**ĐẠI HỌC BÁCH KHOA HÀ NỘI**

**Trường Điện – Điện Tử**

.......................\*\*\*........................



**BÁO CÁO BÀI TẬP LỚN**

Môn học**: Thiết Kế Hệ Thống Nhúng**

**Nhóm 17**

**Giảng viên hướng dẫn: Thầy Lê Công Cường**

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HÀ NỘI – THÁNG 2/2023

# **LỜI NÓI ĐẦU**

Trong thời đại công nghệ 4.0 như hiện nay, có rất nhiều nghiên cứu, phát triển và đạt được nhiều thành tựu tiêu biểu phải kể đến những dự án về các hệ thống nhúng. Vì vậy nên trong kì học qua, nhóm em đã được nhà trường và thầy Lê Công Cường giảng dạy cho về bộ môn “Thiết kế hệ thống nhúng ” để có thể hiểu rõ về bản chất của hệ thống nhúng và cách để tự mình thiết kế, lập trình ra được một hệ thống nhúng. Và để phục vụ cho yêu cầu cuối kì của môn học, nhóm đã hoàn thành đề tài và tổng hợp thành báo cáo dưới đây.

Nội dung báo cáo gồm 5 chương:

Chương I : Giới thiệu yêu cầu bài tập lớn

Chương II: Giới thiệu về phần cứng

Chương III: Thiết kế phần mềm

Chương IV: Kết quả và đánh giá

Chương V: Link share thư mục lập trình

Nhóm em xin gửi lời cảm ơn chân thành nhất tới thầy Lê Công Cường vì đã truyền đạt và chỉ bảo cho nhóm những kiến thức, kinh nghiệm vô cùng quý giá để nhóm có thể hoàn thành được đề tài này. Do đây là lần đầu tiếp cận với đề tài nên là nhóm sẽ không thể tránh khỏi những thiếu sót và hạn chế. Rất mong nhận được sự góp ý, nhận xét từ thầy để nhóm có thể hoàn thiện hơn trong tương lai.

Chúng em xin chân thành cảm ơn thầy!

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# **CHƯƠNG 1: GIỚI THIỆU VỀ YÊU CẦU ĐỀ TÀI**

Lập trình VĐK STM32 giao tiếp với cảm biến DHT11 để hiện thị thông số đo được lên LCD, và truyền thông số lên máy tính. Điều khiển góc của motor theo 2 chế độ:

1) Theo nhiệt độ hoặc độ ẩm

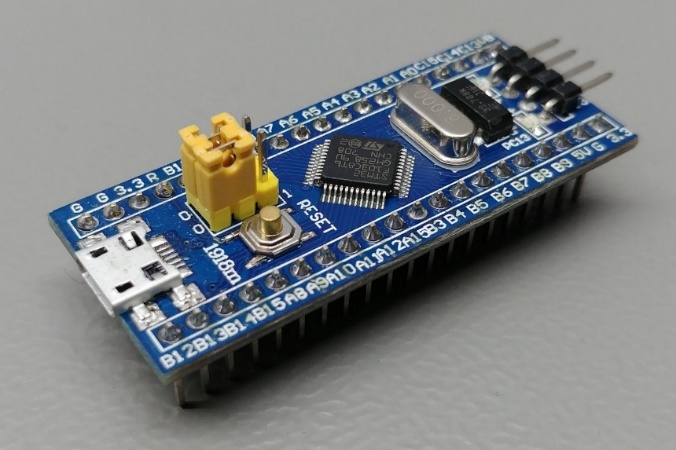
2) Theo yêu cầu từ máy tính

Lựa chọn chế độ và đặt ngưỡng cảnh báo nhiệt độ từ máy tính.

# **CHƯƠNG 2: GIỚI THIỆU VỀ PHẦN CỨNG**

## **2.1** **Nguyên lý làm việc của các module phần cứng**

### **2.1.1 STM32F103C8T6 Blue Pill**

****Module STM32F103C8T6 Blue Pill là một module mạch tích hợp vi điều khiển, được phát triển bởi STMicroelectronics. Module này được thiết kế với vi xử lý ARM Cortex-M3, với tốc độ xung nhịp tối đa lên đến 72 MHz và bộ nhớ Flash ROM 64 KB.

Hình 1. Kit STM32F103C8T6

Module STM32F103C8T6 Blue Pill có cấu trúc bao gồm:

* Vi điều khiển ARM Cortex-M3: Đây là bộ xử lý trung tâm của module, được thiết kế để điều khiển các hoạt động của module.
* Bộ nhớ Flash ROM: Đây là nơi lưu trữ chương trình và dữ liệu của module. Khi vi điều khiển hoạt động, nó sẽ đọc chương trình từ bộ nhớ này và thực hiện các hoạt động theo đúng quy trình.
* Bộ nhớ SRAM: Đây là bộ nhớ tạm thời được sử dụng để lưu trữ dữ liệu trong quá trình hoạt động của module.
* Bộ chuyển đổi Analog-to-Digital Converter (ADC): Bộ chuyển đổi này cho phép module đo các tín hiệu analog từ các cảm biến hoặc thiết bị ngoại vi khác và chuyển đổi chúng thành các giá trị kỹ thuật số để xử lý.
* Các chân kết nối: Module STM32F103C8T6 Blue Pill được trang bị các chân kết nối cho phép nó kết nối với các thiết bị ngoại vi khác như các cảm biến, màn hình, bộ nhớ, và các thiết bị khác.

Nguyên lý hoạt động của module STM32F103C8T6 Blue Pill là vi điều khiển ARM Cortex-M3 sẽ đọc các chương trình và dữ liệu từ bộ nhớ Flash ROM và thực hiện các hoạt động theo các lệnh được chỉ định trong chương trình. Bộ chuyển đổi ADC sẽ đọc các tín hiệu analog và chuyển đổi chúng thành các giá trị kỹ thuật số để xử lý. Các chân kết nối cho phép module kết nối với các thiết bị ngoại vi khác và thực hiện các hoạt động như đọc dữ liệu từ các cảm biến hoặc hiển thị thông tin trên màn hình.

Module STM32F103C8T6 Blue Pill được sử dụng trong nhiều ứng dụng khác nhau, từ điều khiển thiết bị đơn giản đến các hệ thống điện tử phức tạp.

### **Servo SG90**

Servo SG90 là một loại servo cơ bản được sử dụng rộng rãi trong các ứng dụng điều khiển vị trí và góc quay của các thiết bị như robot, máy bay điều khiển từ xa, cánh tay robot, v.v.

