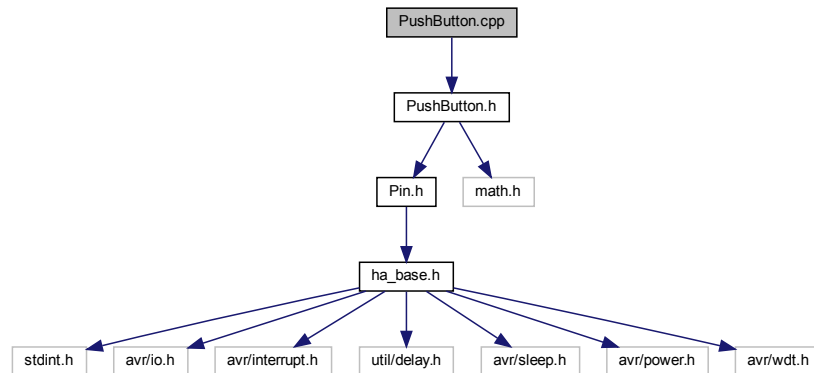
00001 #ifndef PIN_H
00002 #define PIN_H
00003 #include "ha_base.h"
00004
00005 namespace io
00006 {
00007
00011 struct Port
00012 {
00013     volatile uint8_t* mp_ddrReg;
00015     volatile uint8_t* mp_portReg;
00017     volatile uint8_t* mp_pinReg;
00018 };
00019
00020 class Pin
00021 {
00022
00023 public:
00029     Pin(const uint8_t a_pinNumber, const Port &ar_portName);
00032     ~Pin();
00035     void toOutput();
00040     void toInput(const uint8_t &ar_useInternalPullUp);
00043     void setLow();
00046     void setHigh();
00049     void toggle();
00052     uint8_t isHigh();
00055     uint8_t isLow();
00058     uint8_t getPinNumber();
00059
00060 protected:
00061
00062
00063 private:
00064
00065     const Port &mr_portName;
00066     const uint8_t m_pinNumber;
00070 };
00071
00072 static io::Port PortB = { &DDRB, &PORTB, &PINB };
00073 static io::Port PortC = { &DDRC, &PORTC, &PINC };
00074 static io::Port PortD = { &DDRD, &PORTD, &PIND };
00076 }
00077
00078
00079 #endif

```

7.49 PushButton.cpp File Reference

```
#include "PushButton.h"
```

Include dependency graph for PushButton.cpp:



7.50 PushButton.cpp

```

00001 #include "PushButton.h"
00002
00003 component::PushButton::PushButton(const io::Pin& ar_pin, const uint8_t &ar_useInternalPullUp, const
      uint8_t &ar_isActiveLow)
00004                                     : m_pin(ar_pin),
00005                                     mr_isActiveLow(ar_isActiveLow),
00006                                     mr_useInternalPullUp(ar_useInternalPullUp)
00007
00008
00009 {
00010     m_pin.toInput(mr_useInternalPullUp);
00011     m_buttonPressed = 0;
00012 }
00013
00014 component::PushButton::~PushButton()
00015 {
00016
00017 }
00018
00019
00020 uint8_t component::PushButton::isPressed()
00021 {
00022     if (mr_isActiveLow || mr_useInternalPullUp) {
00023         if (m_pin.isLow()) {
00024             _delay_us(PUSHBUTTON_DEBOUNCE_TIME_US);
00025             if (m_pin.isLow()) {
00026                 ++m_buttonPressed;
00027                 return 1;
00028             }
00029         }
00030     } else {
00031         if (m_pin.isHigh()) {
00032             _delay_us(PUSHBUTTON_DEBOUNCE_TIME_US);
00033             if (m_pin.isHigh()) {
00034                 ++m_buttonPressed;
00035                 return 1;
00036             }
00037         }
00038     }
00039 }
00040
00041 m_buttonPressed = 0;
00042 return 0;
00043
00044 }
00045
00046 uint8_t component::PushButton::getPressedCount() const
00047 {
00048
00049     return m_buttonPressed;
00050
00051 }
00052

```

```

00053 void component::PushButton::resetPressedCount ()
00054 {
00055     m_buttonPressed = 0;
00056
00057 }

```

7.51 PushButton.h File Reference

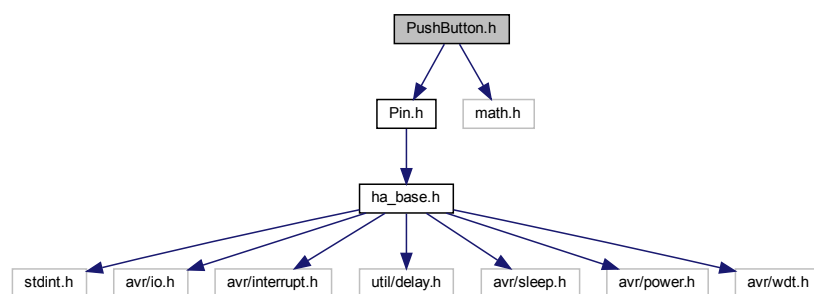
Header file of the Push Button class.

```

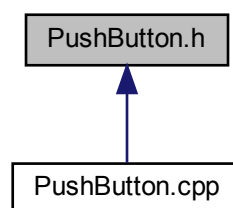
#include "Pin.h"
#include <math.h>

```

Include dependency graph for PushButton.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [component::PushButton](#)

Namespaces

- [component](#)

7.51.1 Detailed Description

Header file of the Push Button class.

class to monitor a Push Button

Usage example (current state):

```
#include "PushButton.h" #include "Led.h"

#define PUSHBUTTON_NUMBER 1 #define LED_NUMBER 0

int main(void) {

    Init

    instantiate a Led object component::Led Led(io::Pin(LED_NUMBER,io::PortB));

    instantiate a Led object component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortB));

    Mainloop while (1) {

        if (PushButton.isPressed()) { Led.on(); } else { Led.off(); }

    } return 0; }
```

Usage example (changing state):

```
#include "PushButton.h" #include "Led.h"

#define PUSHBUTTON_NUMBER 1 #define LED_NUMBER 0

int main(void) {

    Init

    uint8_t l_statePushButton = 0;

    instantiate a Led object component::Led Led(io::Pin(LED_NUMBER,io::PortB));

    instantiate a Led object component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortB));

    Mainloop while (1) {

        if (PushButton.isPressed()) { if (l_statePushButton == 0) {

            Led.toggle();
            l_statePushButton = 1;

        } } else { l_statePushButton = 0; }

    } return 0; }
```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [PushButton.h](#).

7.52 PushButton.h

```

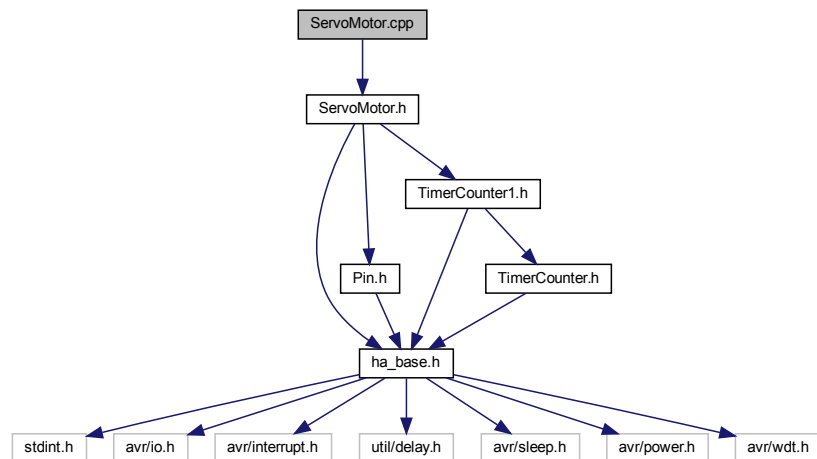
00001
00085 #ifndef PUSHBUTTON_H
00086 #define PUSHBUTTON_H
00087 #include "Pin.h"
00088 #include <math.h>
00089
00090 // TODO: check the use PUSHBUTTON_SAMPLING in ha_m328p.h
00091
00092
00093 namespace component
00094 {
00095 class PushButton
00096 {
00097 public:
00104     PushButton(const io::Pin &ar_pin, const uint8_t &ar_useInternalPullUp=1, const uint8_t
        &ar_isActiveLow=1);
00107     ~PushButton();
00110     uint8_t isPressed();
00113     uint8_t getPressedCount() const;
00116     void resetPressedCount();
00117
00118
00119 protected:
00120
00121 private:
00122     io::Pin m_pin;
00123     const uint8_t &mr_isActiveLow;
00124     const uint8_t &mr_useInternalPullUp;
00125     uint8_t m_buttonPressed;
00129 };
00130 }
00131
00132
00133
00134
00135 #endif

```

7.53 ServoMotor.cpp File Reference

```
#include "ServoMotor.h"
```

Include dependency graph for ServoMotor.cpp:



7.54 ServoMotor.cpp

```
00001 #include "ServoMotor.h"
```

```

00002
00003
00004
00005 component::ServoMotor::ServoMotor(const io::Pin &ar_pin,
00006                                     const uint16_t &ar_pulseCycle,
00007                                     const uint16_t &ar_pulseWidthMin,
00008                                     const uint16_t &ar_pulseWidthMid,
00009                                     const uint16_t &ar_pulseWidthMax)
00010     : m_pin(ar_pin),
00011       m_pulseCycle(ar_pulseCycle),
00012       m_pulseWidthMin(ar_pulseWidthMin),
00013       m_pulseWidthMid(ar_pulseWidthMid),
00014       m_pulseWidthMax(ar_pulseWidthMax)
00015 {
00016     m_pin.toOutput();
00017 }
00018 }
00019
00020 component::ServoMotor::~ServoMotor()
00021 {
00022 }
00023 }
00024
00025
00026
00027
00028 void component::ServoMotor::on()
00029 {
00030     m_pin.setHigh();
00031 }
00032
00033 void component::ServoMotor::off()
00034 {
00035     m_pin.setLow();
00036 }
00037
00038 void component::ServoMotor::toggle()
00039 {
00040     m_pin.toggle();
00041 }
00042 }
00043
00044 uint16_t component::ServoMotor::computePulseCycleCount(const uint16_t &ar_clockPrescaler)
00045 {
00046     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseCycle, ar_clockPrescaler);
00047 }
00048
00049 uint16_t component::ServoMotor::computePulseWidthMinCount(const uint16_t &ar_clockPrescaler)
00050 {
00051     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMin, ar_clockPrescaler);
00052 }
00053
00054 uint16_t component::ServoMotor::computePulseWidthMaxCount(const uint16_t &ar_clockPrescaler)
00055 {
00056     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMax, ar_clockPrescaler);
00057 }
00058
00059 uint16_t component::ServoMotor::computePulseWidthMidCount(const uint16_t &ar_clockPrescaler)
00060 {
00061     return SERVOMOTOR_TIMER_PULSE_WIDTH_COUNT(m_pulseWidthMid, ar_clockPrescaler);
00062 }
00063
00064 uint16_t component::ServoMotor::computeRotationAngleCount(const uint8_t &ar_angle_deg, const uint16_t
&ar_clockPrescaler)
00065 {
00066     return
static_cast<uint16_t>(SERVOMOTOR_TIMER_ANGLE_COUNT(ar_angle_deg, static_cast<long>(computePulseWidthMinCount(ar_clockPre
00067 }
00068
00069
00070
00071 void component::ServoMotor::rotate(core::TimerCounter1 &ar_timerCounter1,
00072                                   const uint8_t &ar_angle_deg,
00073                                   const core::channel &ar_channel)
00074 {
00075     ar_timerCounter1.setOutputCompareRegister(ar_channel,
computeRotationAngleCount(ar_angle_deg, ar_timerCounter1.getClockPrescaler()));
00076
00077     // start timer
00078     ar_timerCounter1.start();
00079 }
00080 }
00081
00082 }
00083
00084
00085 void component::ServoMotor::connect(core::TimerCounter1 &ar_timerCounter1,

```

```

00086         const core::channel &ar_channel)
00087     {
00088     00089
00090     ar_timerCounter1.setInputCaptureRegister(computePulseCycleCount(ar_timerCounter1.getClockPrescaler()));
00091     ar_timerCounter1.selectOperationMode(core::operationMode::fast_PWM_ICR);
00092     ar_timerCounter1.selectCompareOutputMode(ar_channel, core::compareOutputMode::clear);
00093     ar_timerCounter1.setCounter(0);
00094
00095     }
00096
00097 void component::ServoMotor::disconnect(core::TimerCounter1 &ar_timerCounter1,
00098         const core::channel &ar_channel)
00099 {
00100     ar_timerCounter1.selectCompareOutputMode(ar_channel, core::compareOutputMode::normal);
00101     // stop timer
00102     ar_timerCounter1.stop();
00103 }

```

7.55 ServoMotor.h File Reference

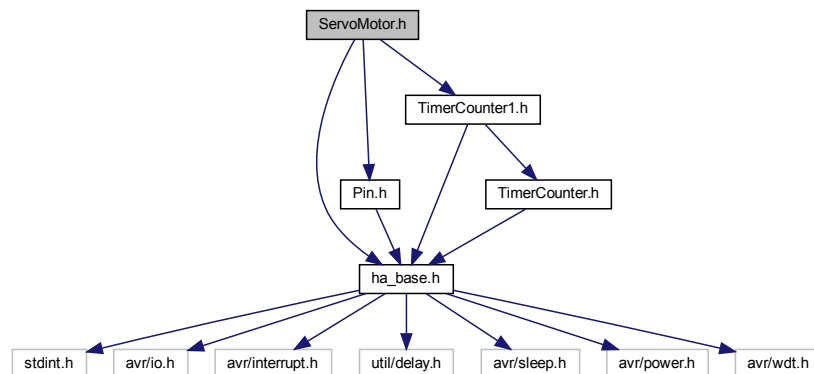
Header file of the ServoMotor class.

```

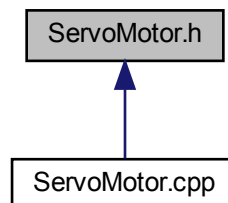
#include "ha_base.h"
#include "Pin.h"
#include "TimerCounter1.h"

```

Include dependency graph for ServoMotor.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [component::ServoMotor](#)

Namespaces

- [component](#)

7.55.1 Detailed Description

Header file of the ServoMotor class.

Header file of the StepperMotor class.

Usage example (separate): #include "MCU.h" #include "ServoMotor.h" #include "TimerCounter1.h"

```
#define SERVOMOTOR_NUMBER 1 #define SERVOMOTOR_PULSE_CYCLE 30000 // pulse cycle [us] #define
SERVOMOTOR_PULSE_WIDTH_MIN 500// pulse width min [us] #define SERVOMOTOR_PULSE_WIDTH_MID
1520 // pulse width mid [us] #define SERVOMOTOR_PULSE_WIDTH_MAX 3000 // pulse width max [us]
```

```
int main(void) {
```

```
    Init initialize MCU core::MCU::init\(\);
```

```
    instantiate the TimerCounter0 object core::TimerCounter1 &myTimerCounter1 = core::TimerCounter1::getInstance\(\);
    myTimerCounter1.selectClockSource(core::clockSource::PS\_8); myTimerCounter1.selectOperationMode(core::operationMode::fast\_PWM\_ICR);
    myTimerCounter1.selectCompareOutputMode(core::channel::A, core::compareOutputMode::clear);
```

```
    instantiate the Buzzer object component::ServoMotor myServoMotor(io::Pin\(SERVOMOTOR\_NUMBER,io::PortB\),
SERVOMOTOR_PULSE_CYCLE, SERVOMOTOR_PULSE_WIDTH_MIN, SERVOMOTOR_PULSE_WIDTH_MID, SERVOMOTOR_PULSE_WIDTH_MAX);
```

```
    myTimerCounter1.setInputCaptureRegister(myServoMotor.computePulseCycleCount(myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(0,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000); myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(45,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000); myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(90,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000); myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(135,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000); myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(180,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000); myTimerCounter1.setOutputCompareRegister(core::channel::A, myServoMotor.computeRotationAngleCount(0,myTimerCounter1.getClockPrescaler()));
    myTimerCounter1.start(); _delay_ms(2000);
```

```
    Mainloop while (1) {
```

```
    } return 0; } Usage example (TimerCounter1): #include "MCU.h" #include "ServoMotor.h" #include "TimerCounter1.h"
```

```
#define SERVOMOTOR_NUMBER 1 #define SERVOMOTOR_PULSE_CYCLE 30000 // pulse cycle [us] #define
SERVOMOTOR_PULSE_WIDTH_MIN 500// pulse width min [us] #define SERVOMOTOR_PULSE_WIDTH_MID 1520 // pulse width mid [us] #define
SERVOMOTOR_PULSE_WIDTH_MAX 3000 // pulse width max [us]
```