Hình 2. Động cơ SG90

Cấu tạo của servo SG90 bao gồm:

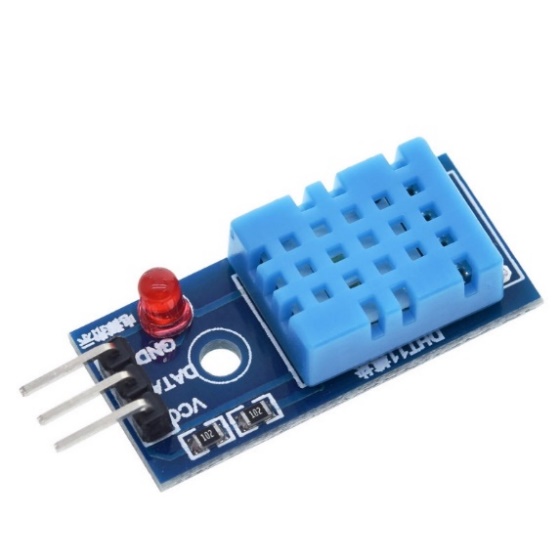
* Động cơ servo: Là phần quan trọng nhất của servo SG90, nó làm việc bằng cách sử dụng nguồn điện DC để tạo ra mô-men xoắn cơ học để quay trục của servo.
* Bộ giảm tốc: Được sử dụng để giảm tốc độ và tăng mô-men xoắn của động cơ servo để giúp servo SG90 hoạt động ổn định và chính xác hơn.
* Mạch điều khiển: Là bộ phận điều khiển tín hiệu điện vào từ các nguồn điều khiển để xác định vị trí và góc quay của servo SG90.
* Cảm biến phản hồi: Được sử dụng để cung cấp thông tin về vị trí và góc quay của servo SG90 cho mạch điều khiển để điều chỉnh và kiểm soát vị trí của servo.

Khi nhận được tín hiệu điều khiển từ nguồn điều khiển, mạch điều khiển sẽ đọc và xử lý tín hiệu này để điều chỉnh động cơ servo và đưa servo đến vị trí mong muốn. Sau khi servo đạt được vị trí mong muốn, cảm biến phản hồi sẽ gửi thông tin về vị trí hiện tại của servo đến mạch điều khiển để kiểm soát và điều chỉnh servo đến vị trí chính xác.

Servo SG90 thường có góc quay giới hạn khoảng 180 độ và được điều khiển bằng các tín hiệu điện analog. Servo SG90 có kích thước nhỏ gọn, dễ dàng sử dụng và có giá thành phải chăng, đây là lý do tại sao nó được sử dụng rộng rãi trong nhiều ứng dụng điều khiển vị trí và góc quay của các thiết bị khác nhau.

### **DHT11**

DHT11 là một cảm biến đo độ ẩm và nhiệt độ. Nó có cấu tạo đơn giản và được sử dụng rộng rãi trong các ứng dụng điện tử, cảm biến môi trường, các dự án IoT, v.v.

****Cấu tạo của DHT11 bao gồm:

Hình3 . DHT11

* Cảm biến nhiệt độ: Là một thanh kẽm nhỏ nằm giữa hai điện cực được kết nối với một bộ điều khiển để đo nhiệt độ.
* Cảm biến độ ẩm: Là một tấm kim loại nhỏ được bao bọc bởi một lớp polymer, khi hơi ẩm tiếp xúc với lớp polymer, cảm biến độ ẩm sẽ đo được độ ẩm.
* Bộ điều khiển: Bao gồm một vi mạch tích hợp để đọc các giá trị đo được từ cảm biến nhiệt độ và độ ẩm, sau đó chuyển đổi chúng thành tín hiệu số để gửi đến microcontroller hoặc vi điều khiển.

Cảm biến sẽ đo độ ẩm và nhiệt độ và gửi tín hiệu analog tương ứng đến bộ điều khiển. Bộ điều khiển sẽ chuyển đổi tín hiệu analog này thành tín hiệu số và gửi nó đến microcontroller hoặc vi điều khiển để xử lý dữ liệu. Dữ liệu đo được được gửi qua giao tiếp số bằng một chuỗi dữ liệu 40 bit. Trong đó, 5 bit đầu tiên là dấu hiệu đồng bộ hóa, tiếp theo là 8 bit dữ liệu độ ẩm, 8 bit dữ liệu nhiệt độ, 8 bit kiểm tra dữ liệu và 8 bit cuối cùng là dữ liệu kiểm tra định dạng.

DHT11 hoạt động trong phạm vi nhiệt độ từ 0 độ C đến 50 độ C và độ ẩm từ 20% đến 90%. Nó có thể được sử dụng với các loại vi điều khiển và microcontroller khác nhau để đo độ ẩm và nhiệt độ trong môi trường khác nhau.

### **USB TTL**

****USB TTL là một thiết bị chuyển đổi tín hiệu từ cổng USB sang cổng TTL (Transistor-Transistor Logic) và ngược lại, được sử dụng rộng rãi trong các ứng dụng như lập trình vi điều khiển, kết nối với các thiết bị ngoại vi qua cổng TTL, v.v.

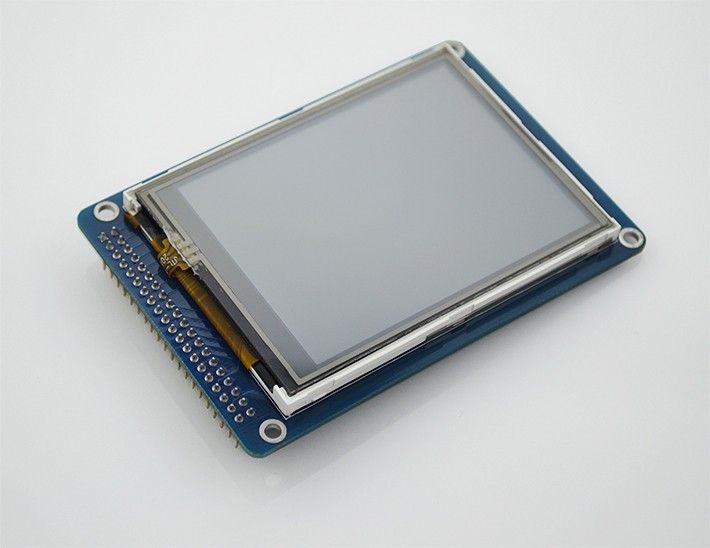
Hình 4 . USB TTL

Cấu tạo của USB TTL bao gồm:

* Chip chuyển đổi USB sang TTL: Là chip chính trong USB TTL, nó có khả năng chuyển đổi tín hiệu USB thành tín hiệu TTL và ngược lại. Chip thường được sử dụng trong USB TTL là chip FT232RL của hãng FTDI.
* Các linh kiện điện tử: Bao gồm các linh kiện như điện trở, tụ điện, đảo pha, v.v. để bảo vệ và ổn định tín hiệu.
* Cổng USB: Dùng để kết nối với máy tính hoặc nguồn cấp.
* Cổng TTL: Dùng để kết nối với các thiết bị ngoại vi qua cổng TTL, ví dụ như vi điều khiển, cảm biến, v.v.

Khi USB TTL được kết nối với máy tính thông qua cổng USB, nó sẽ nhận được nguồn cấp từ máy tính và khởi động chip chuyển đổi USB sang TTL. Tín hiệu dữ liệu từ máy tính được chuyển đổi thành tín hiệu TTL và truyền tới cổng TTL của USB TTL. Nếu kết nối với một vi điều khiển thông qua cổng TTL, tín hiệu TTL sẽ được chuyển đổi thành tín hiệu tương ứng với giao thức truyền thông được sử dụng (UART, SPI, I2C, v.v.) và được gửi tới vi điều khiển. Ngược lại, khi vi điều khiển gửi tín hiệu về USB TTL qua cổng TTL, nó sẽ được chuyển đổi thành tín hiệu USB và được truyền về máy tính. Qua đó, giúp việc giao tiếp giữa máy tính và các thiết bị ngoại vi qua cổng TTL trở nên dễ dàng hơn.

### **Màn hình LCD TFT**

****Màn hình LCD TFT (Thin-Film-Transistor) là một loại màn hình hiển thị phổ biến trong điện tử, được sử dụng trong nhiều ứng dụng như điện thoại di động, máy tính bảng, máy tính, đồng hồ thông minh, v.v.

Hình 5 . LCD TFT

Cấu tạo chi tiết của màn hình LCD TFT bao gồm:

* Tấm kính: Là lớp đầu tiên được bao phủ bên ngoài của màn hình LCD TFT.
* Lớp polaroid: Là lớp tiếp theo, giúp điều chỉnh hướng của ánh sáng.
* Lớp đèn nền: Là lớp phía sau cùng của màn hình LCD TFT, giúp chiếu sáng qua màn hình để tạo ra hình ảnh.
* Mạch điều khiển: Bao gồm một số vi mạch chính, như bộ điều khiển hình ảnh, bộ điều khiển điều khiển bảng điều khiển, bộ điều khiển đèn nền và các bộ khuếch đại tín hiệu.
* Bảng điều khiển: Là lớp bên trong của màn hình LCD TFT, bao gồm hàng ngàn transistor và các điểm ảnh để tạo ra hình ảnh.

Nguyên lý hoạt động của màn hình LCD TFT dựa trên sự điều khiển của các transistor, được kết hợp với các lớp polaroid, để tạo ra hình ảnh trên màn hình. Mỗi pixel trên màn hình được điều khiển bởi một transistor, khi một tín hiệu điều khiển được áp dụng vào transistor đó, nó sẽ mở và cho phép tín hiệu điện tử chạy qua nó. Tín hiệu này sẽ thay đổi trạng thái của lớp polaroid, để tạo ra một mức sáng khác nhau trên màn hình.

Để tạo ra hình ảnh, các transistor sẽ được điều khiển bởi một bộ điều khiển hình ảnh, nó sẽ tạo ra các tín hiệu điều khiển phù hợp để mở và đóng các transistor, tạo ra các mức sáng khác nhau tại các điểm ảnh trên màn hình. Khi đèn nền được bật, ánh sáng sẽ chiếu qua các lớp kính và polaroid, tạo ra hình ảnh tương ứng trên màn hình LCD TFT.

**2.2 Trình bày các ngoại vi của STM32 cần sử dụng**

### **2.2.1 SPI**

SPI là một giao diện cổng nối tiếp đồng bộ ba dây cho phép kết nối truyền thông VĐK được phát triển bởi Motorola. Trong cấu hình mạng kết nối truyền thống này phải có một VĐK giữ vai trò là Chủ (Master) và các VĐK còn lại có thể hoặc là Chủ hoặc là Tớ. SPI có 4 tốc độ có thể lập trình, cực và pha nhịp đồng hồ khả trình và kết thúc ngắt truyền thông. Nhịp đồng hồ không nằm trong dòng dữ liệu và phải được cung cấp như một tín hiệu tách độc lập. Có ba thanh ghi SPSR, SPCR và SPDR cho phép thực hiện các chức năng điều khiển, trạng thái và lữu trữ. Có bốn chân cơ bản cần thiết để thực thi chuẩn giao diện truyền thông này.

Dữ liệu ra MOSI (Master Output – Slave Input)

Dữ liệu vào MISO (Master Input – Slave Output)

Nhịp xung chuẩn SCLK (*Serial Clock*)

Table

Description automatically generatedLựa chọn thành phần tớ SS (*Slave Select*)

Hình 6. Kết nối SPI

**Kết nối nguyên lý truyền thông SPI giữa một Master và một Slave**

Diagram, schematic

Description automatically generatedHình trên chỉ ra nguyên lý kết nối giữa một đơn vị Chủ và một đơn vị Tớ trong truyền thông SPI. Trong đó tín hiệu SCLK sẽ được tạo ra bởi đơn vị Chủ và là tín hiệu vào của đơn vị Tớ. MOSI là đường truyền dữ liệu ra từ đơn vị Chủ tới đơn vị Tớ và MISO là đường truyền dữ liệu vào đơn vị Chủ đến từ đơn vị Tớ. Đơn vị Tớ được lựa chọn khi đơn vị Chủ kích hoạt tín hiệu *SS*.

**Sơ đồ kết nối truyền thống SPI của một đơn vị Chủ với nhiều đơn vị Tớ**

Nếu hệ thống có nhiều đơn vị tớ đơn vị Chủ sẽ tạo phải ra các tín hiệu tách biệt để chọn đơn vị Tớ. Cơ chế đó được thực hiện nhờ sơ đồ kết nối nguyên lý mô tả như hình vẽ. Đơn vị Chủ sẽ tạo ra tín hiệu chọn đơn vị Tớ nhờ các chân tín hiệu logic đa chức năng. Các tín hiệu này phải được điều khiển và đảm bảo ổn định về thời gian để tránh trường hợp tín hiệu bị thay đổi trong quá trình đang truyền dữ liệu. Một điều dễ nhận ra rằng SPI không hỗ trợ cơ chế xác nhận trong quá trình thực hiện truyền thông. Điều này phụ thuộc vào giao thức định nghĩa hoặc phải thực hiện bổ sung thêm một số các mở rộng phụ bên ngoài.

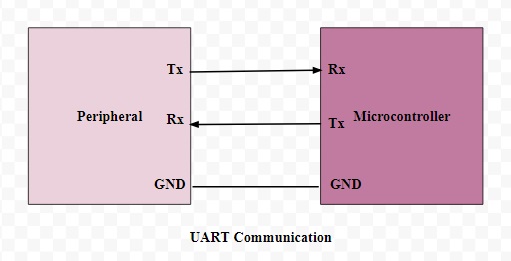
Khả năng truyền thông đồng thời hai chiều với tốc độ lên đến khoảng vài Mbit/s và nguyên lý khá đơn giản nên SPI hoàn toàn phù hợp để thực hiện truyền thông giữa các thiết bị yêu cầu truyền thông tốc độ chậm, đặc biệt hiệu quả trong các ứng dụng một đơn vị Chủ và một đơn vị Tớ. Tuy nhiên trong các ứng dụng với nhiều đơn vị Tớ việc thực thi lại khá phức tạp vì thiếu cơ chế xác định địa chỉ, và sự phức tạp sẽ tăng lên khi số đơn vị Tớ tăng.