```
int main(void) {
```

Init initialize MCU `core::MCU::init();`

instantiate the TimerCounter1 object `core::TimerCounter1` &myTimerCounter1 = `core::TimerCounter1::getInstance();`
`myTimerCounter1.selectClockSource(core::clockSource::PS_8);`

instantiate the Buzzer object `component::ServoMotor` myServoMotor(`io::Pin(SERVOMOTOR_NUMBER,io::PortB)`,
`SERVOMOTOR_PULSE_CYCLE`, `SERVOMOTOR_PULSE_WIDTH_MIN`, `SERVOMOTOR_PULSE_WIDTH_M`↵
`ID`, `SERVOMOTOR_PULSE_WIDTH_MAX`);

`myServoMotor.connect(myTimerCounter1);`

`myServoMotor.rotate(myTimerCounter1,0); _delay_ms(2000); myServoMotor.rotate(myTimerCounter1,45); _`↵
`delay_ms(2000); myServoMotor.rotate(myTimerCounter1,90); _delay_ms(2000); myServoMotor.rotate(myTimer`↵
`Counter1,135); _delay_ms(2000); myServoMotor.rotate(myTimerCounter1,180); _delay_ms(2000); myServo`↵
`Motor.rotate(myTimerCounter1,0); _delay_ms(2000);`

`myServoMotor.disconnect(myTimerCounter1);`

Mainloop while (1) {

}
`return 0;`

}

class to control a servo motor

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

The StepperMotor class is implemented and tested for the 28BYJ-48 Stepper Motor Usage example (basic):

`#include "StepperMotor.h"`

`#define StepperMotor_Pin_1 0 #define StepperMotor_Pin_2 1 #define StepperMotor_Pin_3 2 #define Stepper`↵
`Motor_Pin_4 3`

`#define STEP_ANGLE_FULL_STEP 0.176 #define STEP_ANGLE_HALF_STEP 0.0879`

`int main(void) {`

instantiate the StepperMotor object `component::StepperMotor` myStepperMotor(`component::mode::halfStep`,
`io::Pin(StepperMotor_Pin_1,io::PortB)`, `io::Pin(StepperMotor_Pin_2,io::PortB)`, `io::Pin(StepperMotor_Pin_3,io::PortB)`,
`io::Pin(StepperMotor_Pin_4,io::PortB)`);

`int16_t l_angle = -180; int16_t l_step = static_cast<int16_t>(l_angle / STEP_ANGLE_HALF_STEP);`

set speed [steps/s] full step: max speed: 500p/s half step: max speed: 1000p/s

set speed [%/s] full step: max speed: 40%/s half step: max speed: 80%/s

Mainloop while (1) {

`while (!myStepperMotor.goalReached())`
`{`

set motor steps `myStepperMotor.step(l_step,1000); myStepperMotor.step(l_step,80,STEP_ANGLE_HALF_STEP);`

`}`

`} return 0; }`

class to control a servo motor

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [ServoMotor.h](#).

7.56 ServoMotor.h

```

00001
00126 #ifndef SERVOMOTOR_H
00127 #define SERVOMOTOR_H
00128 #include "ha_base.h"
00129 #include "Pin.h"
00130 #include "TimerCounter1.h"
00131
00132
00133
00134 namespace component
00135 {
00136
00137
00138 class ServoMotor
00139 {
00140 public:
00141
00142     ServoMotor(const io::Pin &ar_pin,
00143               const uint16_t &ar_pulseCycle=0,
00144               const uint16_t &ar_pulseWidthMin=0,
00145               const uint16_t &ar_pulseWidthMid=0,
00146               const uint16_t &ar_pulseWidthMax=0);
00147
00148     ~ServoMotor();
00149
00150     void on();
00151     void off();
00152     void toggle();
00153
00154     uint16_t computePulseCycleCount(const uint16_t &ar_clockPrescaler);
00155
00156     uint16_t computePulseWidthMinCount(const uint16_t &ar_clockPrescaler);
00157
00158     uint16_t computePulseWidthMidCount(const uint16_t &ar_clockPrescaler);
00159
00160     uint16_t computePulseWidthMaxCount(const uint16_t &ar_clockPrescaler);
00161
00162     uint16_t computeRotationAngleCount(const uint8_t &ar_angle_deg, const uint16_t
&ar_clockPrescaler);
00163
00164
00165     void rotate(core::TimerCounter1 &ar_timerCounter1,
00166               const uint8_t &ar_angle_deg,
00167               const core::channel &ar_channel=core::channel::A);
00168
00169     void connect(core::TimerCounter1 &ar_timerCounter1,
00170               const core::channel &ar_channel=core::channel::A);
00171
00172     void disconnect(core::TimerCounter1 &ar_timerCounter1,
00173               const core::channel &ar_channel=core::channel::A);
00174
00175
00176
00177
00178
00179
00180
00181
00182
00183 protected:
00184
00185 private:
00186
00187
00188     io::Pin m_pin;
00189     uint16_t m_pulseCycle;
00190     uint16_t m_pulseWidthMin;
00191     uint16_t m_pulseWidthMid;
00192     uint16_t m_pulseWidthMax;
00203 };
00204
00205
00206
00207

```

```

00208 }
00209
00210
00211
00212 #endif

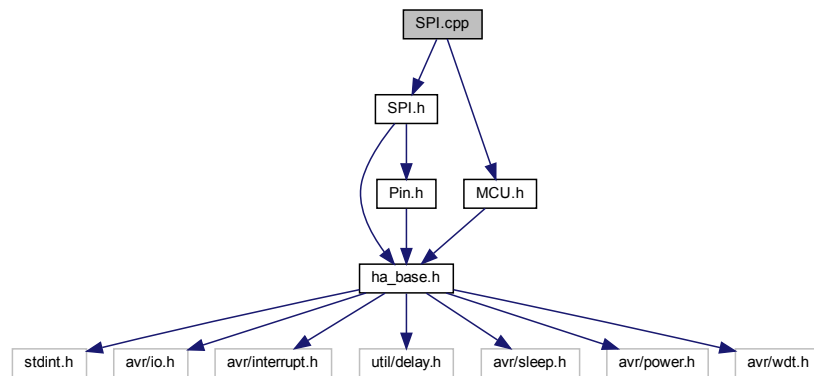
```

7.57 SPI.cpp File Reference

```
#include "SPI.h"
```

```
#include "MCU.h"
```

Include dependency graph for SPI.cpp:



7.58 SPI.cpp

```

00001 #include "SPI.h"
00002 #include "MCU.h"
00003
00004 volatile uint8_t io::SPI::m_data = 0;
00005
00006
00007
00008 io::SPI& io::SPI::getInstance(const Pin &ar_pinSCK,
00009                               const Pin &ar_pinMISO,
00010                               const Pin &ar_pinMOSI,
00011                               const Pin &ar_pinSS)
00012 {
00013     static SPI l_instance(ar_pinSCK,
00014                           ar_pinMISO,
00015                           ar_pinMOSI,
00016                           ar_pinSS);
00017
00018     return l_instance;
00019
00020 }
00021
00022 io::SPI::SPI(const Pin &ar_pinSCK,
00023              const Pin &ar_pinMISO,
00024              const Pin &ar_pinMOSI,
00025              const Pin &ar_pinSS)
00026     : m_pinSCK(ar_pinSCK),
00027       m_pinMISO(ar_pinMISO),
00028       m_pinMOSI(ar_pinMOSI),
00029       m_pinSS(ar_pinSS)
00030 {
00031     core::MCU::enableSPI(1);
00032     sei();
00033     enableTransferCompleteInterrupt(1);
00034 }
00035
00036

```

```

00037 io::SPI::~SPI()
00038 {
00039
00040 }
00041
00042 uint8_t io::SPI::writeCollision()
00043 {
00044     return (SPI_STATUS_REGISTER & (1 << SPI_WRITE_COLLISION));
00045 }
00046
00047
00048 uint8_t io::SPI::transferComplete()
00049 {
00050     return (SPI_STATUS_REGISTER & (1 << SPI_TRANSFER_COMPLETE));
00051 }
00052
00053 void io::SPI::selectClockPrescaler(const clockPrescaler& ar_clockPrescaler)
00054 {
00055     SPI_SELECT_CLOCK_PRESCALER(static_cast<uint8_t>(ar_clockPrescaler));
00056 }
00057
00058
00059 void io::SPI::selectOperationMode(const operationMode& ar_operationMode)
00060 {
00061     switch (ar_operationMode)
00062     {
00063     case operationMode::master:
00064     {
00065         m_pinMOSI.toOutput();
00066         m_pinSCK.toOutput();
00067         m_pinMISO.toInput(1);
00068         m_pinSS.toOutput();
00069         m_pinSS.setHigh();
00070         SPI_SELECT_MASTER_MODE;
00071         SPI_ENABLE;
00072         break;
00073     }
00074     case operationMode::slave:
00075     {
00076         m_pinMISO.toOutput();
00077         SPI_SELECT_SLAVE_MODE;
00078         SPI_ENABLE;
00079         break;
00080     }
00081     case operationMode::submaster:
00082     {
00083         m_pinMOSI.toOutput();
00084         m_pinSCK.toOutput();
00085         m_pinMISO.toInput(1);
00086         m_pinSS.toInput(1);
00087         SPI_SELECT_MASTER_MODE;
00088         SPI_ENABLE;
00089         break;
00090     }
00091     case operationMode::disable:
00092     {
00093         SPI_DISABLE;
00094         break;
00095     }
00096     }
00097 }
00098
00099 void io::SPI::selectDataMode(const dataMode& ar_dataMode)
00100 {
00101     SPI_SELECT_DATA_MODE(static_cast<uint8_t>(ar_dataMode));
00102 }
00103
00104 void io::SPI::selectDataOrder(const dataOrder& ar_dataOrder)
00105 {
00106     SPI_SELECT_DATA_ORDER(static_cast<uint8_t>(ar_dataOrder));
00107 }
00108
00109
00110 void io::SPI::enableTransferCompleteInterrupt(const uint8_t a_enable)
00111 {
00112     if (a_enable) {
00113         SPI_ENABLE_TRANSFER_COMPLETE_INTERRUPT;
00114     } else {
00115         SPI_DISABLE_TRANSFER_COMPLETE_INTERRUPT;
00116     }
00117 }
00118
00119 void io::SPI::selectSlave(const uint8_t a_select)
00120 {
00121     if (a_select) {
00122         m_pinSS.setLow();
00123     }

```



```

00124     } else {
00125         m_pinSS.setHigh();
00126     }
00127 }
00128 }
00129 void io::SPI::transferCompleteServiceRoutine()
00130 {
00131     m_data = SPI_DATA_REGISTER;
00132 }
00133 }
00134 }
00135 void io::SPI::masterSendByte(const uint8_t &ar_byte)
00136 {
00137     SPI_DATA_REGISTER = ar_byte;
00138     selectSlave(1);
00139     while(!transferComplete()){};
00140     selectSlave(0);
00141 }
00142 }
00143 }
00144 }
00145 }
00146 }
00147 void io::SPI::masterReceiveByte(uint8_t &ar_byte)
00148 {
00149     masterSendByte(0);
00150     ar_byte = m_data;
00151 }
00152 }
00153 }
00154 void io::SPI::slaveReceiveByte(uint8_t &ar_byte)
00155 {
00156     ar_byte = m_data;
00157 }
00158 }

```

7.59 SPI.h File Reference

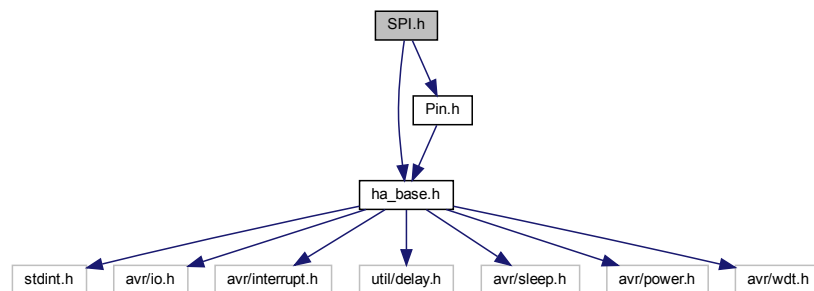
Header file of the SPI class.

```

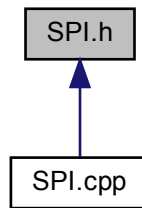
#include "ha_base.h"
#include "Pin.h"

```

Include dependency graph for SPI.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [io::SPI](#)

Namespaces

- [io](#)

Enumerations

- enum [io::operationMode](#) : `uint8_t` { [io::operationMode::master](#) = 0, [io::operationMode::slave](#), [io::operationMode::submaster](#), [io::operationMode::disable](#) }
- enum [io::clockPrescaler](#) : `uint8_t` { [io::clockPrescaler::PS_4](#) = 0, [io::clockPrescaler::PS_16](#), [io::clockPrescaler::PS_64](#), [io::clockPrescaler::PS_128](#), [io::clockPrescaler::PS_2](#), [io::clockPrescaler::PS_8](#), [io::clockPrescaler::PS_32](#) }
- enum [io::dataMode](#) : `uint8_t` { [io::dataMode::mode_0](#) = 0, [io::dataMode::mode_1](#), [io::dataMode::mode_2](#), [io::dataMode::mode_3](#) }
- enum [io::dataOrder](#) : `uint8_t` { [io::dataOrder::first_MSB](#) = 0, [io::dataOrder::first_LSB](#) }

7.59.1 Detailed Description

Header file of the SPI class.

Usage example (test): `#include "MCU.h" #include "SPI.h"`

```
#define SPI_SCK 5 #define SPI_MISO 4 #define SPI_MOSI 3 #define SPI_SS 2
```

```
int main(void) {
```

```
    Init initialize MCU core::MCU::init\(\); instantiate a SPI object io::SPI &myISP = io::SPI::getInstance\(io::Pin\(SPI\_SCK,io::PortB\),  

io::Pin\(SPI\_MISO,io::PortB\), io::Pin\(SPI\_MOSI,io::PortB\), io::Pin\(SPI\_SS,io::PortB\)\);
```

```
    myISP.selectClockPrescaler(io::clockPrescaler::PS\_128); myISP.selectDataMode(io::dataMode::mode\_0); myISP←  

    P.selectDataOrder(io::dataOrder::first\_LSB); myISP.selectOperationMode(io::operationMode::master);
```

```
    myISP.masterSendByte(0x03);
```

```
    Mainloop while (1) {
```

```
    } return 0; }
```

Basic class for IO abstraction of Pin and Port

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [SPI.h](#).

7.60 SPI.h

```

00001
00048 #ifndef SPI_H
00049 #define SPI_H
00050 #include "ha_base.h"
00051 #include "Pin.h"
00052
00053 namespace io
00054 {
00055
00056 enum class operationMode : uint8_t {
00057     master=0,
00058     slave,
00059     submaster,
00060     disable,
00061 };
00062
00063 enum class clockPrescaler : uint8_t {
00064     PS_4 = 0,
00065     PS_16,
00066     PS_64,
00067     PS_128,
00068     PS_2,
00069     PS_8,
00070     PS_32
00071 };
00072
00073 enum class dataMode : uint8_t {
00074     mode_0 = 0,
00075     mode_1,
00076     mode_2,
00077     mode_3,
00078 };
00079
00080 enum class dataOrder : uint8_t {
00081     first_MSB = 0,
00082     first_LSB
00083 };
00084
00085
00086 class SPI
00087 {
00088 public:
00090     static SPI& getInstance(const io::Pin &ar_pinSCK,
00091                             const io::Pin &ar_pinMISO,
00092                             const io::Pin &ar_pinMOSI,
00093                             const io::Pin &ar_pinSS);
00094
00095     void selectDataMode(const dataMode& ar_dataMode);
00096
00097     void selectDataOrder(const dataOrder& ar_dataOrder);
00098
00099     void selectOperationMode(const operationMode& ar_operationMode);
00100
00101     void selectClockPrescaler(const clockPrescaler& ar_clockPrescaler);
00102
00103     void selectSlave(const uint8_t a_select);
00104
00107     uint8_t writeCollision();
00108
00111     uint8_t transferComplete();
00112
00113
00114     static void enableTransferCompleteInterrupt(const uint8_t a_enable);
00115
00116     void masterSendByte(const uint8_t &ar_byte);

```

```

00117
00118     void masterReceiveByte(uint8_t &ar_byte);
00119
00120     void slaveReceiveByte(uint8_t &ar_byte);
00121
00124     static void transferCompleteServiceRoutine() __asm__(STR(SPI_TRANSFER_COMPLETE_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00125
00126
00127
00128 private:
00137     SPI(const io::Pin &ar_pinSCK,
00138         const io::Pin &ar_pinMISO,
00139         const io::Pin &ar_pinMOSI,
00140         const io::Pin &ar_pinSS);
00141
00144     ~SPI();
00145
00148     SPI(const SPI&);
00149
00152     const SPI& operator=(const SPI&);
00153
00154     static volatile uint8_t m_data;
00155
00156     io::Pin m_pinSCK;
00157     io::Pin m_pinMISO;
00158     io::Pin m_pinMOSI;
00159     io::Pin m_pinSS;
00167 };
00168
00169 }
00170 #endif // SPI_H

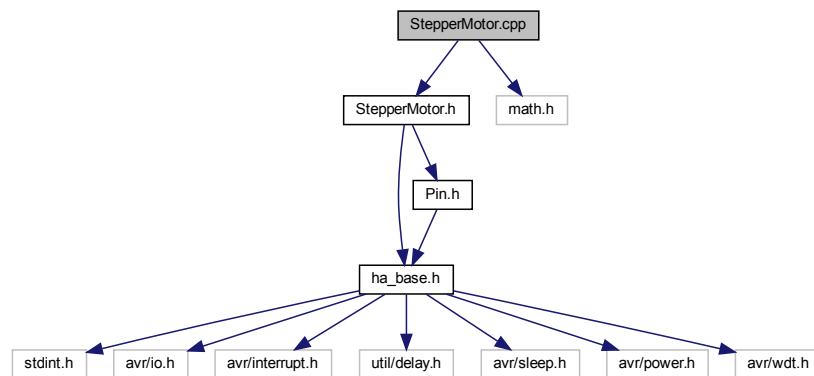
```

7.61 StepperMotor.cpp File Reference

```
#include "StepperMotor.h"
```

```
#include <math.h>
```

Include dependency graph for StepperMotor.cpp:



7.62 StepperMotor.cpp

```

00001 #include "StepperMotor.h"
00002 #include <math.h>
00003
00004 // TODO: steps to angle
00005 // TODO: maximum speed
00006 // TODO: speed and acceleration profiles
00007
00008 component::StepperMotor::StepperMotor(const mode &ar_mode,
00009                                         const io::Pin &ar_pinCoill,

```