SPI được sử dụng trong nhiều ứng dụng như đọc và ghi bộ nhớ flash, giao tiếp với các mạch điều khiển màn hình, đọc các cảm biến nhiệt độ, ánh sáng và độ ẩm, và điều khiển các động cơ và bộ điều khiển động cơ khác.

Việc sử dụng SPI giúp giảm độ trễ truyền dữ liệu, tốc độ truyền dữ liệu nhanh và khả năng điều khiển các thiết bị ngoại vi từ xa. Do đó, SPI được sử dụng rộng rãi trong các ứng dụng IoT, điện tử và công nghiệp.

### **UART**

UART tiếng anh là Universal Asynchronous Reciver/Transmister một chuẩn giao tiếp không đồng bộ cho MCU và các thiết bị ngoại vi.

Chuẩn UART là chuẩn giao tiếp điểm và điểm, nghĩa là trong mạng chỉ có hai thiết bị đóng vai trò là transmister hoặc reciver.

Hình 7 . Giao tiếp UART

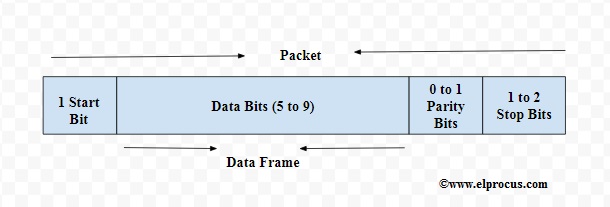
**+ Cách hoạt động của giao thức UART:**

UART là giao thức truyền thông không đồng bộ, nghĩa là không có xung Clock, các thiết bị có thể hiểu được nhau nếu các Setting giống nhau.

UART là truyền thông song công (Full duplex) nghĩa là tại một thời điểm có thể truyền và nhận đồng thời.

Trong đó quan trọng nhất là Baund rate (tốc độ Baund) là khoảng thời gian dành cho 1-bit được truyền. Phải được cài đặt giống nhau ở gửi và nhận.

Sau đó là định dạng gói tin.Định dạng gói tin như sau:

**Start – Bit:** Start-bit còn được gọi là bit đồng bộ hóa được đặt trước dữ liệu thực tế. Nói chung, một đường truyền dữ liệu không hoạt động được điều khiển ở mức điện áp cao. Để bắt đầu truyền dữ liệu, truyền UART kéo đường dữ liệu từ mức điện áp cao (1) xuống mức điện áp thấp (0). UART thu được thông báo sự chuyển đổi này từ mức cao sang mức thấp qua đường dữ liệu cũng như bắt đầu hiểu dữ liệu thực. Nói chung, chỉ có một start-bit.

Hình 8. Data frame của UART

**Stop – Bit:** Bit dừng được đặt ở phần cuối của gói dữ liệu. Thông thường, bit này dài 2 bit nhưng thường chỉ sử dụng 1 bit. Để dừng sóng, UART giữ đường dữ liệu ở mức điện áp cao.

**Partity Bit:** Bit chẵn lẻ cho phép người nhận đảm bảo liệu dữ liệu được thu thập có đúng hay không. Đây là một hệ thống kiểm tra lỗi cấp thấp & bit chẵn lẻ có sẵn trong hai phạm vi như Chẵn lẻ – chẵn lẻ cũng như Chẵn lẻ – lẻ. Trên thực tế, bit này không được sử dụng rộng rãi nên không bắt buộc.

**Data frame:** Các bit dữ liệu bao gồm dữ liệu thực được truyền từ người gửi đến người nhận. Độ dài khung dữ liệu có thể nằm trong khoảng 5 & 8. Nếu bit chẵn lẻ không được sử dụng thì chiều dài khung dữ liệu có thể dài 9 bit. Nói chung, LSB của dữ liệu được truyền trước tiên sau đó nó rất hữu ích cho việc truyền.

**Table

Description automatically generated+ STM32F1 có 3 kênh UART**

UART được sử dụng rộng rãi trong các ứng dụng như giao tiếp với máy tính hoặc các thiết bị điện tử khác như GPS, cảm biến, mạch điều khiển động cơ, đọc dữ liệu từ các thiết bị lưu trữ như bộ nhớ flash, EEPROM, thẻ nhớ.

Tuy nhiên, UART có một số hạn chế như tốc độ truyền dữ liệu thấp hơn so với SPI và I2C, khoảng cách truyền tối đa giữa hai thiết bị không được xa và không có khả năng điều khiển từ xa các thiết bị ngoại vi.

### **Timer**

Timer là 1 mạch digital logic có vai trò đếm mỗi chu kỳ clock (đếm lên hoặc đếm xuống).

A picture containing table

Description automatically generatedDưới đây là 1 bộ timer 16 bit cơ bản, nó có thể đếm từ 0 -> 65535 (216-1). Mỗi chu kỳ clock, giá trị của bộ đếm được tăng thêm 1.

Hình 9. PSC của Timer

Prescaler là bộ chia tần số của timer. Bộ chia này có giá trị tối đa là 16 bit tương ứng với giá trị là 65535. Các giá trị này có thể được thay đổi và điều chỉnh bằng lập trình. Tần số sau bộ chia này sẽ được tính là:

**fCK\_CNT = fCK\_PSC / (PSC+1).**

* + fCK\_CNT: tần số sau bộ chia.
  + fCK\_PSC: tần số clock đầu vào cấp cho timer.
  + PSC: chính là giá trị truyền vào được lập trình bằng phần mềm

Auto Reload value là giá trị bộ đếm tối đa có thể được điều chỉnh để nạp vào cho timer. Giá trị bộ đếm này được cài đặt tối đa là 16bit tương ứng với giá trị là 65535. Từ các thông số trên ta rút ra công thức cần tính cuối cùng đó là:

**FTIMER = fSYSTEM / [(PSC+1) (Period+1)]**

* + Ftimer : là giá trị cuối cùng của bài toán, đơn vị là hz.
  + F system : tần số clock hệ thống được chia cho timer sử dụng, đơn vị là hz.
  + PSC: giá trị nạp vào cho bộ chia tần số của timer. Tối đa là 65535.
  + Period: giá trị bộ đếm nạp vào cho timer. Tối đa là 65535.

**– Các chế độ đếm:** Mỗi bộ timer đều hỗ trợ 3 chế chế độ đếm sau:

**Diagram, box and whisker chart

Description automatically generated+**Upcounting mode (chế độ đếm lên): Ở chế độ này, CNT đếm lên từ 0 (hoặc một giá trị nào đó được người dùng ghi vào CNT trước) đến giá trị của thanh ghi ARR, sau đó CNT bắt đầu lại từ 0. Lúc này có sự kiện tràn counter – overflow, sự kiện này có thể tạo yêu cầu ngắt nếu người dùng cấu hình cho phép ngắt. Một ví dụ với ARR = 36:

**Diagram

Description automatically generated with medium confidence**+ Downcouting mode (chế độ đếm xuống): Ở chế độ này, CNT đếm xuống từ giá trị thanh ghi ARR (hoặc 1 giá trị nào đó do người dùng ghi trực tiếp vào CNT trước) đến 0, sau đó CNT bắt đầu lại từ giá trị ARR, lúc này có sự kiện tràn counter – underflow, sự kiện này có thể tạo yêu cầu ngắt nếu người dùng cấu hình cho phép ngắt. Một ví dụ với ARR = 36:

+ Center-Aligned mode (chế độ đếm lên và xuống): Ở chế độ này, counter sẽ đếm lên từ 0 (hoặc một giá trị nào đó được người dùng ghi vào CNT trước) đến giá trị thanh ghi ARR – 1, lúc này xuất hiện sự kiện tràn counter – overflow, tiếp theo CNT  sẽ đếm xuống từ ARR tới 1, lúc này có sự kiện tràn counter – underflow, sau đó CNT sẽ về giá Diagram

Description automatically generatedtrị 0 và bắt đầu lại quá trình đếm lên. Một ví dụ với ARR = 06:

Diagram, schematic

Description automatically generatedDưới đây là sơ đồ khối timer của STM32f103C8T6.

Hình 10. Sơ đồ khối Timer

Trong các ứng dụng, Timer được sử dụng rộng rãi như trong hệ thống điều khiển PID, điều khiển motor, tạo các xung tín hiệu cho mạch đồng hồ, tạo các tín hiệu PWM để điều khiển độ rộng xung tín hiệu của motor, đèn LED, tạo các tín hiệu xung đầu vào cho các chức năng như đo tốc độ, đo khoảng cách, đo lực, và nhiều ứng dụng khác.

### **GPIO**

GPIO là chức năng ngoại vi cơ bản của vi điều khiển, cho phép người dùng lập trình các tín hiệu đầu vào và đầu ra.

Pin: Các chân tín hiệu Input/Output

Port: Mỗi khối GPIO trong vi điều khiển có thể điều khiển tối đa 1 số lượng pin nhất định, gọi là Port

Diagram, schematic

Description automatically generatedCác chế độ hoạt động của GPIO:

Hình 11. Các chế độ hoạt động của GPIO

* Input pull-up: Cấu hình Pin I/O là ngõ vào, có trở kéo lên nguồn.
* Input pull-down: Cấu hình Pin I/O là ngõ vào, có trở kéo xuống GND.
* Input floating: Cấu hình Pin I/O thả nổi, không có trở kéo. Sử dụng khi muốn dùng điện trở kéo ở ngoài mạch.
* Analog: Cấu hình chân là Analog, dùng cho các mode có sử dụng ADC hoặc DAC.
* Output push-pull: Cấu hình chân I/O là ngõ ra, khi output control bằng 0 thì N-MOS dẫn, chân I/O nối với Vss — xuất ra mức 0. Khi Output Control bằng 1 thì P-MOS dẫn, chân I/O nối ới Vdd — xuất ra mức 1.
* Output open-drain: Cấu hình chân I/O là ngõ ra, nếu Output control băng 0 thì N-MOS dẫn, chân I/O nối với Vss. Khi Output control băng 1 thì P-MOS và N-MOS đều không dẫn, chân I/O để nổi.
* Alternate function push-pull: Cấu hình chân I/O vừa là ngõ ra vừa là ngõ vào, nhưng không có trở kéo lên và kéo xuống ở input, chức năng output thì giống Output push-pull. Ngoài ra còn để sử dụng chức năng remap ( dùng để đổi chân cho các chức năng khác).
* Alternate function open-drain: Cấu hình chân I/O vừa là ngõ ra vừa ngõ vào. Ở chế độ Input không có trở kéo lên và xuống, ở chế độ output thì giống Output open-drain. Ngoài ra còn để sử dụng chức năng remap ( dùng để đổi chân cho các chức năng khác).

**\*\*\* Ngắt Ngoài:**

[**EXTI**](https://wiki.st.com/stm32mpu/wiki/EXTI_internal_peripheral) **(External Interupts)** tạm dịch là ngắt ngoài hay ngắt sự kiện bên ngoài. Ngắt EXTI được kích hoạt khi có sự kiện từ bên ngoài tác động vào chân EXTI đó, tùy theo sự kiện đó có phù hợp với điều kiện ngắt không thì ngắt ngoài mới sảy ra.

Ngắt ngoài STM32 được mô tả như sau:

Các tham số (Main Features):

* Kích hoạt độc lập trên mỗi dòng ngắt (Line Interrupts)
* Truy cập đến từng Bit trong mỗi dòng ngắt
* Tạo ra tối đa 20 sự kiện/ngắt
* Tín hiệu phải có độ rộng xung thấp hơn chu kì xung nhịp của APB2 (vì APB2 cấp xung cho GPIO)

Các Line ngắt ngoài được tổ chức như sau:

Diagram

Description automatically generated

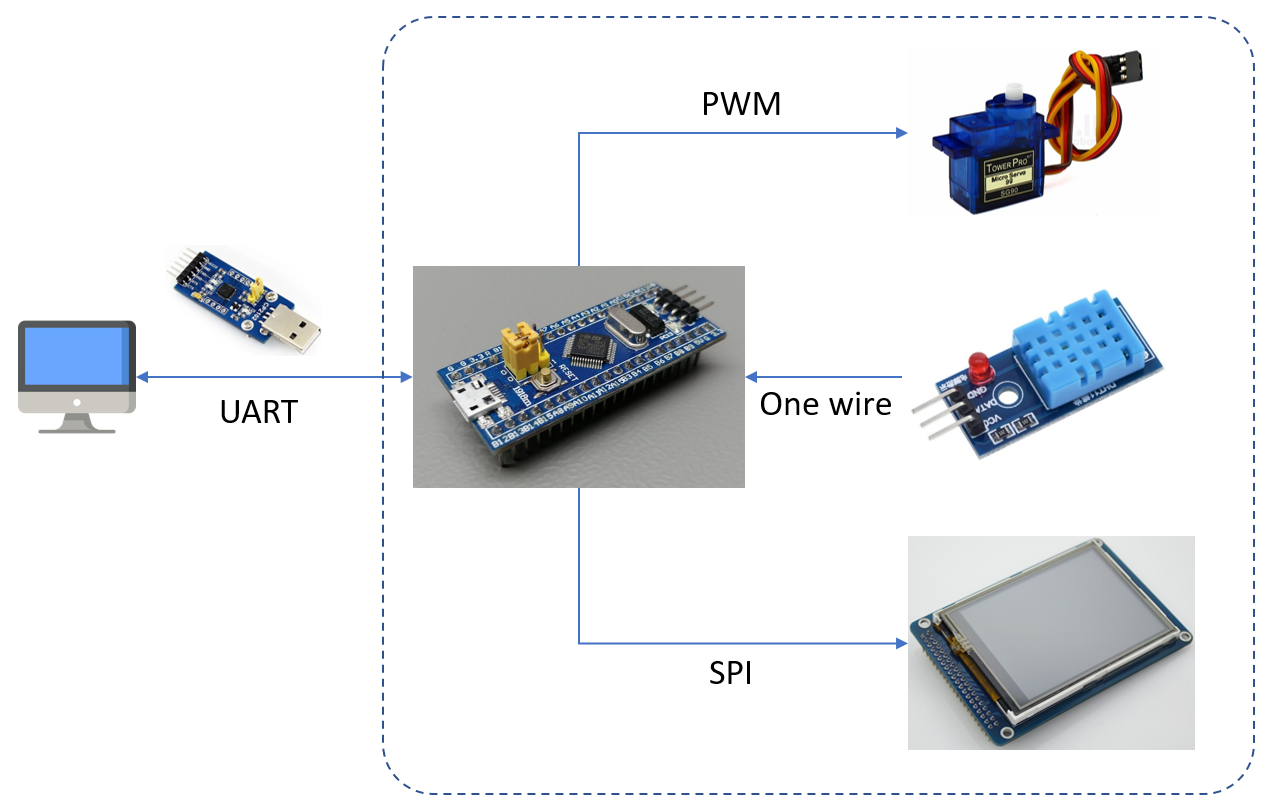
Hình 12. Cấu trúc tín hiệu của ngắt ngoài