```

00010                                     const io::Pin &ar_pinCoil2,
00011                                     const io::Pin &ar_pinCoil3,
00012                                     const io::Pin &ar_pinCoil4)
00013     : m_pinCoil1(ar_pinCoil1),
00014       m_pinCoil2(ar_pinCoil2),
00015       m_pinCoil3(ar_pinCoil3),
00016       m_pinCoil4(ar_pinCoil4),
00017       stepMode(ar_mode)
00018 {
00019     m_pinCoil1.toOutput();
00020     m_pinCoil2.toOutput();
00021     m_pinCoil3.toOutput();
00022     m_pinCoil4.toOutput();
00023     m_goalReached = 0;
00024     m_currentPos = 0;
00025 }
00026
00027
00028 }
00029
00030 component::StepperMotor::~StepperMotor()
00031 {
00032 }
00033
00034
00035 void component::StepperMotor::setCurrentPos(uint16_t a_currentPos)
00036 {
00037     m_currentPos = a_currentPos;
00038 }
00039
00040 uint16_t component::StepperMotor::currentPos()
00041 {
00042     return m_currentPos;
00043 }
00044
00045
00046
00047 void component::StepperMotor::step(const int16_t a_step,
00048                                     const uint16_t a_speed,
00049                                     const uint16_t a_accel,
00050                                     const uint16_t a_decel)
00051 {
00052     static int16_t l_stepNumber = 0;
00053     uint8_t l_stepDelay_ms = 0;
00054     uint16_t l_step=0;
00055
00056     if (a_step<=0)
00057     {
00058         l_step = -a_step;
00059     } else
00060     {
00061         l_step = a_step;
00062     }
00063
00064     l_stepDelay_ms = computeStepDelay(l_step,
00065                                     a_speed,
00066                                     a_accel,
00067                                     a_decel);
00068
00069     if (l_stepDelay_ms>0)
00070     {
00071         if (a_step<=0)
00072         {
00073             if (l_stepNumber== -a_step)
00074             {
00075                 m_goalReached = 1;
00076             } else {
00077                 l_stepNumber++;
00078                 m_currentPos++;
00079             }
00080         } else {
00081             if (l_stepNumber == -a_step)
00082             {
00083                 m_goalReached = 1;
00084             } else {
00085                 l_stepNumber--;
00086                 m_currentPos--;
00087             }
00088         }
00089     }
00090 }
00091
00092
00093
00094
00095
00096

```

```

00097
00098     if (m_goalReached == 0)
00099     {
00100
00101         switch (stepMode)
00102         {
00103             case mode::fullStep:
00104             {
00105                 // equivalent to l_stepNumber % 4
00106                 // 1 3 5 7 <->
00107                 stepPulse(2*(l_stepNumber & 3)+1);
00108                 break;
00109             }
00110
00111             case mode::halfStep:
00112             {
00113                 // equivalent to l_stepNumber % 8
00114                 // 0 1 2 3 4 5 6 7 <->
00115                 stepPulse(l_stepNumber & 7);
00116                 break;
00117             }
00118         }
00119
00120         stepDelay(l_stepDelay_ms);
00121
00122     }
00123 }
00124
00125 }
00126
00127 uint8_t component::StepperMotor::computeStepDelay(uint16_t a_step,
00128             uint16_t a_speed,
00129             uint16_t a_accel,
00130             uint16_t a_decel)
00131 {
00132
00133
00134     uint32_t l_accelTime= (1000UL*a_speed/a_accel);
00135     uint16_t l_decelTime = (1000UL*a_speed/a_decel);
00136     int16_t l_constSpeedTime=((1000UL*a_step/a_speed)-(l_accelTime/2)-(l_decelTime/2));
00137     static uint32_t l_time=0;
00138     static uint32_t l_speed=0;
00139     static uint64_t l_speed_time_product=0;
00140     static uint64_t l_current_position=0;
00141
00142
00143
00144
00145
00146
00147
00148     if (l_constSpeedTime<0)
00149     {
00150         l_constSpeedTime=0;
00151         l_accelTime = static_cast<uint32_t>(1000UL*sqrtf(a_step/a_accel));
00152         a_speed=l_accelTime*a_accel/1000UL;
00153         l_decelTime = 1000UL*a_speed/a_decel;
00154     }
00155
00156
00157
00158
00159
00160     if (l_time<=l_accelTime)
00161     {
00162         l_speed=a_accel*l_time;
00163     }
00164
00165     else if ((l_time>l_accelTime) && (l_time<=(l_accelTime+l_constSpeedTime)))
00166     {
00167         l_speed=1000UL*a_speed;
00168     }
00169
00170     else if
00171     ((l_time>(l_accelTime+l_constSpeedTime)) && (l_time<=l_accelTime+l_constSpeedTime+l_decelTime))
00172     {
00173         l_speed= (1000UL*a_speed)-a_decel*(l_time-l_accelTime-l_constSpeedTime);
00174     }
00175
00176
00177     l_time=l_time+1;
00178
00179
00180
00181     l_speed_time_product = l_speed_time_product+l_speed;
00182

```

```

00183     if (l_speed_time_product - l_current_position >= 1000000UL)
00184     {
00185         l_current_position=l_current_position+1000000UL;
00186         return 1;
00187     }
00188     else
00189     {
00190         stepDelay(1);
00191         return 0;
00192     }
00193
00194
00195
00196
00197
00198 }
00199
00200
00201 void component::StepperMotor::step(const int16_t a_step, const uint16_t a_speed)
00202 {
00203     static int16_t l_stepNumber = 0;
00204     static uint8_t l_stepDelay_ms = static_cast<uint8_t>(1000UL/a_speed);
00205
00206     if (a_step<=0)
00207     {
00208         if (l_stepNumber== -a_step)
00209         {
00210             m_goalReached = 1;
00211
00212         } else {
00213             l_stepNumber++;
00214             m_currentPos++;
00215         }
00216
00217     } else {
00218
00219         if (l_stepNumber == -a_step)
00220         {
00221             m_goalReached = 1;
00222
00223         } else {
00224             l_stepNumber--;
00225             m_currentPos--;
00226
00227         }
00228     }
00229 }
00230
00231
00232 if (m_goalReached == 0)
00233 {
00234
00235     switch (stepMode)
00236     {
00237         case mode::fullStep:
00238         {
00239             // equivalent to l_stepNumber % 4
00240             // 1 3 5 7 <->
00241             stepPulse(2*(l_stepNumber & 3)+1);
00242             break;
00243         }
00244
00245         case mode::halfStep:
00246         {
00247             // equivalent to l_stepNumber % 8
00248             // 0 1 2 3 4 5 6 7 <->
00249             stepPulse(l_stepNumber & 7);
00250             break;
00251         }
00252     }
00253
00254     stepDelay(l_stepDelay_ms);
00255 }
00256 }
00257 }
00258
00259 void component::StepperMotor::step(const int16_t a_step, const uint16_t a_speed, const float
a_stepAngle)
00260 {
00261     static int16_t l_stepNumber = 0;
00262     static uint8_t l_stepDelay_ms = static_cast<uint8_t>(1000UL*a_stepAngle/a_speed);
00263
00264     if (a_step<=0)
00265     {
00266         if (l_stepNumber== -a_step)
00267         {
00268             m_goalReached = 1;

```

```

00269
00270     } else {
00271         l_stepNumber++;
00272         m_currentPos++;
00273     }
00274
00275
00276     } else {
00277
00278         if (l_stepNumber == -a_step)
00279         {
00280             m_goalReached = 1;
00281
00282         } else {
00283             l_stepNumber--;
00284             m_currentPos--;
00285         }
00286     }
00287 }
00288
00289
00290 if (m_goalReached == 0)
00291 {
00292
00293     switch (stepMode)
00294     {
00295         case mode::fullStep:
00296         {
00297             // equivalent to l_stepNumber % 4
00298             // 1 3 5 7 <->
00299             stepPulse(2*(l_stepNumber & 3)+1);
00300             break;
00301         }
00302
00303         case mode::halfStep:
00304         {
00305             // equivalent to l_stepNumber % 8
00306             // 0 1 2 3 4 5 6 7 <->
00307             stepPulse(l_stepNumber & 7);
00308             break;
00309         }
00310     }
00311
00312     stepDelay(l_stepDelay_ms);
00313
00314 }
00315
00316
00317 }
00318
00319
00320 void component::StepperMotor::stepPulse(const uint8_t a_stepPulse)
00321 {
00322
00323     switch (a_stepPulse) {
00324         case 0: // 1000
00325         {
00326             m_pinCoil1.setHigh();
00327             m_pinCoil2.setLow();
00328             m_pinCoil3.setLow();
00329             m_pinCoil4.setLow();
00330             break;
00331         }
00332         case 1: // 1100
00333         {
00334             m_pinCoil1.setHigh();
00335             m_pinCoil2.setHigh();
00336             m_pinCoil3.setLow();
00337             m_pinCoil4.setLow();
00338             break;
00339         }
00340         case 2: // 0100
00341         {
00342             m_pinCoil1.setLow();
00343             m_pinCoil2.setHigh();
00344             m_pinCoil3.setLow();
00345             m_pinCoil4.setLow();
00346             break;
00347         }
00348         case 3: // 0110
00349         {
00350             m_pinCoil1.setLow();
00351             m_pinCoil2.setHigh();
00352             m_pinCoil3.setHigh();
00353             m_pinCoil4.setLow();
00354             break;
00355     }

```



```

00356     case 4:      //0010
00357     {
00358         m_pinCoil1.setLow();
00359         m_pinCoil2.setLow();
00360         m_pinCoil3.setHigh();
00361         m_pinCoil4.setLow();
00362         break;
00363     }
00364     case 5:      //0011
00365     {
00366         m_pinCoil1.setLow();
00367         m_pinCoil2.setLow();
00368         m_pinCoil3.setHigh();
00369         m_pinCoil4.setHigh();
00370         break;
00371     }
00372     case 6:      //0001
00373     {
00374         m_pinCoil1.setLow();
00375         m_pinCoil2.setLow();
00376         m_pinCoil3.setLow();
00377         m_pinCoil4.setHigh();
00378         break;
00379     }
00380     case 7:      //1001
00381     {
00382         m_pinCoil1.setHigh();
00383         m_pinCoil2.setLow();
00384         m_pinCoil3.setLow();
00385         m_pinCoil4.setHigh();
00386         break;
00387     }
00388 }
00389
00390
00391 }
00392
00393
00394
00395 void component::StepperMotor::stepDelay(uint8_t a_stepDelay)
00396 {
00397     while(a_stepDelay-->0)
00398     {
00399         _delay_ms(1);
00400     }
00401 }
00402
00403 uint8_t component::StepperMotor::goalReached()
00404 {
00405     return m_goalReached;
00406 }
00407 }

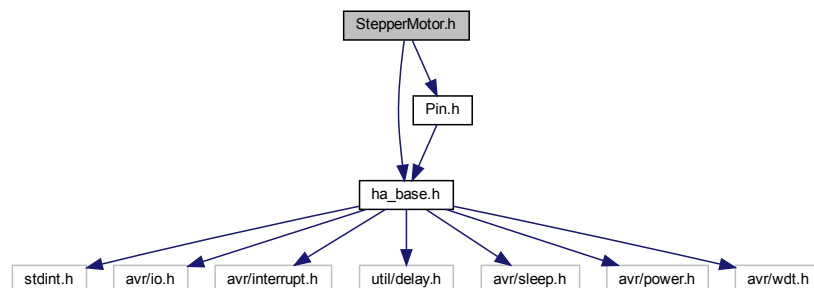
```

7.63 StepperMotor.h File Reference

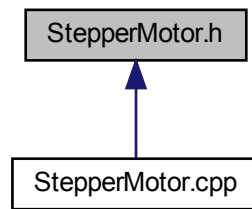
```
#include "ha_base.h"
```

```
#include "Pin.h"
```

Include dependency graph for StepperMotor.h:



This graph shows which files directly or indirectly include this file:



Classes

- class `component::StepperMotor`

Namespaces

- `component`

Enumerations

- enum `component::mode` : `uint8_t` { `component::mode::fullStep` =0, `component::mode::halfStep` }

7.64 StepperMotor.h

```

00001
00062 #ifndef STEPPERMOTOR_H
00063 #define STEPPERMOTOR_H
00064 #include "ha_base.h"
00065 #include "Pin.h"
00066
00067 namespace component
00068 {
00069
00070 enum class mode : uint8_t {
00071     fullStep=0,
00072     halfStep,
00073 };
00074
00075 class StepperMotor
00076 {
00077 public:
00078
00079     StepperMotor(const mode &ar_mode,
00080                 const io::Pin &ar_pinCoil1,
00081                 const io::Pin &ar_pinCoil2,
00082                 const io::Pin &ar_pinCoil3,
00083                 const io::Pin &ar_pinCoil4);
00084
00085     ~StepperMotor();
00086
00090     void step(const int16_t a_step,
00091              const uint16_t a_speed);
00092
00093     void step(const int16_t a_step,
00094              const uint16_t a_speed,
00095              const float a_stepAngle);
  
```

```

00096
00097     void step(const int16_t a_step,
00098               const uint16_t a_speed,
00099               const uint16_t a_accel,
00100               const uint16_t a_decel);
00101
00102     void stepPulse(const uint8_t a_stepPulse);
00103
00104     void stepDelay(uint8_t a_stepDelay);
00105
00106     uint8_t goalReached();
00107
00108     void setCurrentPos(uint16_t a_currentPos);
00109
00110     uint16_t currentPos();
00111
00112
00113     uint8_t computeStepDelay(uint16_t a_step,
00114                               const uint16_t a_speed,
00115                               const uint16_t a_accel,
00116                               const uint16_t a_decel);
00117
00118     uint16_t m_accelTime;
00119     uint16_t m_decelTime;
00120     uint16_t m_constSpeedTime;
00124 private:
00125
00126     //     uint8_t computeStepDelay(int16_t a_step,
00127     //                               const uint16_t a_speed,
00128     //                               const uint16_t a_accel,
00129     //                               const uint16_t a_decel);
00130
00131
00132     io::Pin m_pinCoil1;
00133     io::Pin m_pinCoil2;
00134     io::Pin m_pinCoil3;
00135     io::Pin m_pinCoil4;
00137     mode stepMode;
00138     uint8_t m_goalReached;
00139     uint16_t m_currentPos;
00144 };
00145
00146 }
00147 #endif // STEPPERMOTOR_H

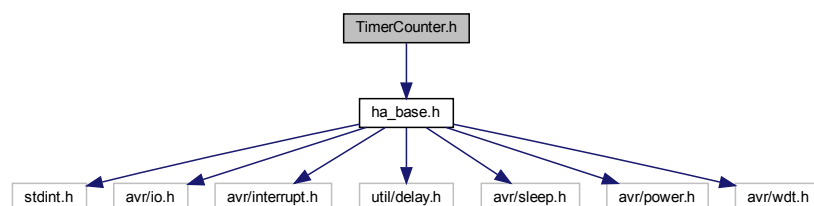
```

7.65 TimerCounter.h File Reference

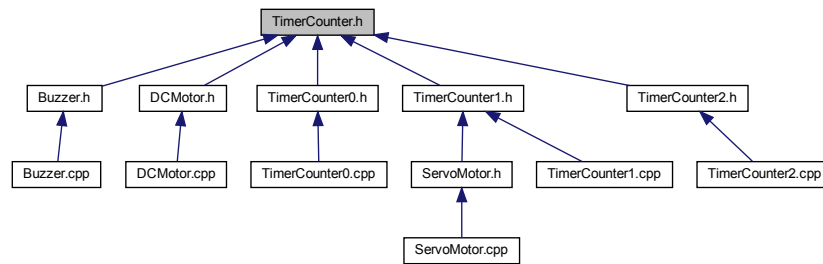
Header file of the TimerCounter class.