Các chân PA0,PB0,…,PG0 sẽ chung là line EXTI0, Tiếp tục như vậy đến EXTI15 chúng ta có 16 ngắt.

4 ngắt ngoài đặc biệt đó là:

* EXTI line 16: dùng cho PVD output
* EXTI line 17: dùng cho sự kiện báo thức của bộ RTC
* EXTI line 18: dùng cho sự kiện thức dậy của USB
* EXTI line 19: dùng cho sự kiện thức dậy của ngoại vi Ethernet

**2.3 Sơ đồ ghép nối giữa STM32 và module phần cứng**

USB TTL được sử dụng để chuyển đổi tín hiệu UART (Universal Asynchronous Receiver Transmitter) từ STM32 sang tín hiệu USB và ngược lại. Việc kết nối USB TTL với STM32 sẽ giúp cho máy tính có thể giao tiếp với STM32 thông qua giao thức UART, mà không cần phải sử dụng các thiết bị ngoại vi khác như bo mạch Arduino.

Hình 13 . Sơ đồ ghép nối

Màn hình TFT là một loại màn hình tương tác với người dùng và được sử dụng trong các ứng dụng như điều khiển một số hệ thống. Để kết nối màn hình TFT với STM32, ta cần sử dụng giao thức truyền thông SPI (Serial Peripheral Interface). Giao thức SPI là một giao thức truyền thông đồng bộ, cho phép truyền dữ liệu giữa các thiết bị theo cách đồng bộ và nhanh chóng.

DHT11 là một cảm biến nhiệt độ và độ ẩm được sử dụng để đo nhiệt độ và độ ẩm của môi trường. Cảm biến này sử dụng giao thức one wire để truyền dữ liệu đến STM32. Giao thức one wire là một giao thức đơn dây cho phép truyền dữ liệu giữa các thiết bị thông qua một dây đơn.

Servo SG90 là một loại động cơ servo được sử dụng trong các ứng dụng điều khiển và định vị. Để điều khiển Servo SG90, STM32 sử dụng xung PWM (Pulse Width Modulation). Xung PWM là một loại xung điện áp được sử dụng để điều khiển độ rộng xung và tần số xung của động cơ servo, giúp điều khiển động cơ vận hành theo ý muốn.

Tóm lại, các thiết bị như USB TTL, màn hình TFT, DHT11 và servo SG90 đều được kết nối với STM32 thông qua các giao thức truyền thông khác nhau như UART, SPI, one wire và xung PWM, giúp cho STM32 có thể giao tiếp và điều khiển các thiết bị khác trong hệ thống.

**CHƯƠNG 3: THIẾT KẾ PHẦN MỀM**

## **Phân tích yêu cầu xử lý đảm bảo tính thời gian thực cho các đối tượng**

Để đáp ứng với điều khiển motor theo yêu cầu từ máy tính ở chế độ manual cần thực hiện ngay khi gửi tín hiệu xuống, cần phải có 1 tác vụ có mức ưu tiên cao để xử lý. Tác vụ này được thực thi khi có sự kiện yêu cầu điều khiển từ trên máy tính được gửi xuống

Để đảm bảo các tác vụ thực hiện đúng thời gian quy định đảm bảo tính thời gian thực cần phải có các bộ định thời để định thời gian thực hiện của các tác vụ

Các tác vụ quan trọng như hiển thị lên LCD TFT, truyền thông số lên máy tính, cần phải được thực thi riêng thành từng tác vụ với các mức ưu tiên hợp lý. Để giao tiếp trạng thái hoạt động của các tác vụ với nhau, cần sử dụng Semaphore thích hợp khi thực hiện xong tác vụ đọc thông số từ cảm biến sẽ release 2 Semaphore sau đó các tác vụ hiển thị và truyền dữ liệu sẽ lấy Semaphore tương ứng và thực hiện tác vụ.

## **Phân tích lựa chọn mô hình lập trình đơn nhiệm**

### **Phân tích**

Để đảm bảo tính thời gian thực trong lập trình đơn nhiệm, cần phải chú ý đến thời gian xử lý của các tác vụ, định thời cho các chu kỳ thực thi và ưu tiên các tác vụ theo độ ưu tiên được định trước. Ngoài ra, cũng cần đảm bảo các task không block nhau để tránh gây ảnh hưởng đến tính thời gian thực của chương trình

Với các yêu cầu được phân tích ở trên, tác vụ đo các thông số từ cảm biến phải được thực hiện trước tiên, sau đó sau khi đã lấy được các thông số, hệ thống sẽ thực hiện tác vụ điều khiển góc quay của động cơ nếu có thông số vượt ngưỡng theo chế độ manual, sau đó là hiển thị các thông số lên LCD và truyền thông số lên máy tính. Chức năng điều khiển góc quay của động cơ theo yêu cầu gửi trên máy tính xuống được ưu tiên cao nhất, nếu có tín hiệu yêu cầu gửi xuống sẽ lập tức dừng chương trình và lưu trạng thái của chương trình hiện tại sau đó thực hiện điều khiển động cơ.

Để có thể gửi được lệnh điều khiển góc quay của động cơ từ máy tính xuống ta xây dựng chức năng chuyển đổi mode giữa manual và auto. Ở đây, khi ở mode auto, khi đó nếu có thông số đo được vượt với ngưỡng đặt ra thì động cơ sẽ tự động quay. Còn khi được chuyển sang chế độ manual bằng cách gửi tín hiệu manual từ máy tính xuống, khi đó hệ thống sẽ chuyển sang chế độ điều khiển manual, ta sẽ gửi góc quay từ trên máy tính xuống và điều khiển góc của động cơ.

Trong chương trình này, nhóm thiết kế tác vụ đọc thông số từ cảm biến do có chu kỳ lấy mẫu là 750ms nên thiết kế task chạy trong 1s. Các tác vụ hiển thị lên LCD và điều khiển động cơ chỉ cho ra tín hiệu điều khiển nên thiết kế mỗi task chạy trong 500ms.Để chuyển sang task khác ta sử dụng 1 Timer để định thời gian các task thực hiện, khi Timer đếm xong khoảng thời gian đó, lập tức chuyển sang task khác. Nếu các task trên đang thực hiện mà có tín hiệu từ máy tính gửi xuống lập tức chương trình tạm dừng và lưu trạng thái của chương trình hiện tại và thực hiện yêu cầu từ máy tính.