```
#include "ha_base.h"
```

Include dependency graph for TimerCounter.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::TimerCounter](#)

Namespaces

- [core](#)

Enumerations

- enum [core::channel](#) : uint8_t { [core::channel::A](#) =0, [core::channel::B](#) }
- enum [core::compareOutputMode](#) : uint8_t { [core::compareOutputMode::normal](#) =0, [core::compareOutputMode::toggle](#), [core::compareOutputMode::clear](#), [core::compareOutputMode::set](#) }
- enum [core::operationMode](#) : uint8_t {
[core::operationMode::normal](#) =0, [core::operationMode::PWM_PC](#), [core::operationMode::PWM_PC_8bit](#),
[core::operationMode::PWM_PC_9bit](#), [core::operationMode::PWM_PC_10bit](#), [core::operationMode::PWM_PFC_ICR](#), [core::operationMode::PWM_PFC_OCR](#),
[core::operationMode::PWM_PC_ICR](#), [core::operationMode::PWM_PC_OCR](#), [core::operationMode::fast_PWM](#), [core::operationMode::fast_PWM_8bit](#),
[core::operationMode::fast_PWM_9bit](#), [core::operationMode::fast_PWM_10bit](#), [core::operationMode::fast_PWM_ICR](#), [core::operationMode::fast_PWM_OCR](#),
[core::operationMode::CTC_OCR](#), [core::operationMode::CTC_ICR](#), [core::operationMode::interrupt](#) =1, [core::operationMode::reset](#), [core::operationMode::interrupt](#)
}
- enum [core::clockSource](#) : uint16_t {
[core::clockSource::noClock](#) =0, [core::clockSource::PS_1](#), [core::clockSource::PS_8](#), [core::clockSource::PS_32](#),
[core::clockSource::PS_64](#), [core::clockSource::PS_128](#), [core::clockSource::PS_256](#), [core::clockSource::PS_1024](#),
[core::clockSource::extern_Clock_T0_Falling_Edge](#), [core::clockSource::extern_Clock_T0_Rising_Edge](#) }

7.65.1 Detailed Description

Header file of the TimerCounter class.

Basic class for abstraction of the TimerCounter peripherals.

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Basic class for abstraction of the TimerCounter peripherals.

Usage example (Reaction Timer): #include "TimerCounter.h" #include "USART0.h" #include "PushButton.h" #include "Led.h"

```
void randomDelay(void); void printWord(uint16_t word);
```

```
instantiate the Counter object extern core::TimerCounter core::TimerCounter &myCounter = core::TimerCounter::getInstanceTimerCounter0();
```

```
instantiate the USART0 object extern io::USART0 io::USART0 &myUSART0 = io::USART0::getInstance();
```

```
#define BUFFER_SIZE 1 #define LED_NUMBER 0 #define PUSHBUTTON_NUMBER 2
```

```
int main(void) {
```

```
    Init uint16_t timerValue;
```

```
    char l_receiverBuffer[BUFFER_SIZE];
```

```
    myCounter.selectClockSource(core::timerCounter::timerCounter1, core::clockSource::PS_1024);
```

```
    / instantiate a Led object component::Led Led(io::Pin(LED_NUMBER,io::PortB));
```

```
    instantiate a Led object component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortD));
```

```
    ready to send flag uint8_t l_ready2Send = 1;
```

```
    if (myUSART0.ready2Send()) { myUSART0.sendString("Reaction Timer:\r\n"); }
```

```
    wait to send next string while (!myUSART0.ready2Send());
```

```
    if (myUSART0.ready2Send()) { myUSART0.sendString("-----\r\n"); }
```

```
    wait to send next string while (!myUSART0.ready2Send());
```

```
    if (myUSART0.ready2Send()) { myUSART0.sendString("Press any key to start.\r\n"); }
```

```
    Mainloop while (1) {
```

```
        myUSART0.receiveFrame(reinterpret_cast<uint8_t*>(l_receiverBuffer),BUFFER_SIZE);
```

```
        wait for a key press while (!myUSART0.getNumberBytesReceived()) {
```

```
    }
```

```
    reset number of bytes after extracting the received data myUSART0.resetNumberBytesReceived();
```

```
    wait to send next string while (!myUSART0.ready2Send());
```

```

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nGet ready..."); }

randomDelay();

wait to send next string while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nGo!\r\n"); }

Led.on();

myCounter.setCounter(core::timerCounter::timerCounter1,0);

if (PushButton.isPressed()) { wait to send next string while (!myUSART0.ready2Send()){}; }

if (myUSART0.ready2Send()) { myUSART0.sendString("You're only cheating yourself.\r\n"); }

} else {

wait for a button press while (!PushButton.isPressed()) {

} get counter value myCounter.getCounter(core::timerCounter::timerCounter1, &timerValue); bit shift divide by 16 =
2^4 to convert from micro to milliseconds timerValue = timerValue >> 4; print response time printWord(timerValue);
}

Led.off();

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nPress any key to try again.\r\n"); }

} return 0; }

void randomDelay(void) {

Waits for a "random" delay from 1 - 3.5 sec Requires timer 1 initialized and running It's not really random, but very
hard to control –like coin-flipping.

uint16_t counter;
__delay_ms(1000);

myCounter.getCounter(core::timerCounter::timerCounter1, &counter);
uint8_t randomTime = static_cast<uint8_t>(counter);

```

type-casting the 16-bit TCNT1 as an 8-bit number keeps only the 8 least-significant (fastest-changing) bits

```

while (--randomTime) {
__delay_ms(10);
}

void printWord(uint16_t word) {

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendByte('0' + (word / 10000));
}

while (!myUSART0.ready2Send()){};

```

```
if (myUSART0.ready2Send())
{
    myUSART0.sendByte('0' + ((word / 1000) % 10));
}

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendByte('0' + ((word / 100) % 10));
}

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendByte('0' + ((word / 10) % 10));
}

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendByte('0' + (word % 10));
}

}

void printWord(uint16_t word) {

char timerValue = '0' + (word / 10000);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue),BUFFER_SIZE);
}

timerValue = '0' + ((word / 1000) % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue),BUFFER_SIZE);
}

timerValue = '0' + ((word / 100) % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue),BUFFER_SIZE);
}

timerValue = '0' + ((word / 10) % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue),BUFFER_SIZE);
}

}
```

```

timerValue = '0' + (word % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue),BUFFER_SIZE);
}

}

```

Usage example (PWM):

```

#include "Led.h" #include "USART0.h" #include "TimerCounter1.h" #include "TimerCounter2.h"

uint8_t getNumber(const char *ap_receive);

#define LED_1 1 #define LED_2 2 #define LED_3 3 #define BUFFER_SIZE 4

int main(void) {

    Init receiver buffer char l_receiverBuffer[BUFFER_SIZE];

    instantiate Led objects component::Led Led1(io::Pin(LED_1,io::PortB)); component::Led Led2(io::Pin(LED_2,io::PortB)); component::Led Led3(io::Pin(LED_3,io::PortB));

    instantiate USART0 object io::USART0 &myUSART0 = io::USART0::getInstance();

    instantiate Timer1 object core::TimerCounter1 &myTimerCounter1 = core::TimerCounter1::getInstance(); myTimerCounter1.selectOperationMode(core::operationMode::Fast_PWM_8bit); myTimerCounter1.selectCompareOutputMode(core::channel::A,core::compareOutputMode::Clear); myTimerCounter1.selectCompareOutputMode(core::channel::B,core::compareOutputMode::Clear); instantiate Timer2 object core::TimerCounter2 &myTimerCounter2 = core::TimerCounter2::getInstance(); myTimerCounter2.selectOperationMode(core::operationMode::Fast_PWM); myTimerCounter2.selectCompareOutputMode(core::channel::A,core::compareOutputMode::Clear);

    if (myUSART0.ready2Send()) { myUSART0.sendString("-- LED PWM Demo --\r\n"); } wait to send next string while (!myUSART0.ready2Send()){

    myTimerCounter1.start(core::clockSource::PS_64); myTimerCounter2.start(core::clockSource::PS_64);

    ----- Event loop ----- // while (1) {

    if (myUSART0.ready2Send())
    {
        myUSART0.sendString("\r\nEnter (0-255) for PWM duty cycle: ");
    }

    myUSART0.receiveFrame(reinterpret_cast<uint8_t*>(l_receiverBuffer),BUFFER_SIZE);

    wait for a key press while (myUSART0.getNumberBytesReceived()<4){

    reset number of bytes after extracting the received data myUSART0.resetNumberBytesReceived();

    send back the received character if (myUSART0.ready2Send()) { myUSART0.sendFrame(reinterpret_cast<uint8_t*>(l_receiverBuffer),BUFFER_SIZE); }

    while (!myUSART0.ready2Send()){ myTimerCounter2.setOutputCompareRegister(core::channel::A,myTimerCounter1.getOutputCompareRegister(core::channel::B)); myTimerCounter1.setOutputCompareRegister(core::channel::B,myTimerCounter1.getOutputCompareRegister(core::channel::A)); myTimerCounter1.setOutputCompareRegister(core::channel::A,getNumber(l_receiverBuffer));

```



```

}
return 0;

```

```

}

```

```

uint8_t getNumber(const char *ap_receive) { Gets a numerical 0-255 from the serial port. Converts from string to
number. char hundreds = '0'; char tens = '0'; char ones = '0'; char thisChar = '0'; do { hundreds = tens; tens = ones;
ones = thisChar; thisChar = *ap_receive; ap_receive++;

```

```

} while (*ap_receive != '\r'); return (100 * (hundreds - '0') + 10 * (tens - '0') + ones - '0'); }

```

Usage example (PWM on Any Pin):

```

#include "TimerCounter0.h" #include "Led.h"

```

```

#define LED_0 0 #define LED_1 1 #define LED_2 2 #define LED_3 3

```

```

instantiate Timer0 object extern core::TimerCounter0 core::TimerCounter0 &myTimerCounter0 = core::TimerCounter0::getInstance();

```

```

instantiate Led objects extern component::Led Led0; component::Led Led0(io::Pin(LED_0,io::PortB)); ex-
tern component::Led Led1; component::Led Led1(io::Pin(LED_1,io::PortB)); extern component::Led Led2;
component::Led Led2(io::Pin(LED_2,io::PortB)); extern component::Led Led3; component::Led Led3(io::Pin(LED_3,io::PortB));

```

```

#define DELAYTIME 3

```

```

volatile uint8_t l_brightnessA; volatile uint8_t l_brightnessB;

```

```

int main(void) {

```

```

    Init uint8_t i;

```

```

    sei();

```

```

    myTimerCounter0.enableOutputCompareMatchInterrupt(core::channel::A,1); myTimerCounter0.enableOutputCompareMatchInterrupt(core::channel::B,1); myTimerCounter0.enableOverflowInterrupt(1); myTimerCounter0.start(core::clockSource::PS_1024);

```

```

    ----- Event loop ----- // while (1) {

```

```

        for (i = 0; i < 255; i++) {
            _delay_ms(DELAYTIME);
            l_brightnessA = i;
            l_brightnessB = 255 - i;
        }
        for (i = 254; i > 0; i--) {
            _delay_ms(DELAYTIME);
            l_brightnessA = i;
            l_brightnessB = 255 - i;
        }

```

```

    } return 0; }

```

```

void core::TimerCounter0::overflowServiceRoutine()
{
    Led0.on();
    Led1.on();
    Led2.on();
    Led3.on();
    myTimerCounter0.setOutputCompareRegister(core::channel::A, l_brightnessA);
    myTimerCounter0.setOutputCompareRegister(core::channel::B, l_brightnessB);
}

void core::TimerCounter0::outputCompareMatchAServiceRoutine()
{
    Led0.off();
    Led1.off();
    Led2.on();
    Led3.on();
}
void core::TimerCounter0::outputCompareMatchBServiceRoutine()
{
    Led0.on();
    Led1.on();
    Led2.off();
    Led3.off();
}

```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Basic class for abstraction of the TimerCounter peripherals.

Usage example (Reaction Timer): #include "TimerCounter.h" #include "USART0.h" #include "PushButton.h" #include "Led.h"

void randomDelay(void); void printWord(uint16_t word);

instantiate the Counter object extern [core::TimerCounter](#) [core::TimerCounter](#) &myCounter = [core::TimerCounter](#)↔
::getInstanceTimerCounter0();

instantiate the USART0 object extern [io::USART0](#) [io::USART0](#) &myUSART0 = [io::USART0::getInstance\(\)](#);

#define BUFFER_SIZE 1 #define LED_NUMBER 0 #define PUSHBUTTON_NUMBER 2

int [main](#)(void) {

Init uint16_t timerValue;

char l_receiverBuffer[BUFFER_SIZE];

myCounter.selectClockSource(core::timerCounter::timerCounter1, core::clockSource::PS_1024);

```

/ instantiate a Led object component::Led Led(io::Pin(LED_NUMBER,io::PortB));

instantiate a Led object component::PushButton PushButton(io::Pin(PUSHBUTTON_NUMBER,io::PortD));

ready to send flag uint8_t I_ready2Send = 1;

if (myUSART0.ready2Send()) { myUSART0.sendString("Reaction Timer:\r\n"); }

wait to send next string while (!myUSART0.ready2Send());

if (myUSART0.ready2Send()) { myUSART0.sendString("-----\r\n"); }

wait to send next string while (!myUSART0.ready2Send());

if (myUSART0.ready2Send()) { myUSART0.sendString("Press any key to start.\r\n"); }

Mainloop while (1) {

myUSART0.receiveFrame(reinterpret_cast<uint8_t*>(&I_receiverBuffer),BUFFER_SIZE);

wait for a key press while (!myUSART0.getNumberBytesReceived()) {

}

reset number of bytes after extracting the received data myUSART0.resetNumberBytesReceived();

wait to send next string while (!myUSART0.ready2Send());

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nGet ready..."); }

randomDelay();

wait to send next string while (!myUSART0.ready2Send());

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nGo!\r\n"); }

Led.on();

myCounter.setCounter(core::timerCounter::timerCounter1,0);

if (PushButton.isPressed()) { wait to send next string while (!myUSART0.ready2Send()); }

if (myUSART0.ready2Send()) { myUSART0.sendString("You're only cheating yourself.\r\n"); }

} else {

wait for a button press while (!PushButton.isPressed()) {

} get counter value myCounter.getCounter(core::timerCounter::timerCounter1, &timerValue); bit shift divide by 16 =
2^4 to convert from micro to milliseconds timerValue = timerValue >> 4; print response time printWord(timerValue);
}

Led.off();

while (!myUSART0.ready2Send());

if (myUSART0.ready2Send()) { myUSART0.sendString("\r\nPress any key to try again.\r\n"); }

} return 0; }

void randomDelay(void) {

Waits for a "random" delay from 1 - 3.5 sec Requires timer 1 initialized and running It's not really random, but very
hard to control –like coin-flipping.

```

```
uint16_t counter;
_delay_ms(1000);

myCounter.getCounter(core::timerCounter::timerCounter1, &counter);
uint8_t randomTime = static_cast<uint8_t>(counter);
```

type-casting the 16-bit TCNT1 as an 8-bit number keeps only the 8 least-significant (fastest-changing) bits

```
while (--randomTime) {
    _delay_ms(10);
}

void printWord(uint16_t word) {

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendByte('0' + (word / 10000));
    }

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendByte('0' + ((word / 1000) % 10));
    }

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendByte('0' + ((word / 100) % 10));
    }

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendByte('0' + ((word / 10) % 10));
    }

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendByte('0' + (word % 10));
    }
}

void printWord(uint16_t word) {

    char timerValue = '0' + (word / 10000);

    while (!myUSART0.ready2Send()){};

    if (myUSART0.ready2Send())
    {
        myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue), BUFFER_SIZE);
    }

    timerValue = '0' + ((word / 1000) % 10);

    while (!myUSART0.ready2Send()){};
```

```

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue), BUFFER_SIZE);
}

timerValue = '0' + ((word / 100) % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue), BUFFER_SIZE);
}

timerValue = '0' + ((word / 10) % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue), BUFFER_SIZE);
}

timerValue = '0' + (word % 10);

while (!myUSART0.ready2Send()){};

if (myUSART0.ready2Send())
{
    myUSART0.sendFrame(reinterpret_cast<uint8_t*>(&timerValue), BUFFER_SIZE);
}

}

```

Usage example (Reaction Timer):

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [TimerCounter.h](#).

7.66 TimerCounter.h

```

00001
00039
00461 #ifndef TIMER_COUNTER_H
00462 #define TIMER_COUNTER_H
00463 #include "ha_base.h"
00464
00465
00466 namespace core
00467 {
00468
00469
00470 enum class channel : uint8_t {
00471     A=0,

```

```

00472     B,
00473 };
00474
00475
00476 enum class compareOutputMode : uint8_t {
00477     normal=0,
00478     toggle,
00479     clear,
00480     set,
00481 };
00482
00483
00484
00485 enum class operationMode : uint8_t {
00486     normal=0,
00487     PWM_PC,
00488     PWM_PC_8bit,
00489     PWM_PC_9bit,
00490     PWM_PC_10bit,
00491     PWM_PFC_ICR,
00492     PWM_PFC_OCR,
00493     PWM_PC_ICR,
00494     PWM_PC_OCR,
00495     fast_PWM,
00496     fast_PWM_8bit,
00497     fast_PWM_9bit,
00498     fast_PWM_10bit,
00499     fast_PWM_ICR,
00500     fast_PWM_OCR,
00501     CTC_OCR,
00502     CTC_ICR,
00503 };
00504 enum class clockSource : uint16_t {
00505     noClock=0,
00506     PS_1,
00507     PS_8,
00508     PS_32,
00509     PS_64,
00510     PS_128,
00511     PS_256,
00512     PS_1024,
00513     extern_Clock_T0_Falling_Edge,
00514     extern_Clock_T0_Rising_Edge,
00515 };
00516
00517 class TimerCounter
00518 {
00519
00520 public:
00521
00522
00523     virtual void selectOperationMode(const operationMode &ar_operationMode) = 0;
00524
00525     virtual void start() = 0;
00526
00527     virtual void stop() = 0;
00528
00529     virtual void selectClockSource(const clockSource &ar_clockSource) = 0;
00530
00531     virtual void selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode) = 0;
00532
00533     virtual void setCounter(const uint16_t &ar_dataBuffer) = 0;
00534
00535     virtual uint16_t getCounter() const = 0;
00536
00537     virtual void setOutputCompareRegister(const channel &ar_channel, const uint16_t &ar_dataBuffer) =
0;
00538
00539     virtual uint16_t getOutputCompareRegister(const channel &ar_channel) const = 0;
00540
00541     virtual void enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t a_enable)
= 0;
00542
00543     virtual void enableOverflowInterrupt(const uint8_t a_enable) = 0;
00544
00545     virtual uint16_t getClockPrescaler() = 0;
00546
00547 protected:
00548
00549 private:
00550
00551
00552
00553
00554 };
00555

```

```

00556 }
00557
00558
00559 #endif

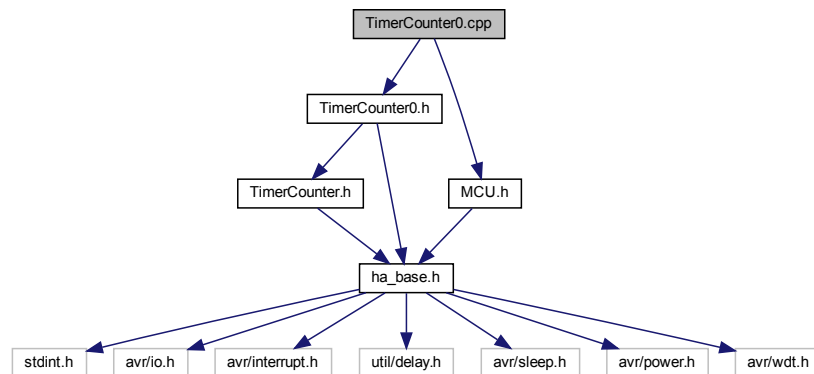
```

7.67 TimerCounter0.cpp File Reference

```
#include "TimerCounter0.h"
```

```
#include "MCU.h"
```

Include dependency graph for TimerCounter0.cpp:



7.68 TimerCounter0.cpp

```

00001 #include "TimerCounter0.h"
00002 #include "MCU.h"
00003
00004
00005 core::TimerCounter0& core::TimerCounter0::getInstance(const channel &ar_channel,
00006                                                         const operationMode &ar_operationMode,
00007                                                         const clockSource &ar_clockSource,
00008                                                         const compareOutputMode &ar_compareOutputMode)
00009 {
00010     static TimerCounter0 l_instance(ar_channel,
00011                                     ar_operationMode,
00012                                     ar_clockSource,
00013                                     ar_compareOutputMode);
00014
00015     return l_instance;
00016 }
00017
00018 }
00019
00020 core::TimerCounter0::TimerCounter0(const channel &ar_channel,
00021                                     const operationMode &ar_operationMode,
00022                                     const clockSource &ar_clockSource,
00023                                     const compareOutputMode& ar_compareOutputMode)
00024 {
00025     core::MCU::enableTimerCounter0(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel, ar_compareOutputMode);
00030
00031
00032
00033 }
00034 core::TimerCounter0::~TimerCounter0()
00035 {
00036
00037 }

```

```
00038
00039 void core::TimerCounter0::selectClockSource(const clockSource &ar_clockSource)
00040 {
00041     switch (ar_clockSource)
00042     {
00043         case core::clockSource::noClock:
00044         {
00045             m_clockPrescaler=0;
00046             m_clockSource=0;
00047             break;
00048         }
00049         case core::clockSource::PS_1:
00050         {
00051             m_clockPrescaler=1;
00052             m_clockSource=1;
00053             break;
00054         }
00055         case core::clockSource::PS_8:
00056         {
00057             m_clockPrescaler=8;
00058             m_clockSource=2;
00059             break;
00060         }
00061         case core::clockSource::PS_64:
00062         {
00063             m_clockPrescaler=64;
00064             m_clockSource=3;
00065             break;
00066         }
00067         case core::clockSource::PS_256:
00068         {
00069             m_clockPrescaler=256;
00070             m_clockSource=4;
00071             break;
00072         }
00073         case core::clockSource::PS_1024:
00074         {
00075             m_clockPrescaler=1024;
00076             m_clockSource=5;
00077             break;
00078         }
00079         case core::clockSource::extern_Clock_T0_Falling_Edge:
00080         {
00081             m_clockPrescaler=0;
00082             m_clockSource=6;
00083             break;
00084         }
00085         case core::clockSource::extern_Clock_T0_Rising_Edge:
00086         {
00087             m_clockPrescaler=0;
00088             m_clockSource=7;
00089             break;
00090         }
00091     }
00092 }
00093
00094 }
00095
00096 void core::TimerCounter0::selectOperationMode(const operationMode &ar_operationMode)
00097 {
00098     switch (ar_operationMode)
00099     {
00100         case core::operationMode::normal:
00101         {
00102             TIMER0_SELECT_OPERATION_MODE(0);
00103             break;
00104         }
00105         case core::operationMode::PWM_PC:
00106         {
00107             TIMER0_SELECT_OPERATION_MODE(1);
00108             break;
00109         }
00110         case core::operationMode::CTC_OCR:
00111         {
00112             TIMER0_SELECT_OPERATION_MODE(2);
00113             break;
00114         }
00115         case core::operationMode::fast_PWM:
00116         {
00117             TIMER0_SELECT_OPERATION_MODE(3);
00118             break;
00119         }
00120         case core::operationMode::PWM_PC_OCR:
00121         {
00122             TIMER0_SELECT_OPERATION_MODE(5);
00123             break;
00124         }
00125     }
00126 }
```



```

00125         case core::operationMode::fast_PWM_OCR:
00126         {
00127             TIMER0_SELECT_OPERATION_MODE(7);
00128             break;
00129         }
00130
00131     }
00132
00133 }
00134
00135
00136 void core::TimerCounter0::start()
00137 {
00138     TIMER0_SELECT_CLOCK_SOURCE(m_clockSource);
00139 }
00140
00141 uint16_t core::TimerCounter0::getClockPrescaler()
00142 {
00143     return m_clockPrescaler;
00144 }
00145
00146 void core::TimerCounter0::stop()
00147 {
00148     TIMER0_STOP;
00149 }
00150
00151
00152 void core::TimerCounter0::selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode)
00153 {
00154     switch (ar_channel)
00155     {
00156         case core::channel::A:
00157         {
00158             TIMER0_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00159             break;
00160         }
00161         case core::channel::B:
00162         {
00163             TIMER0_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00164             break;
00165         }
00166     }
00167 }
00168
00169
00170
00171 void core::TimerCounter0::setCounter(const uint16_t &ar_dataBuffer)
00172 {
00173     TCNT0 = static_cast<uint8_t>(ar_dataBuffer);
00174 }
00175
00176 uint16_t core::TimerCounter0::getCounter() const
00177 {
00178     return TCNT0;
00179 }
00180
00181 void core::TimerCounter0::setOutputCompareRegister(const channel &ar_channel, const uint16_t
&ar_dataBuffer)
00182 {
00183     switch (ar_channel)
00184     {
00185         case core::channel::A:
00186         {
00187             OCR0A = static_cast<uint8_t>(ar_dataBuffer);
00188             break;
00189         }
00190         case core::channel::B:
00191         {
00192             OCR0B = static_cast<uint8_t>(ar_dataBuffer);
00193             break;
00194         }
00195     }
00196 }
00197
00198
00199
00200
00201 uint16_t core::TimerCounter0::getOutputCompareRegister(const channel &ar_channel) const
00202 {
00203     switch (ar_channel)
00204     {
00205         case core::channel::A:
00206         {
00207             return OCR0A;
00208         }
00209         case core::channel::B:

```

```

00210     {
00211         return OCR0B;
00212     }
00213 }
00214 }
00215
00216 void core::TimerCounter0::enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t
a_enable)
00217 {
00218     switch (ar_channel)
00219     {
00220         case core::channel::A:
00221         {
00222             if (a_enable) {
00223
00224                 TIMER0_ENABLE_COM_CHANNEL_A_INTERRUPT;
00225
00226             } else {
00227
00228                 TIMER0_DISABLE_COM_CHANNEL_A_INTERRUPT;
00229             }
00230             break;
00231         }
00232         case core::channel::B:
00233         {
00234             if (a_enable) {
00235
00236                 TIMER0_ENABLE_COM_CHANNEL_B_INTERRUPT;
00237
00238             } else {
00239
00240                 TIMER0_DISABLE_COM_CHANNEL_B_INTERRUPT;
00241             }
00242             break;
00243         }
00244     }
00245 }
00246
00247 }
00248
00249
00250
00251 void core::TimerCounter0::enableOverflowInterrupt(const uint8_t a_enable)
00252 {
00253
00254     if (a_enable) {
00255
00256         TIMER0_ENABLE_OVERFLOW_INTERRUPT;
00257
00258     } else {
00259
00260         TIMER0_DISABLE_OVERFLOW_INTERRUPT;
00261     }
00262 }
00263 }

```

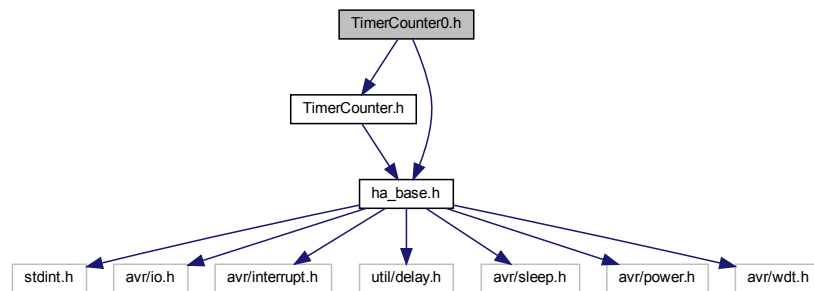
7.69 TimerCounter0.h File Reference

```

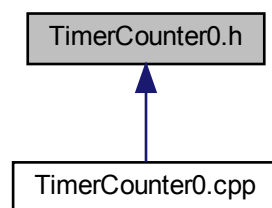
#include "TimerCounter.h"
#include "ha_base.h"

```

Include dependency graph for TimerCounter0.h:



This graph shows which files directly or indirectly include this file:



Classes

- class `core::TimerCounter0`

Namespaces

- `core`

7.70 TimerCounter0.h

```

00001
00039
00268 #ifndef TIMER_COUNTER0_H
00269 #define TIMER_COUNTER0_H
00270 #include "TimerCounter.h"
00271 #include "ha_base.h"
00272
00273
00274
00275 namespace core
00276 {
00277
00278
00279 class TimerCounter0 : public TimerCounter
  
```

```

00280 {
00281
00282 public:
00283
00284     static TimerCounter0& getInstance(const channel &ar_channel = channel::A,
00285                                     const operationMode &ar_operationMode = operationMode::normal,
00286                                     const clockSource &ar_clockSource= clockSource::noClock,
00287                                     const compareOutputMode& ar_compareOutputMode =
compareOutputMode::normal);
00288
00289     void selectOperationMode(const operationMode &ar_operationMode) override;
00290
00291     void start() override;
00292
00293     void stop() override;
00294
00295     void selectClockSource(const clockSource &ar_clockSource) override;
00296
00297     void selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode) override;
00298
00299     void setCounter(const uint16_t &ar_dataBuffer) override;
00300
00301     uint16_t getCounter() const override;
00302
00303     void setOutputCompareRegister(const channel &ar_channel, const uint16_t &ar_dataBuffer) override;
00304
00305     uint16_t getOutputCompareRegister(const channel &ar_channel) const override;
00306
00307     void enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t a_enable)
override;
00308
00309     void enableOverflowInterrupt(const uint8_t a_enable) override;
00310
00311     uint16_t getClockPrescaler() override;
00312
00313     static void outputCompareMatchAServiceRoutine() __asm__(STR(TIMERO_COM_CHANNEL_A_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00314
00315     static void outputCompareMatchBServiceRoutine() __asm__(STR(TIMERO_COM_CHANNEL_B_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00316
00317     static void overflowServiceRoutine() __asm__(STR(TIMERO_OVERFLOW_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00318
00319
00320
00321 protected:
00322
00323 private:
00324
00325     TimerCounter0(const channel &ar_channel,
00326                  const operationMode &ar_operationMode,
00327                  const clockSource &ar_clockSource,
00328                  const compareOutputMode& ar_compareOutputMode);
00329
00330     ~TimerCounter0();
00331
00332     TimerCounter0(const TimerCounter0&);
00333
00334     const TimerCounter0& operator=(const TimerCounter0&);
00335
00336     uint16_t m_clockPrescaler;
00337
00338     uint8_t m_clockSource;
00339
00340 };
00341
00342
00343
00344
00345
00346 };
00347
00348 }
00349
00350
00351 #endif

```

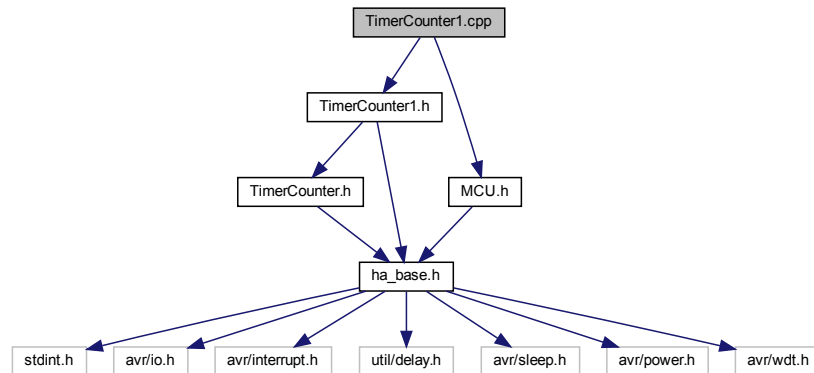
7.71 TimerCounter1.cpp File Reference

```

#include "TimerCounter1.h"
#include "MCU.h"

```

Include dependency graph for TimerCounter1.cpp:



7.72 TimerCounter1.cpp

```

00001 #include "TimerCounter1.h"
00002 #include "MCU.h"
00003
00004
00005 core::TimerCounter1& core::TimerCounter1::getInstance(const channel &ar_channel,
00006                                                         const operationMode &ar_operationMode,
00007                                                         const clockSource &ar_clockSource,
00008                                                         const compareOutputMode& ar_compareOutputMode)
00009 {
00010     static TimerCounter1 l_instance(ar_channel,
00011                                     ar_operationMode,
00012                                     ar_clockSource,
00013                                     ar_compareOutputMode);
00014
00015     return l_instance;
00016 }
00017
00018 }
00019
00020 core::TimerCounter1::TimerCounter1(const channel &ar_channel,
00021                                     const operationMode &ar_operationMode,
00022                                     const clockSource &ar_clockSource,
00023                                     const compareOutputMode& ar_compareOutputMode)
00024 {
00025     core::MCU::enableTimerCounter1(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel, ar_compareOutputMode);
00030 }
00031
00032 }
00033 core::TimerCounter1::~TimerCounter1()
00034 {
00035 }
00036 }
00037
00038 void core::TimerCounter1::selectClockSource(const clockSource &ar_clockSource)
00039 {
00040     switch (ar_clockSource)
00041     {
00042     case core::clockSource::noClock:
00043     {
00044         m_clockPrescaler=0;
00045         m_clockSource=0;
00046         break;
00047     }
00048     case core::clockSource::PS_1:
00049     {
00050         m_clockPrescaler=1;
00051         m_clockSource=1;
00052         break;
00053     }
  
```

```

00054         case core::clockSource::PS_8:
00055         {
00056             m_clockPrescaler=8;
00057             m_clockSource=2;
00058             break;
00059         }
00060         case core::clockSource::PS_64:
00061         {
00062             m_clockPrescaler=64;
00063             m_clockSource=3;
00064             break;
00065         }
00066         case core::clockSource::PS_256:
00067         {
00068             m_clockPrescaler=256;
00069             m_clockSource=4;
00070             break;
00071         }
00072         case core::clockSource::PS_1024:
00073         {
00074             m_clockPrescaler=1024;
00075             m_clockSource=5;
00076             break;
00077         }
00078         case core::clockSource::extern_Clock_T0_Falling_Edge:
00079         {
00080             m_clockPrescaler=0;
00081             m_clockSource=6;
00082             break;
00083         }
00084         case core::clockSource::extern_Clock_T0_Rising_Edge:
00085         {
00086             m_clockPrescaler=0;
00087             m_clockSource=7;
00088             break;
00089         }
00090     }
00091 }
00092
00093 }
00094
00095 void core::TimerCounter1::selectOperationMode(const operationMode &ar_operationMode)
00096 {
00097     switch (ar_operationMode)
00098     {
00099         case core::operationMode::normal:
00100         {
00101             TIMER1_SELECT_OPERATION_MODE(0);
00102             break;
00103         }
00104         case core::operationMode::PWM_PC_8bit:
00105         {
00106             TIMER1_SELECT_OPERATION_MODE(1);
00107             break;
00108         }
00109         case core::operationMode::PWM_PC_9bit:
00110         {
00111             TIMER1_SELECT_OPERATION_MODE(2);
00112             break;
00113         }
00114         case core::operationMode::PWM_PC_10bit:
00115         {
00116             TIMER1_SELECT_OPERATION_MODE(3);
00117             break;
00118         }
00119         case core::operationMode::CTC_OCR:
00120         {
00121             TIMER1_SELECT_OPERATION_MODE(4);
00122             break;
00123         }
00124         case core::operationMode::fast_PWM_8bit:
00125         {
00126             TIMER1_SELECT_OPERATION_MODE(5);
00127             break;
00128         }
00129         case core::operationMode::fast_PWM_9bit:
00130         {
00131             TIMER1_SELECT_OPERATION_MODE(6);
00132             break;
00133         }
00134         case core::operationMode::fast_PWM_10bit:
00135         {
00136             TIMER1_SELECT_OPERATION_MODE(7);
00137             break;
00138         }
00139         case core::operationMode::PWM_PFC_ICR:
00140         {

```

```

00141         TIMER1_SELECT_OPERATION_MODE(8);
00142         break;
00143     }
00144     case core::operationMode::PWM_PFC_OCR:
00145     {
00146         TIMER1_SELECT_OPERATION_MODE(9);
00147         break;
00148     }
00149     case core::operationMode::PWM_PC_ICR:
00150     {
00151         TIMER1_SELECT_OPERATION_MODE(10);
00152         break;
00153     }
00154     case core::operationMode::PWM_PC_OCR:
00155     {
00156         TIMER1_SELECT_OPERATION_MODE(11);
00157         break;
00158     }
00159     case core::operationMode::CTC_ICR:
00160     {
00161         TIMER1_SELECT_OPERATION_MODE(12);
00162         break;
00163     }
00164     case core::operationMode::fast_PWM_ICR:
00165     {
00166         TIMER1_SELECT_OPERATION_MODE(14);
00167         break;
00168     }
00169     case core::operationMode::fast_PWM_OCR:
00170     {
00171         TIMER1_SELECT_OPERATION_MODE(15);
00172         break;
00173     }
00174 }
00175 }
00176
00177
00178 }
00179
00180
00181 void core::TimerCounter1::start()
00182 {
00183     TIMER1_SELECT_CLOCK_SOURCE(m_clockSource);
00184 }
00185
00186 uint16_t core::TimerCounter1::getClockPrescaler()
00187 {
00188     return m_clockPrescaler;
00189 }
00190
00191 void core::TimerCounter1::stop()
00192 {
00193     TIMER1_STOP;
00194 }
00195
00196
00197 void core::TimerCounter1::selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode)
00198 {
00199     switch (ar_channel)
00200     {
00201         case core::channel::A:
00202         {
00203             TIMER1_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00204             break;
00205         }
00206         case core::channel::B:
00207         {
00208             TIMER1_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00209             break;
00210         }
00211     }
00212 }
00213 }
00214
00215
00216 void core::TimerCounter1::setCounter(const uint16_t &ar_dataBuffer)
00217 {
00218     TCNT1 = ar_dataBuffer;
00219 }
00220
00221 uint16_t core::TimerCounter1::getCounter() const
00222 {
00223     return TCNT1;
00224 }
00225
00226 void core::TimerCounter1::setOutputCompareRegister(const channel &ar_channel, const uint16_t

```