Dựa vào các thiết lập ở trên, lưu đồ thuật toán của hệ thống theo đơn nhiệm như sau:

Diagram

Description automatically generated

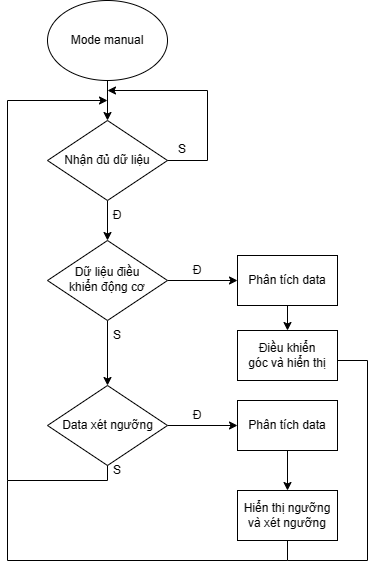
Hình 14. Lưu đồ thuật toán tổng quan

Lưu đồ thuật toán tổng quan của hệ thống

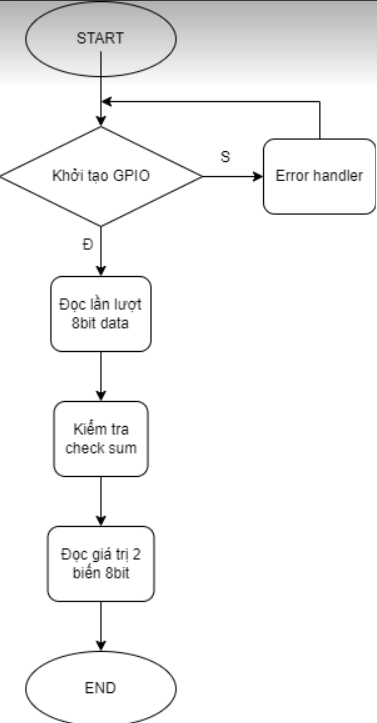
Diagram

Description automatically generated

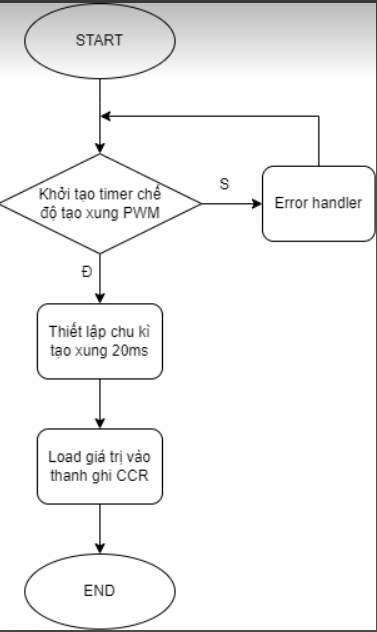
Hình 15 . Mode auto của chương trình



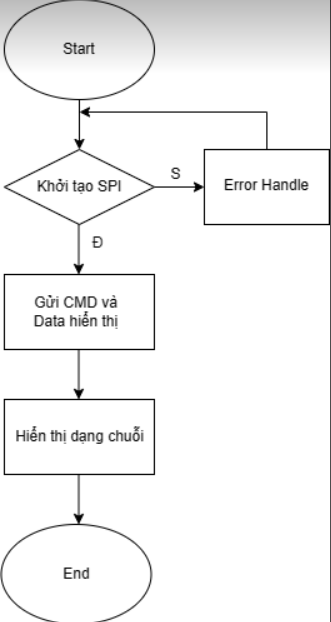
Hình16 . Mode manual của chương trình



Hình 17 . Đọc thông số từ cảm biến



Hình18 . Điều khiển động cơ



Hình 19. Hiển thị LCD TFT

### **Đo thời gian và tính toán thời gian lập lịch**

Nhóm sử dụng đo đạc và tính toán thời gian hoạt động của các Task thông qua cấu hình Timer2 để đo thời gian từ khi bắt đầu đến khi kết thúc của 1Task.Thông qua

Đo đạc và quy đổi,chúng ta có bảng thời gian hoạt động. Cấu hình timer2 để đo chu kì hoạt động của các task:

Diagram

Description automatically generated

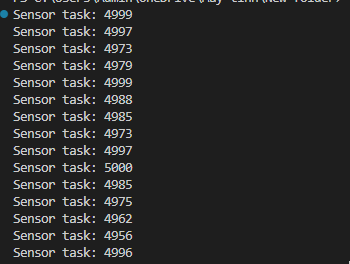
Hình 20. Xung clock là 72MHz

Graphical user interface, text, application

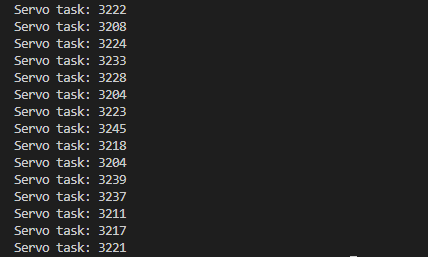
Description automatically generated

Hình 21 . Prescaler là 240

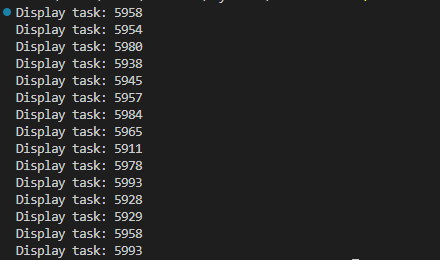
Task1: Task đọc cảm biến nhiệt độ DHT22



Task2: Task điều khiển động cơ



Task3: Task hiển thị



|  |  |  |
| --- | --- | --- |
| Task | Số chu kì máy lớn nhất | Thời gian hoạt động |
| Task1 | 240\*4992 | 5.3ms |
| Task2 | 240\*3224 | 2.9ms |
| Task3 | 240\*5963 | 8.7ms |

Từ kết quả phần trước, chúng em lập được bảng thông số thời gian thực hiện của các tasks như sau:

|  |  |  |  |
| --- | --- | --- | --- |
| Task | Ti(ms) | Di(ms) | Ci(ms) |
| Task1 | 500-1000 | 500-1000 | 5.3 |
| Task2 | 50 | 50 | 2.9 |
| Task3 | 50 | 50 | 8.7 |

Giả sử cấu hình chu kì đo của cảm biến là 750ms.