```

        &ar_dataBuffer)
00227 {
00228     switch (ar_channel)
00229     {
00230         case core::channel::A:
00231         {
00232             OCR1A = ar_dataBuffer;
00233             break;
00234         }
00235         case core::channel::B:
00236         {
00237             OCR1B = ar_dataBuffer;
00238             break;
00239         }
00240     }
00241 }
00242
00243
00244
00245 uint16_t core::TimerCounter1::getOutputCompareRegister(const channel &ar_channel) const
00246 {
00247     switch (ar_channel)
00248     {
00249         case core::channel::A:
00250         {
00251             return OCR1A;
00252         }
00253         case core::channel::B:
00254         {
00255             return OCR1B;
00256         }
00257     }
00258 }
00259
00260 void core::TimerCounter1::enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t
a_enable)
00261 {
00262     switch (ar_channel)
00263     {
00264         case core::channel::A:
00265         {
00266             if (a_enable) {
00267
00268                 TIMER1_ENABLE_COM_CHANNEL_A_INTERRUPT;
00269
00270             } else {
00271
00272                 TIMER1_DISABLE_COM_CHANNEL_A_INTERRUPT;
00273             }
00274             break;
00275         }
00276         case core::channel::B:
00277         {
00278             if (a_enable) {
00279
00280                 TIMER1_ENABLE_COM_CHANNEL_B_INTERRUPT;
00281
00282             } else {
00283
00284                 TIMER1_DISABLE_COM_CHANNEL_B_INTERRUPT;
00285             }
00286             break;
00287         }
00288     }
00289 }
00290
00291 }
00292
00293
00294
00295 void core::TimerCounter1::enableOverflowInterrupt(const uint8_t a_enable)
00296 {
00297     if (a_enable) {
00298
00299         TIMER1_ENABLE_OVERFLOW_INTERRUPT;
00300
00301     } else {
00302
00303         TIMER1_DISABLE_OVERFLOW_INTERRUPT;
00304     }
00305 }
00306
00307 }
00308
00309 void core::TimerCounter1::enableInputCaptureInterrupt(const uint8_t a_enable)
00310 {
00311     if (a_enable) {

```



```

00312
00313     TIMER1_ENABLE_INPUT_CAPTURE_INTERRUPT;
00314
00315 } else {
00316
00317     TIMER1_DISABLE_INPUT_CAPTURE_INTERRUPT;
00318 }
00319 }
00320
00321 void core::TimerCounter1::setInputCaptureRegister(const uint16_t &ar_dataBuffer)
00322 {
00323     ICR1 = ar_dataBuffer;
00324 }
00325
00326
00327 uint16_t core::TimerCounter1::getInputCaptureRegister() const
00328 {
00329     return ICR1;
00330 }

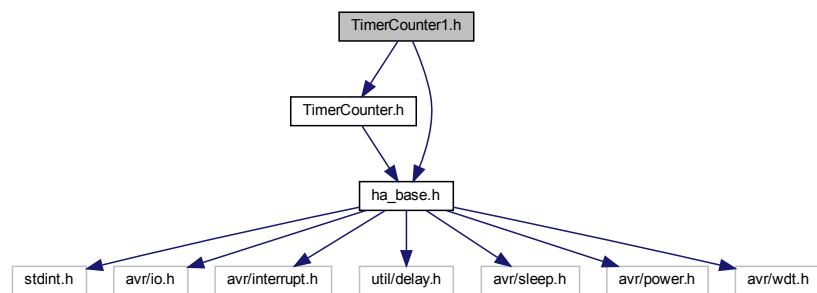
```

7.73 TimerCounter1.h File Reference

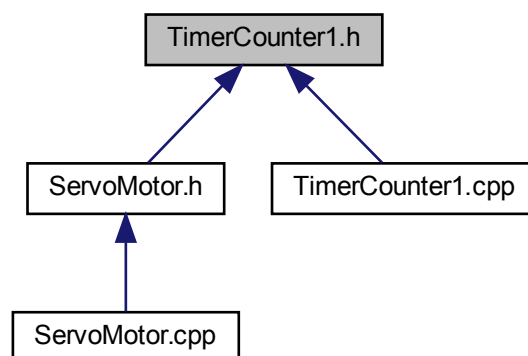
```
#include "TimerCounter.h"
```

```
#include "ha_base.h"
```

Include dependency graph for TimerCounter1.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::TimerCounter1](#)

Namespaces

- [core](#)

7.74 TimerCounter1.h

```

00001
00039
00268 #ifndef TIMER_COUNTER1_H
00269 #define TIMER_COUNTER1_H
00270 #include "TimerCounter.h"
00271 #include "ha_base.h"
00272
00273
00274
00275 namespace core
00276 {
00277
00278
00279 class TimerCounter1 : public TimerCounter
00280 {
00281
00282 public:
00283
00284     static TimerCounter1& getInstance(const channel &ar_channel = channel::A,
00285                                     const operationMode &ar_operationMode = operationMode::normal,
00286                                     const clockSource &ar_clockSource= clockSource::noClock,
00287                                     const compareOutputMode& ar_compareOutputMode =
00288                                     compareOutputMode::normal);
00289
00289     void selectOperationMode(const operationMode &ar_operationMode) override;
00290
00291     void start() override;
00292
00293     void stop() override;
00294
00295     void selectClockSource(const clockSource &ar_clockSource) override;
00296
00297
00298     void selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
00299 &ar_compareOutputMode) override;
00300
00301     void setCounter(const uint16_t &ar_dataBuffer) override;
00302
00303     uint16_t getCounter() const override;
00304
00305     void setOutputCompareRegister(const channel &ar_channel, const uint16_t &ar_dataBuffer) override;
00306
00307     uint16_t getOutputCompareRegister(const channel &ar_channel) const override;
00308
00309     void setInputCaptureRegister(const uint16_t &ar_dataBuffer);
00310
00311     uint16_t getInputCaptureRegister() const;
00312
00313     void enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t a_enable)
00314 override;
00315
00316     void enableOverflowInterrupt(const uint8_t a_enable) override;
00317
00318     void enableInputCaptureInterrupt(const uint8_t a_enable);
00319
00320     static void outputCompareMatchAServiceRoutine() __asm__(STR(TIMER1_COM_CHANNEL_A_INTERRUPT))
00321 __attribute__((__signal__, __used__, __externally_visible__));
00322
00323     static void outputCompareMatchBServiceRoutine() __asm__(STR(TIMER1_COM_CHANNEL_B_INTERRUPT))
00324 __attribute__((__signal__, __used__, __externally_visible__));
00325
00326     static void overflowServiceRoutine() __asm__(STR(TIMER1_OVERFLOW_INTERRUPT))
00327 __attribute__((__signal__, __used__, __externally_visible__));
00328
00329     static void inputCaptureServiceRoutine() __asm__(STR(TIMER1_INPUT_CAPTURE_INTERRUPT))
00330 __attribute__((__signal__, __used__, __externally_visible__));

```

```

00327
00328
00329
00330 protected:
00331
00332 private:
00333
00334     TimerCounter1(const channel &ar_channel,
00335                  const operationMode &ar_operationMode,
00336                  const clockSource &ar_clockSource,
00337                  const compareOutputMode& ar_compareOutputMode);
00338
00339     ~TimerCounter1();
00340
00341     TimerCounter1(const TimerCounter1&);
00342
00343     const TimerCounter1& operator=(const TimerCounter1&);
00344
00345     uint16_t m_clockPrescaler;
00346
00347     uint8_t m_clockSource;
00348
00349 };
00350
00351 #endif

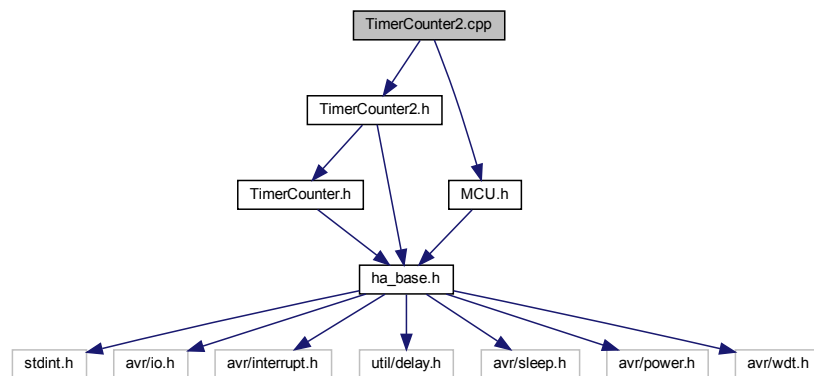
```

7.75 TimerCounter2.cpp File Reference

```
#include "TimerCounter2.h"
```

```
#include "MCU.h"
```

Include dependency graph for TimerCounter2.cpp:



7.76 TimerCounter2.cpp

```

00001 #include "TimerCounter2.h"
00002 #include "MCU.h"
00003
00004
00005 core::TimerCounter2& core::TimerCounter2::getInstance(const channel &ar_channel,
00006                                                         const operationMode &ar_operationMode,
00007                                                         const clockSource &ar_clockSource,
00008                                                         const compareOutputMode& ar_compareOutputMode)
00009 {
00010     static TimerCounter2 l_instance(ar_channel,
00011                                     ar_operationMode,
00012                                     ar_clockSource,
00013                                     ar_compareOutputMode);

```

```
00014
00015     return l_instance;
00016
00017
00018 }
00019
00020 core::TimerCounter2::TimerCounter2(const channel &ar_channel,
00021                                     const operationMode &ar_operationMode,
00022                                     const clockSource &ar_clockSource,
00023                                     const compareOutputMode& ar_compareOutputMode)
00024 {
00025     core::MCU::enableTimerCounter2(1);
00026     stop();
00027     selectOperationMode(ar_operationMode);
00028     selectClockSource(ar_clockSource);
00029     selectCompareOutputMode(ar_channel, ar_compareOutputMode);
00030
00031 }
00032 core::TimerCounter2::~TimerCounter2()
00033 {
00034
00035 }
00036
00037 void core::TimerCounter2::selectClockSource(const clockSource &ar_clockSource)
00038 {
00039     switch (ar_clockSource)
00040     {
00041         case core::clockSource::noClock:
00042         {
00043             m_clockPrescaler=0;
00044             m_clockSource=0;
00045             break;
00046         }
00047         case core::clockSource::PS_1:
00048         {
00049             m_clockPrescaler=1;
00050             m_clockSource=1;
00051             break;
00052         }
00053         case core::clockSource::PS_8:
00054         {
00055             m_clockPrescaler=8;
00056             m_clockSource=2;
00057             break;
00058         }
00059         case core::clockSource::PS_32:
00060         {
00061             m_clockPrescaler=32;
00062             m_clockSource=3;
00063             break;
00064         }
00065         case core::clockSource::PS_64:
00066         {
00067             m_clockPrescaler=64;
00068             m_clockSource=4;
00069             break;
00070         }
00071         case core::clockSource::PS_128:
00072         {
00073             m_clockPrescaler=128;
00074             m_clockSource=5;
00075             break;
00076         }
00077         case core::clockSource::PS_256:
00078         {
00079             m_clockPrescaler=256;
00080             m_clockSource=6;
00081             break;
00082         }
00083         case core::clockSource::PS_1024:
00084         {
00085             m_clockPrescaler=1024;
00086             m_clockSource=7;
00087             break;
00088         }
00089     }
00090
00091 }
00092
00093 void core::TimerCounter2::selectOperationMode(const operationMode &ar_operationMode)
00094 {
00095     switch (ar_operationMode)
00096     {
00097         case core::operationMode::normal:
00098         {
00099             TIMER2_SELECT_OPERATION_MODE(0);
00100             break;
00101         }
00102     }
00103 }
```

```

00101     }
00102     case core::operationMode::PWM_PC:
00103     {
00104         TIMER2_SELECT_OPERATION_MODE(1);
00105         break;
00106     }
00107     case core::operationMode::CTC_OCR:
00108     {
00109         TIMER2_SELECT_OPERATION_MODE(2);
00110         break;
00111     }
00112     case core::operationMode::fast_PWM:
00113     {
00114         TIMER2_SELECT_OPERATION_MODE(3);
00115         break;
00116     }
00117     case core::operationMode::PWM_PC_OCR:
00118     {
00119         TIMER2_SELECT_OPERATION_MODE(5);
00120         break;
00121     }
00122     case core::operationMode::fast_PWM_OCR:
00123     {
00124         TIMER2_SELECT_OPERATION_MODE(7);
00125         break;
00126     }
00127 }
00128 }
00129 }
00130 }
00131 }
00132 }
00133 void core::TimerCounter2::start()
00134 {
00135     TIMER2_SELECT_CLOCK_SOURCE(m_clockSource);
00136 }
00137 }
00138 uint16_t core::TimerCounter2::getClockPrescaler()
00139 {
00140     return m_clockPrescaler;
00141 }
00142 }
00143 }
00144 void core::TimerCounter2::stop()
00145 {
00146     TIMER2_STOP;
00147 }
00148 }
00149 }
00150 void core::TimerCounter2::selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode)
00151 {
00152     switch (ar_channel)
00153     {
00154         case core::channel::A:
00155         {
00156             TIMER2_SELECT_COM_CHANNEL_A(static_cast<uint8_t>(ar_compareOutputMode));
00157             break;
00158         }
00159         case core::channel::B:
00160         {
00161             TIMER2_SELECT_COM_CHANNEL_B(static_cast<uint8_t>(ar_compareOutputMode));
00162             break;
00163         }
00164     }
00165 }
00166 }
00167 }
00168 }
00169 }
00170 }
00171 void core::TimerCounter2::setCounter(const uint16_t &ar_dataBuffer)
00172 {
00173     TCNT2 = static_cast<uint8_t>(ar_dataBuffer);
00174 }
00175 }
00176 uint16_t core::TimerCounter2::getCounter() const
00177 {
00178     return TCNT2;
00179 }
00180 }
00181 void core::TimerCounter2::setOutputCompareRegister(const channel &ar_channel, const uint16_t
&ar_dataBuffer)
00182 {
00183     switch (ar_channel)
00184     {
00185         case core::channel::A:

```

```

00186         {
00187             OCR2A = static_cast<uint8_t>(ar_dataBuffer);
00188             break;
00189         }
00190         case core::channel::B:
00191         {
00192             OCR2B = static_cast<uint8_t>(ar_dataBuffer);
00193             break;
00194         }
00195     }
00196 }
00197
00198
00199 uint16_t core::TimerCounter2::getOutputCompareRegister(const channel &ar_channel) const
00200 {
00201     switch (ar_channel)
00202     {
00203         case core::channel::A:
00204         {
00205             return OCR2A;
00206         }
00207         case core::channel::B:
00208         {
00209             return OCR2B;
00210         }
00211     }
00212 }
00213 }
00214
00215 void core::TimerCounter2::enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t
a_enable)
00216 {
00217     switch (ar_channel)
00218     {
00219         case core::channel::A:
00220         {
00221             if (a_enable) {
00222                 TIMER2_ENABLE_COM_CHANNEL_A_INTERRUPT;
00223             } else {
00224                 TIMER2_DISABLE_COM_CHANNEL_A_INTERRUPT;
00225             }
00226             break;
00227         }
00228         case core::channel::B:
00229         {
00230             if (a_enable) {
00231                 TIMER2_ENABLE_COM_CHANNEL_B_INTERRUPT;
00232             } else {
00233                 TIMER2_DISABLE_COM_CHANNEL_B_INTERRUPT;
00234             }
00235             break;
00236         }
00237     }
00238 }
00239
00240 void core::TimerCounter2::enableOverflowInterrupt(const uint8_t a_enable)
00241 {
00242     if (a_enable) {
00243         TIMER2_ENABLE_OVERFLOW_INTERRUPT;
00244     } else {
00245         TIMER2_DISABLE_OVERFLOW_INTERRUPT;
00246     }
00247 }
00248
00249
00250 void core::TimerCounter2::enableOverflowInterrupt(const uint8_t a_enable)
00251 {
00252     if (a_enable) {
00253         TIMER2_ENABLE_OVERFLOW_INTERRUPT;
00254     } else {
00255         TIMER2_DISABLE_OVERFLOW_INTERRUPT;
00256     }
00257 }
00258
00259 void core::TimerCounter2::enableOverflowInterrupt(const uint8_t a_enable)
00260 {
00261     if (a_enable) {
00262         TIMER2_ENABLE_OVERFLOW_INTERRUPT;
00263     } else {
00264         TIMER2_DISABLE_OVERFLOW_INTERRUPT;
00265     }
00266 }

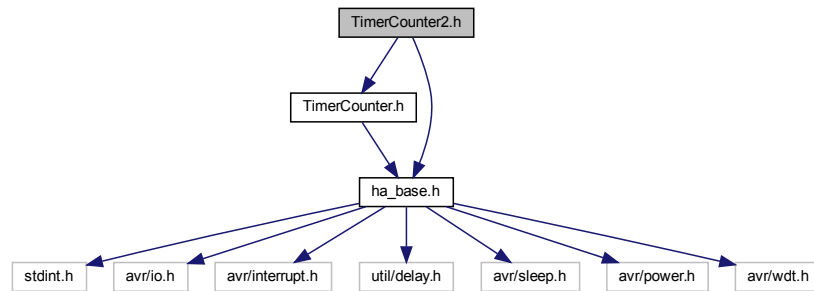
```

7.77 TimerCounter2.h File Reference

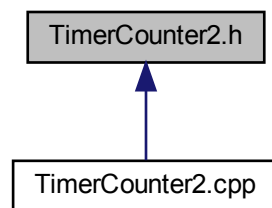
```
#include "TimerCounter.h"
```

```
#include "ha_base.h"
```

Include dependency graph for TimerCounter2.h:



This graph shows which files directly or indirectly include this file:



Classes

- class `core::TimerCounter2`

Namespaces

- `core`

7.78 TimerCounter2.h

```

00001
00039
00268 #ifndef TIMER_COUNTER2_H
00269 #define TIMER_COUNTER2_H
00270 #include "TimerCounter.h"
00271 #include "ha_base.h"
00272
00273
00274
00275 namespace core
00276 {
00277

```

```

00278
00279 class TimerCounter2 : public TimerCounter
00280 {
00281
00282 public:
00283
00284     static TimerCounter2& getInstance(const channel &ar_channel = channel::A,
00285                                     const operationMode &ar_operationMode = operationMode::normal,
00286                                     const clockSource &ar_clockSource= clockSource::noClock,
00287                                     const compareOutputMode& ar_compareOutputMode =
compareOutputMode::normal);
00288
00289     void selectOperationMode(const operationMode &ar_operationMode) override;
00290
00291     void start() override;
00292
00293     void stop() override;
00294
00295     void selectClockSource(const clockSource &ar_clockSource) override;
00296
00297     void selectCompareOutputMode(const channel &ar_channel, const compareOutputMode
&ar_compareOutputMode) override;
00298
00299     void setCounter(const uint16_t &ar_dataBuffer) override;
00300
00301     uint16_t getCounter() const override;
00302
00303     void setOutputCompareRegister(const channel &ar_channel, const uint16_t &ar_dataBuffer) override;
00304
00305     uint16_t getOutputCompareRegister(const channel &ar_channel) const override;
00306
00307     void enableOutputCompareMatchInterrupt(const channel &ar_channel, const uint8_t a_enable)
override;
00308
00309     void enableOverflowInterrupt(const uint8_t a_enable) override;
00310
00311     uint16_t getClockPrescaler() override;
00312
00313     static void outputCompareMatchAServiceRoutine() __asm__(STR(TIMER2_COM_CHANNEL_A_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00314
00315     static void outputCompareMatchBServiceRoutine() __asm__(STR(TIMER2_COM_CHANNEL_B_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00316
00317     static void overflowServiceRoutine() __asm__(STR(TIMER2_OVERFLOW_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00318
00319 protected:
00320
00321 private:
00322
00323     TimerCounter2(const channel &ar_channel,
00324                  const operationMode &ar_operationMode,
00325                  const clockSource &ar_clockSource,
00326                  const compareOutputMode& ar_compareOutputMode);
00327
00328     ~TimerCounter2();
00329
00330     TimerCounter2(const TimerCounter2&);
00331
00332     const TimerCounter2& operator=(const TimerCounter2&);
00333
00334     uint16_t m_clockPrescaler;
00335
00336     uint8_t m_clockSource;
00337
00338 };
00339
00340
00341
00342 };
00343
00344 }
00345
00346
00347 #endif

```

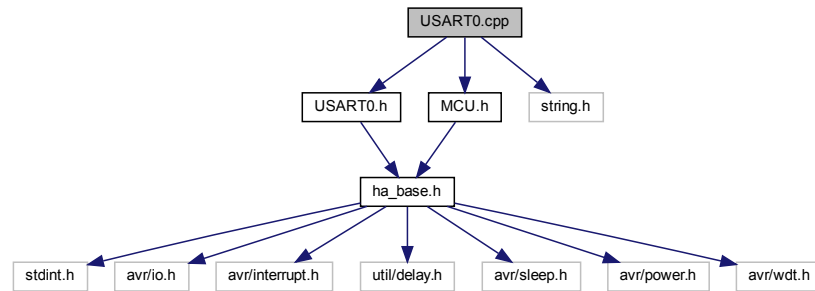
7.79 USART0.cpp File Reference

```

#include "USART0.h"
#include "MCU.h"
#include <string.h>

```


Include dependency graph for USART0.cpp:



7.80 USART0.cpp

```

00001 #include "USART0.h"
00002 #include "MCU.h"
00003 #include <string.h>
00004
00005 volatile uint8_t io::USART0::m_status = 0;
00006 const uint8_t* io::USART0::mp_data2Send = nullptr;
00007 uint8_t* io::USART0::mp_data2Receive = nullptr;
00008 uint16_t io::USART0::m_sizeData2Send = 0;
00009 uint16_t io::USART0::m_sizeData2Receive = 0;
00010 volatile uint16_t io::USART0::m_numberBytesReceived = 0;
00011 volatile uint16_t io::USART0::m_numberBytesSent = 0;
00012 volatile uint8_t io::USART0::m_ready2Send = 1;
00013
00014
00015
00016
00017 io::USART0& io::USART0::getInstance(const transmissionMode& ar_transMode,
00018                                     const communicationMode& ar_comMode,
00019                                     const frameSize& ar_frameSize,
00020                                     const stopBit& ar_stopBit,
00021                                     const parityMode& ar_parityMode)
00022 {
00023     static USART0 l_instance(ar_transMode,
00024                               ar_comMode,
00025                               ar_frameSize,
00026                               ar_stopBit,
00027                               ar_parityMode);
00028
00029     return l_instance;
00030 }
00031
00032
00033
00034 io::USART0::USART0(const transmissionMode& ar_transMode,
00035                   const communicationMode& ar_comMode,
00036                   const frameSize& ar_frameSize,
00037                   const stopBit& ar_stopBit,
00038                   const parityMode& ar_parityMode)
00039 {
00040     core::MCU::enableUSART0(1);
00041     setBaudRate();
00042     setTransmissionMode(ar_transMode);
00043     setCommunicationMode(ar_comMode);
00044     setParityMode(ar_parityMode);
00045     setFrameSize(ar_frameSize);
00046     setStopBit(ar_stopBit);
00047     sei();
00048     enableReceiveCompleteInterrupt(1);
00049 }
00050
00051
00052 io::USART0::~~USART0()
00053 {
00054 }
00055
00056
00057 void io::USART0::setBaudRate()

```

```
00058 {
00059     USART0_SET_BAUDRATE_HIGH_REGISTER;
00060     USART0_SET_BAUDRATE_LOW_REGISTER;
00061 }
00062 }
00063
00064 void io::USART0::setTransmissionMode(const transmissionMode& ar_transMode)
00065 {
00066     switch (ar_transMode)
00067     {
00068         case transmissionMode::async:
00069         {
00070             USART0_ENABLE_ASYNC_TRANSMISSION_MODE;
00071             break;
00072         }
00073         case transmissionMode::sync:
00074         {
00075             USART0_DISABLE_DOUBLE_SPEED_MODE;
00076             USART0_ENABLE_SYNC_TRANSMISSION_MODE;
00077             break;
00078         }
00079         case transmissionMode::masterSPI:
00080         {
00081             USART0_ENABLE_MASTER_SPI_MODE;
00082             break;
00083         }
00084     }
00085 }
00086
00087 }
00088
00089 void io::USART0::setCommunicationMode(const communicationMode &ar_comMode)
00090 {
00091     switch (ar_comMode)
00092     {
00093         case communicationMode::duplex:
00094         {
00095             USART0_ENABLE_TRANSMITTER;
00096             USART0_ENABLE_RECEIVER;
00097             break;
00098         }
00099         case communicationMode::receive:
00100         {
00101             USART0_ENABLE_RECEIVER;
00102             USART0_DISABLE_TRANSMITTER;
00103             break;
00104         }
00105         case communicationMode::transmit:
00106         {
00107             USART0_ENABLE_TRANSMITTER;
00108             USART0_DISABLE_RECEIVER;
00109             break;
00110         }
00111     }
00112 }
00113 }
00114
00115 void io::USART0::setParityMode(const parityMode& ar_parityMode)
00116 {
00117     switch (ar_parityMode)
00118     {
00119         case parityMode::noParity:
00120         {
00121             USART0_DISABLE_PARITY_MODE;
00122             break;
00123         }
00124         case parityMode::evenParity:
00125         {
00126             USART0_ENABLE_EVEN_PARITY_MODE;
00127             break;
00128         }
00129         case parityMode::oddParity:
00130         {
00131             USART0_ENABLE_ODD_PARITY_MODE;
00132             break;
00133         }
00134     }
00135 }
00136 }
00137
00138 void io::USART0::setFrameSize(const frameSize& ar_frameSize)
00139 {
00140     switch (ar_frameSize)
00141     {
00142         case frameSize::eightBits:
00143         {
00144             USART0_SET_8BIT_FRAME_SIZE;
```

```

00145         break;
00146     }
00147     case frameSize::sevenBits:
00148     {
00149         USART0_SET_7BIT_FRAME_SIZE;
00150         break;
00151     }
00152     case frameSize::sixBits:
00153     {
00154         USART0_SET_6BIT_FRAME_SIZE;
00155         break;
00156     }
00157     case frameSize::fiveBits:
00158     {
00159         USART0_SET_5BIT_FRAME_SIZE;
00160         break;
00161     }
00162     case frameSize::neineBits:
00163     {
00164         USART0_SET_9BIT_FRAME_SIZE;
00165         break;
00166     }
00167 }
00168
00169 }
00170 void io::USART0::setStopBit(const stopBit& ar_stopBit)
00171 {
00172     switch (ar_stopBit)
00173     {
00174     case stopBit::oneStopBit:
00175     {
00176         USART0_SET_ONE_STOP_BIT;
00177         break;
00178     }
00179     case stopBit::twoStopBits:
00180     {
00181         USART0_SET_TWO_STOP_BITS;
00182         break;
00183     }
00184     }
00185 }
00186 }
00187
00188
00189 uint8_t io::USART0::frameError()
00190 {
00191     return (m_status & (1 << USART0_FRAME_ERROR));
00192 }
00193 }
00194
00195 uint8_t io::USART0::dataOverrun()
00196 {
00197     return (m_status & (1 << USART0_DATA_OVERRUN));
00198 }
00199 }
00200
00201 uint8_t io::USART0::parityError()
00202 {
00203     return (m_status & (1 << USART0_PARITY_ERROR));
00204 }
00205 }
00206
00207 void io::USART0::sendFrames(const uint8_t* ap_dataBuffer, const uint8_t a_size)
00208 {
00209     while (!ready2Send()){};
00210     m_sizeData2Send = a_size;
00211     mp_data2Send = ap_dataBuffer;
00212     enableDataRegisterEmptyInterrupt(1);
00213 }
00214
00215
00216 void io::USART0::sendString(const char* ap_string)
00217 {
00218     while (!ready2Send()){};
00219     m_sizeData2Send = strlen(ap_string);
00220     mp_data2Send = reinterpret_cast<const uint8_t*>(ap_string);
00221     enableDataRegisterEmptyInterrupt(1);
00222 }
00223 }
00224
00225
00226 void io::USART0::sendByte(const uint8_t &ar_byte)
00227 {
00228     static uint8_t l_byte2Send[3];
00229     l_byte2Send[0] = '0' + (ar_byte / 100);
00230     l_byte2Send[1] = '0' + ((ar_byte / 10) % 10);
00231     l_byte2Send[2] = '0' + (ar_byte % 10);

```

```

00232
00233     while (!ready2Send()){};
00234     m_sizeData2Send = 3;
00235     mp_data2Send = l_byte2Send;
00236     enableDataRegisterEmptyInterrupt(1);
00237
00238 }
00239 void io::USART0::sendLong(const uint32_t &ar_long)
00240 {
00241     static uint8_t l_word2Send[10];
00242     l_word2Send[0] = '0' + (ar_long / 1000000000);
00243     l_word2Send[1] = '0' + ((ar_long / 100000000) % 10);
00244     l_word2Send[2] = '0' + ((ar_long / 10000000) % 10);
00245     l_word2Send[3] = '0' + ((ar_long / 1000000) % 10);
00246     l_word2Send[4] = '0' + ((ar_long / 100000) % 10);
00247     l_word2Send[5] = '0' + ((ar_long / 10000) % 10);
00248     l_word2Send[6] = '0' + ((ar_long / 1000) % 10);
00249     l_word2Send[7] = '0' + ((ar_long / 100) % 10);
00250     l_word2Send[8] = '0' + ((ar_long / 10) % 10);
00251     l_word2Send[9] = '0' + (ar_long % 10);
00252
00253     while (!ready2Send()){};
00254     m_sizeData2Send = 10;
00255     mp_data2Send = l_word2Send;
00256     enableDataRegisterEmptyInterrupt(1);
00257
00258 }
00259 void io::USART0::sendWord(const uint16_t &ar_word)
00260 {
00261     static uint8_t l_word2Send[5];
00262     l_word2Send[0] = '0' + (ar_word / 10000);
00263     l_word2Send[1] = '0' + ((ar_word / 1000) % 10);
00264     l_word2Send[2] = '0' + ((ar_word / 100) % 10);
00265     l_word2Send[3] = '0' + ((ar_word / 10) % 10);
00266     l_word2Send[4] = '0' + (ar_word % 10);
00267
00268     while (!ready2Send()){};
00269     m_sizeData2Send = 5;
00270     mp_data2Send = l_word2Send;
00271     enableDataRegisterEmptyInterrupt(1);
00272
00273 }
00274
00275 void io::USART0::sendChar(const uint8_t &ar_char)
00276 {
00277     while (!ready2Send()){};
00278     m_sizeData2Send = 1;
00279     mp_data2Send = &ar_char;
00280     enableDataRegisterEmptyInterrupt(1);
00281
00282 }
00283
00284 void io::USART0::receiveChar(uint8_t &ar_char)
00285 {
00286     m_sizeData2Receive = 1;
00287     mp_data2Receive = &ar_char;
00288 }
00289
00290
00291 void io::USART0::receiveFrames(uint8_t *ap_dataBuffer, const uint8_t a_size)
00292 {
00293     m_sizeData2Receive = a_size;
00294     mp_data2Receive = ap_dataBuffer;
00295
00296
00297
00298 }
00299
00300 void io::USART0::receiveString(const char *ap_string)
00301 {
00302
00303 }
00304
00305
00306 void io::USART0::receiveCompleteServiceRoutine()
00307 {
00308     static volatile uint8_t *lp_dataReceived = mp_data2Receive;
00309     static uint16_t l_dataSize = m_sizeData2Receive;
00310
00311     m_status = USART0_CONTROL_STATUS_REGISTER;
00312
00313
00314
00315     if (l_dataSize)
00316     {
00317
00318         *lp_dataReceived++ = USART0_DATA_REGISTER;

```

```

00319         l_dataSize--;
00320         m_numberBytesReceived++;
00321     }
00322 }
00323 else
00324 {
00325     l_dataSize = m_sizeData2Receive;
00326     lp_dataReceived = mp_data2Receive;
00327 }
00328 }
00329 }
00330
00331 void io::USART0::dataRegisterEmptyServiceRoutine()
00332 {
00333     if (m_sizeData2Send)
00334     {
00335         m_ready2Send = 0;
00336         USART0_DATA_REGISTER = *mp_data2Send++;
00337         m_sizeData2Send--;
00338         m_numberBytesSent++;
00339     }
00340     else
00341     {
00342         enableDataRegisterEmptyInterrupt(0);
00343         m_numberBytesSent = 0;
00344         m_ready2Send = 1;
00345     }
00346 }
00347 }
00348 }
00349 }
00350 }
00351 }
00352 }
00353 void io::USART0::enableTransmitCompleteInterrupt(const uint8_t ar_enable)
00354 {
00355     if (ar_enable) {
00356         USART0_ENABLE_TRANSMIT_COMPLETE_INTERRUPT;
00357     } else {
00358         USART0_DISABLE_TRANSMIT_COMPLETE_INTERRUPT;
00359     }
00360 }
00361 }
00362 }
00363 void io::USART0::enableReceiveCompleteInterrupt(const uint8_t ar_enable)
00364 {
00365     if (ar_enable) {
00366         USART0_ENABLE_RECEIVE_COMPLETE_INTERRUPT;
00367     } else {
00368         USART0_DISABLE_RECEIVE_COMPLETE_INTERRUPT;
00369     }
00370 }
00371 }
00372 }
00373 }
00374 void io::USART0::enableDataRegisterEmptyInterrupt(const uint8_t ar_enable)
00375 {
00376     if (ar_enable) {
00377         USART0_ENABLE_DATA_REGISTER_EMPTY_INTERRUPT;
00378     } else {
00379         USART0_DISABLE_DATA_REGISTER_EMPTY_INTERRUPT;
00380     }
00381 }
00382 }
00383 }
00384 }
00385 void io::USART0::transmitCompleteServiceRoutine()
00386 {
00387 }
00388 }
00389 }
00390 uint16_t io::USART0::getNumberBytesSent()
00391 {
00392     return m_numberBytesSent;
00393 }
00394 }
00395 uint16_t io::USART0::getNumberBytesReceived()
00396 {
00397     return m_numberBytesReceived;
00398 }
00399 }
00400 void io::USART0::resetNumberBytesReceived()
00401 {
00402     m_numberBytesReceived = 0;
00403 }
00404 }
00405 uint8_t io::USART0::ready2Send()

```

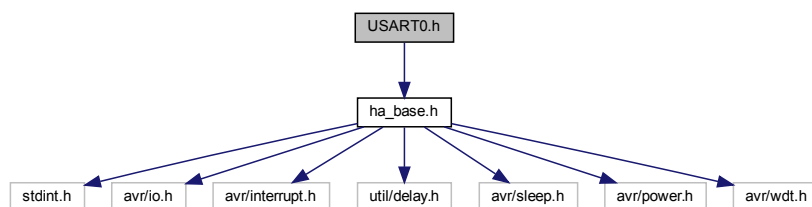
```
00406 {  
00407     return m_ready2Send;  
00408  
00409 }  
00410
```

7.81 USART0.h File Reference

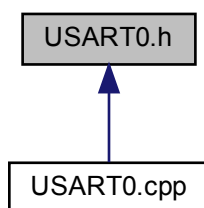
Header file of the USART0 class.

```
#include "ha_base.h"
```

Include dependency graph for USART0.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [io::USART0](#)

Namespaces

- [io](#)

Enumerations

- enum `io::transmissionMode` : `uint8_t` { `io::transmissionMode::async` =0, `io::transmissionMode::sync`, `io::transmissionMode::masterSPI` }
- enum `io::communicationMode` : `uint8_t` { `io::communicationMode::duplex` =0, `io::communicationMode::transmit`, `io::communicationMode::receive` }
- enum `io::parityMode` : `uint8_t` { `io::parityMode::noParity` =0, `io::parityMode::evenParity`, `io::parityMode::oddParity` }
- enum `io::frameSize` : `uint8_t` { `io::frameSize::eightBits` =0, `io::frameSize::fiveBits`, `io::frameSize::sixBits`, `io::frameSize::sevenBits`, `io::frameSize::neineBits` }
- enum `io::stopBit` : `uint8_t` { `io::stopBit::oneStopBit` =0, `io::stopBit::twoStopBits` }

7.81.1 Detailed Description

Header file of the USART0 class.

Basic class for IO abstraction of the Universal Synchronous and Asynchronous serial Receiver and Transmitter serial communication device.

Usage example (loopback v1):

```
#include "USART0.h"

#define BUFFER_SIZE 1

int main(void) {
    Init uint8_t l_data[BUFFER_SIZE];

    io::USART0 &myUSART0 = io::USART0::getInstance();

    myUSART0.sendString("Hello World!\r\n");

    ----- Event loop ----- // while (1) {

        myUSART0.receiveFrames(l_data, BUFFER_SIZE);
        if (myUSART0.getNumberBytesReceived() == BUFFER_SIZE)
        {
            myUSART0.sendFrames(l_data, BUFFER_SIZE);
            myUSART0.resetNumberBytesReceived();
        }

    } return 0; }
```

Usage example (loopback v2):

```
#include "USART0.h"

int main(void) {
    Init uint8_t l_data;

    io::USART0 &myUSART0 = io::USART0::getInstance();

    myUSART0.sendString("Hello World!\r\n");

    ----- Event loop ----- // while (1) {

        myUSART0.receiveChar(l_data);
        if (myUSART0.getNumberBytesReceived() == 1)
        {
            myUSART0.sendChar(l_data);
            myUSART0.resetNumberBytesReceived();
        }

    } return 0; }
```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [USART0.h](#).

7.82 USART0.h

```

00001
00071 #ifndef USART_H
00072 #define USART_H
00073 #include "ha_base.h"
00074
00075 // TODO: add additional function to send data
00076 // TODO: add a fuse programmer
00077 namespace io
00078 {
00079     enum class transmissionMode : uint8_t {
00080         async=0,
00081         sync,
00082         masterSPI
00083     };
00084
00085     enum class communicationMode : uint8_t {
00086         duplex=0,
00087         transmit,
00088         receive,
00089     };
00090
00091     enum class parityMode : uint8_t {
00092         noParity=0,
00093         evenParity,
00094         oddParity
00095     };
00096
00097     enum class frameSize : uint8_t {
00098         eightBits=0,
00099         fiveBits,
00100         sixBits,
00101         sevenBits,
00102         neineBits
00103     };
00104
00105     enum class stopBit : uint8_t {
00106         oneStopBit=0,
00107         twoStopBits
00108     };
00109
00110     class USART0
00111     {
00112     public:
00113
00126         static USART0& getInstance(const transmissionMode& ar_transMode = transmissionMode::async,
00127                                   const communicationMode& ar_comMode = communicationMode::duplex,
00128                                   const frameSize& ar_frameSize = frameSize::eightBits,
00129                                   const stopBit& ar_stopBit = stopBit::oneStopBit,
00130                                   const parityMode& ar_parityMode = parityMode::noParity);
00131
00132         void setBaudRate();
00133         void setTransmissionMode(const transmissionMode& ar_transMode);
00134         void setCommunicationMode(const communicationMode& ar_comMode);
00135         void setParityMode(const parityMode& ar_parityMode);
00136         void setFrameSize(const frameSize& ar_frameSize);
00137         void setStopBit(const stopBit& ar_stopBit);
00138         void sendFrames(const uint8_t *ap_dataBuffer, const uint8_t a_size);
00139         void sendString(const char *ap_string);
00140         void receiveString(const char *ap_string);
00141         void sendChar(const uint8_t &ar_char);
00142         void sendByte(const uint8_t &ar_byte);
00143
00144         void sendWord(const uint16_t &ar_word);
00145         void sendLong(const uint32_t &ar_long);

```



```

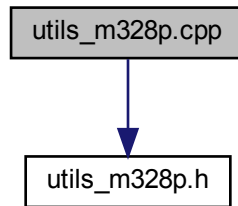
00197
00202     void receiveChar(uint8_t &ar_char);
00203
00210     void receiveFrames(uint8_t *ap_dataBuffer, const uint8_t a_size);
00215     void enableTransmitCompleteInterrupt(const uint8_t ar_enable);
00220     void enableReceiveCompleteInterrupt(const uint8_t ar_enable);
00225     static void enableDataRegisterEmptyInterrupt(const uint8_t ar_enable);
00228     uint8_t frameError();
00231     uint8_t dataOverrun();
00234     uint8_t parityError();
00237     uint16_t getNumberBytesReceived();
00240     uint16_t getNumberBytesSent();
00243     uint8_t ready2Send();
00246     void resetNumberBytesReceived();
00249     static void receiveCompleteServiceRoutine() __asm__(STR(USART0_RECEIVE_COMPLETE_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00252     static void dataRegisterEmptyServiceRoutine() __asm__(STR(USART0_DATA_REGISTER_EMPTY_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00255     static void transmitCompleteServiceRoutine() __asm__(STR(USART0_TRANSMIT_COMPLETE_INTERRUPT))
__attribute__((__signal__, __used__, __externally_visible__));
00256
00257
00258 protected:
00259
00260
00261
00262
00263 private:
00272     USART0(const transmissionMode& ar_transMode,
00273            const communicationMode& ar_comMode,
00274            const frameSize& ar_frameSize,
00275            const stopBit& ar_stopBit,
00276            const parityMode& ar_parityMode);
00277
00280     ~USART0();
00281
00284     USART0(const USART0&);
00285
00288     const USART0& operator=(const USART0&);
00289
00290     static volatile uint8_t m_status;
00292     static const uint8_t *mp_data2Send;
00294     static uint8_t *mp_data2Receive;
00296     static uint16_t m_sizeData2Send;
00298     static uint16_t m_sizeData2Receive;
00300     static volatile uint16_t m_numberBytesReceived;
00302     static volatile uint16_t m_numberBytesSent;
00304     static volatile uint8_t m_ready2Send;
00307 };
00308
00309
00310
00311 }
00312
00313
00314
00315
00316
00317
00318
00319
00320
00321
00322
00323 #endif

```

7.83 utils_m328p.cpp File Reference

```
#include "utils_m328p.h"
```

Include dependency graph for `utils_m328p.cpp`:

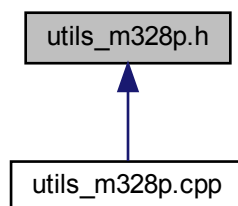


7.84 `utils_m328p.cpp`

```
00001 #include "utils_m328p.h"
00002
00003 long utils::map(long x, long in_min, long in_max, long out_min, long out_max)
00004 {
00005     return (x - in_min) * (out_max - out_min) / (in_max - in_min) + out_min;
00006 }
```

7.85 `utils_m328p.h` File Reference

This graph shows which files directly or indirectly include this file:



Namespaces

- `utils`

Functions

- long `utils::map` (long x, long in_min, long in_max, long out_min, long out_max)

7.86 utils_m328p.h

```

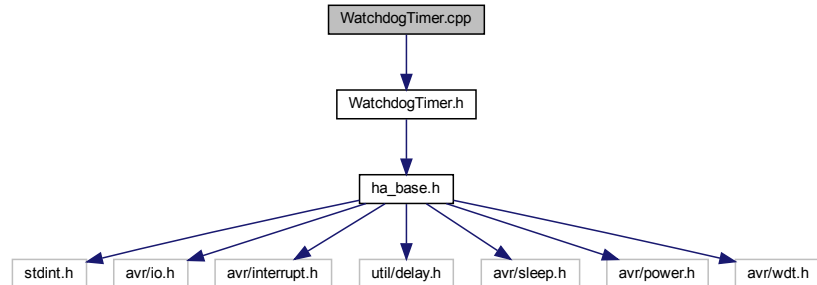
00001 #ifndef UTILSM329P_H
00002 #define UTILSM329P_H
00003 namespace utils
00004 {
00005
00006
00007 // delay functions
00008
00009
00010
00011 // multiplication / division operations bit-shift devide multiply
00012
00013
00014 // clock division (set prescaler)
00015
00016 // clock power saving through macros
00017
00018
00019 // mapping values
00020
00021 long map(long x, long in_min, long in_max, long out_min, long out_max);
00022
00023
00024 }
00025 #endif

```

7.87 WatchdogTimer.cpp File Reference

```
#include "WatchdogTimer.h"
```

Include dependency graph for WatchdogTimer.cpp:



7.88 WatchdogTimer.cpp

```

00001 #include "WatchdogTimer.h"
00002
00003
00004 core::WatchdogTimer& core::WatchdogTimer::getInstance()
00005 {
00006     static WatchdogTimer l_instance;
00007     return l_instance;
00008 }
00009
00010
00011 core::WatchdogTimer::WatchdogTimer()
00012 {
00013     sei();
00014     stop();
00015 }
00016
00017 core::WatchdogTimer::~WatchdogTimer()
00018 {
00019

```

```

00020 }
00021
00022 void core::WatchdogTimer::selectTimeOut(const timeOut &ar_timeOut)
00023 {
00024     m_timeOut = static_cast<uint8_t>(ar_timeOut);
00025     m_timeOut = static_cast<uint8_t>((m_timeOut & 7) | ((m_timeOut & 8) << 2));
00026     cli();
00027     wdt_reset();
00028     WATCHDOG_SELECT_TIMEOUT(m_timeOut);
00029     sei();
00030 }
00031 }
00032
00033 void core::WatchdogTimer::reset()
00034 {
00035     wdt_reset();
00036 }
00037 }
00038
00039 void core::WatchdogTimer::start(const operationMode &ar_operationMode)
00040 {
00041     m_operationMode = static_cast<uint8_t>(ar_operationMode);
00042     m_operationMode = static_cast<uint8_t>((m_operationMode & 1) << 6) | ((m_operationMode & 2) << 3);
00043     cli();
00044     wdt_reset();
00045     WATCHDOG_START(m_operationMode, m_timeOut);
00046     sei();
00047 }
00048 }
00049
00050 void core::WatchdogTimer::start(const operationMode &ar_operationMode, const timeOut &ar_timeOut)
00051 {
00052     m_timeOut = static_cast<uint8_t>(ar_timeOut);
00053     m_timeOut = static_cast<uint8_t>((m_timeOut & 7) | ((m_timeOut & 8) << 2));
00054     m_operationMode = static_cast<uint8_t>(ar_operationMode);
00055     m_operationMode = static_cast<uint8_t>((m_operationMode & 1) << 6) | ((m_operationMode & 2) << 3);
00056     cli();
00057     wdt_reset();
00058     WATCHDOG_START(m_operationMode, m_timeOut);
00059     sei();
00060 }
00061 }
00062
00063 void core::WatchdogTimer::stop()
00064 {
00065     cli();
00066     wdt_reset();
00067     WATCHDOG_STOP;
00068     sei();
00069 }
00070 }
00071

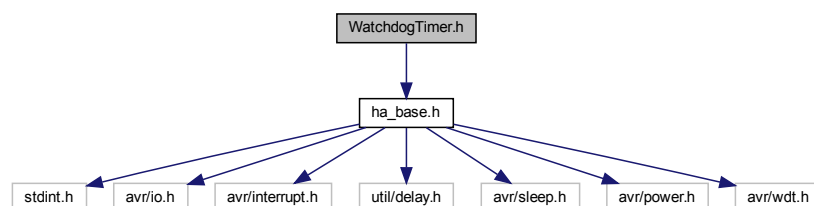
```

7.89 WatchdogTimer.h File Reference

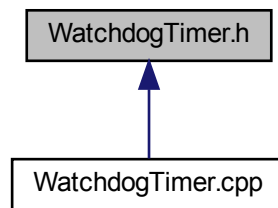
Header file of the WatchdogTimer class.

```
#include "ha_base.h"
```

Include dependency graph for WatchdogTimer.h:



This graph shows which files directly or indirectly include this file:



Classes

- class [core::WatchdogTimer](#)

Namespaces

- [core](#)

Enumerations

- enum [core::timeOut](#) : `uint8_t` {
[core::timeOut::to_16ms](#) =0, [core::timeOut::to_32ms](#), [core::timeOut::to_64ms](#), [core::timeOut::to_125ms](#),
[core::timeOut::to_250ms](#), [core::timeOut::to_500ms](#), [core::timeOut::to_1s](#), [core::timeOut::to_2s](#),
[core::timeOut::to_4s](#), [core::timeOut::to_8s](#) }
- enum [core::operationMode](#) : `uint8_t` {
[core::operationMode::normal](#) =0, [core::operationMode::PWM_PC](#), [core::operationMode::PWM_PC_8bit](#),
[core::operationMode::PWM_PC_9bit](#),
[core::operationMode::PWM_PC_10bit](#), [core::operationMode::PWM_PFC_ICR](#), [core::operationMode::PWM_PFC_OCR](#),
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[core::operationMode::PWM_PC_OCR](#), [core::operationMode::fast_PWM](#), [core::operationMode::fast_PWM_8bit](#),
[core::operationMode::fast_PWM_9bit](#),
[core::operationMode::fast_PWM_10bit](#), [core::operationMode::fast_PWM_ICR](#), [core::operationMode::fast_PWM_OCR](#),
[core::operationMode::CTC_OCR](#),
[core::operationMode::CTC_ICR](#), [core::operationMode::interrupt](#) =1, [core::operationMode::reset](#), [core::operationMode::interrupt](#)
}

7.89.1 Detailed Description

Header file of the WatchdogTimer class.

Basic class abstraction of the WatchdogTimer peripheral

Usage example (test):

```
#include "WatchdogTimer.h" #include "Led.h" instantiate a Led object extern component::Led Led; component::Led
Led(io::Pin(1,io::PortB)); extern component::Led LedStart; component::Led LedStart(io::Pin(2,io::PortB));
```

```
int main(void) {
```

```
Init instantiate a Watchdog object core::WatchdogTimer &myWatchdog = core::WatchdogTimer::getInstance(); my↵
Watchdog.selectTimeOut(core::timeOut::to\_8s); LedStart.on(); _delay_ms(5000); LedStart.off(); myWatchdog.↵
start(core::operationMode::reset); ----- Event loop ----- // while (1) {
```

```
Led.on();
_delay_ms(1000);
Led.off();
_delay_ms(1000);
```

```
} return 0; }
```

```
void core::WatchdogTimer::timeOutServiceRoutine() { for (uint8_t i=0;i<10;i++) { Led.on(); _delay_ms(100); Led.off(); _delay_ms(100);
```

```
}
```

```
}
```

Author

Farid Oubbati (<https://github.com/faroub>)

Date

March 2020

Definition in file [WatchdogTimer.h](#).

7.90 WatchdogTimer.h

```
00001
00057 #ifndef WATCHDOG_TIMER_H
00058 #define WATCHDOG_TIMER_H
00059 #include "ha_base.h"
00060
00061
00062
00063 namespace core
00064 {
00065     enum class timeOut : uint8_t {
00066         to_16ms=0,
00067         to_32ms,
00068         to_64ms,
00069         to_125ms,
00070         to_250ms,
00071         to_500ms,
00072         to_1s,
00073         to_2s,
00074         to_4s,
00075         to_8s,
00076     };
00077
00078     enum class operationMode : uint8_t {
00079         interrupt=1,
00080         reset,
00081         interrupt_reset,
00082     };
00083
00084     class WatchdogTimer
00085     {
00086
00087     public:
00088
00089         static WatchdogTimer& getInstance();
00090
00091         void selectTimeOut(const timeOut &ar_timeOut);
00092
00093         void reset();
00094
00095         void start(const operationMode &ar_operationMode);
00096
00097         void start(const operationMode &ar_operationMode, const timeOut &ar_timeOut);
00098
00099
```

```
00100     void stop();
00101
00102     static void timeOutServiceRoutine() __asm__(STR(WATCHDOG_TIMEOUT_INTERRUPT))
    __attribute__((__signal__, __used__, __externally_visible__));
00103
00104
00105 protected:
00106
00107 private:
00108
00109     WatchdogTimer();
00110
00111     ~WatchdogTimer();
00112
00113     WatchdogTimer(const WatchdogTimer&);
00114
00115     const WatchdogTimer& operator=(const WatchdogTimer&);
00116
00117     uint8_t m_timeOut;
00118
00119     uint8_t m_operationMode;
00120
00121 };
00122
00123
00124
00125
00126
00127
00128
00129
00130
00131
00132 #endif
```


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