Chu kì P là BCNN của các Ti

P = BCNN(750,50,50)=750

Tiến hành tính toán:

F <= max {750,50,50} = 750

F >= min{5.3;2.9;8.7} = 2.9

2f-GCD(Ti,f) **<=** Di với mọi Task(i)

Từ kết quả trên chúng em tính toán được frame cần chọn là f=100

Vậy thời gian thực hiện được phân chia theo biểu đồ sau:

![Diagram

Description automatically generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAYABgAAD/4RDqRXhpZgAATU0AKgAAAAgABgALAAIAAAAmAAAIYgESAAMAAAABAAgAAAExAAIAAAAmAAAIiAEyAAIAAAAUAAAIrodpAAQAAAABAAAIwuocAAcAAAgMAAAAVgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFdpbmRvd3MgUGhvdG8gRWRpdG9yIDEwLjAuMTAwMTEuMTYzODQAV2luZG93cyBQaG90byBFZGl0b3IgMTAuMC4xMDAxMS4xNjM4NAAyMDIzOjAzOjEwIDIzOjU0OjQ4AAAB6hwABwAACAwAAAjUAAAAABzqAAAACAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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TFmAc+Y2fxx0/StfGFVl5kDfNU2sMaAIysjYLZB4pgJ3eZISFznFPiAV2lkYgKcYxnrSFXY72OI88Z6mmMGLXEjBm/dhvkHoKjKsHZOwPB9R605GLvsxhc8EGhygPkx9mIyO1IBisAQq5BBH5UHGz5eX3En6U9QcbRwQcGkxsGQVJPGKBEeFULIemT+dIuDlmPytyBijYBjzOhOcHrSSEyABh8inIAoAam5nGRiPOBzzTBl3KDscUrBnIVcKvYYxSM7D93GCrg4z3oAiYFhhPzpu4RnIxu9KlBMYwAMjjFRkosqtIMDn88cUwI2PG/J+9yKiJJIyfoKk7gnpnpTSM+oAoERMDkZ6UxsZIFSH7uOlRnk8evNADMHNIwwPSl4H40hNMQw0xskU8+9NPTntQMZRRR6CgQduaKD+lJ9aADvRS0lAAPpRRijqaYBR/Og0fzoAPrmiiigB4o+lGPSlpDE+lFLSUAHej0o60uPp+VACe+KKOOuaDwKACgUUUAH9KMUUtACdqO9FLQAlFKKTigAFFFHfigA/KiiigA46UUUdKAD8OaOtFHagA/OigUfSgAooo+tAB3zRR70UAGP84oxxRRQAUcYooxmgA9M0Udj60elABRijvR3oAPaiijFABR9aMcUUAFFFHagA7UnSlooASlxxR3oFACdaP50tHtQAnWjr1paOe1ACUv0oooAKTpS9sCgetABR1oFIKAF/E0c0dKKAE+tFLRQAmKKB70v1PFACUUv4UUAJRS0g60AHejvS0fSgBKKKKYgo70opBxigAxR3o/KigAoo5o7YoAO3XtRR3oxz70AFFBooGFHaiikAUD2oooEHFHfiiigAo4oxRQMM5o7Ue+KP50xB3oxR0oxzQAdfejpRRQAfnR6Zo7UUhh09qKKKYBR196O1GOaBB24oo/zmigA70d6KBQAUUUUgCg0UCgAooo9qACjrRRQAUf0o70tMBKXpikpaAEpaKKAE7Zpe1HtRQAUYopfwoGJjJ5qTt70ijnmne9AgxzSHpR2o/lTAKKKWgBM46Ud+aX2pOnNAC0mOtLRQAUg5GaXHrRQAfSij+ftRQAUUfWigAo7cdaO1FABR2+tH8qMnd2x9KAE7Y60hPpTj3phPXFIAPWk60UfWgA4x7UUdaKBi9uKBSClHSkAtFJ2p1AAOvtS4yaQ9MilGcZxQApIxSkYO3POaTvijOD60CJIn8uZHH8LV0UBH2YzFgTwMehrmxz1rT0yfgxueM5pAjRcMBuJ43DpTyfOnIziLPrilfMkQU/d3bsUgjaRREoGPUnFBQwkszKq4CtjjmkQgK5yVfOQf507gJtUHAfBOfSmqoT0LFiaQDl3KMAZY011+zkSMGJY9MdacG2FWcFgzYOKaclssTjsCc0AJtBYl2OM8VESZJFyAEBP41JES0jZGEDU190zLFHgHJAPrmgCNSGUjOCD+lM3sD8p5PenqQ8SKvXJ/8A1VHtCfdHOSTzQAzhMnq1NcYX5jyeo9KVlKjcR1qMs38X60ARvljg/dHcU3GW6VKy5OO1RZOSF/lVCI26jFISMAAfWlboCKaw4z60AMI5pDjH1604kYGelR8YGaBCGm9eKdj1pp5pgNYDjHWm8DrTm+8RnNNpAFB6nHSj2o4oAD/Sj19KBQKYCdBRS0Y5pAJQOtFAxTADRR2xR2oAfR1paMUhhR9KPwooABR0NBooAO9Hc+lGOPajBoAKKKKACgUc/wD16T8M0ALSUDpSmgBOmfejtS/WigBP8ml56UZzQelACCilooAOnNJS54AzQaACj370UUAJ1+lLRRQAlLj0FGaKAEFLRRigBOpo74opaACg0UfyoAKSl9qMUAFFGKB1xigBO1HbtS0d6AE9qKKWgBKP8KXHPvR7UAFJR/OjvQAd6KKBjtQACjpRRQAYooFAFABRiijtQAUdaKDxQAd6KMcUUAFFFFAB3o7UY4HvRigA9aKKO9ABR6Ue9FABRg0d6MZoAPpSdqWj60AJRS0daYgoo/CjHr0pAFFFFMA96P8AGiigAxRR+FFAAKSlPSjr2oGJRS9sfyopAIaXvRz2o70CCkHtRS0AHaijrQaBiUUv8qKBCY6UtHWjFMBO/NFKRQKAE/lR26UdKXv0pAJ/KiloxzTAKO1JS0AH0pO5paKAA0Uc4o7daAE4IopTR2pAJSmijmgAo70dOtFACd80vWj+VH0oAKSlxkUfXpTAOhopaTv60AHejFGKKAAUtA5ooAQ+1OGKOlOXrQAAdaXpR1pO1MBeaTvS+lHpQAdqDij8KKACijpR9aACj+VFHbNAAelFLz0ooEJRQOKKBh1NL0NGT+tFAB3pM/hSkUntQAUHpSn2pDQA0n86b3pT1pKQB/OjrR9KKACiij+lAC0neig9elAxRS0go69BSAU04nC7aQfkPSgcZFAC9h7Uox+NJ65o75NADhyM1LBIUkUg8Z6ZqEcj2pV6EDPFAjqoXE8aNGBsGOc013O/5AfvDp9QP61m6XdNtFsB98jBrULpFG8aODMSOMdOc0mUI5KBo1bnfzimSKEAYt8x/h6/jS8Lzty+fWmquC8suSc9BSAORtkcZUnH0pilpJWB/wBWM4p38G8s2w8gZ4FClnJ6YyD+FACIHYhCuBnrUKbmbanByeanc7mIBxls5pnEXCAls85NMCLb5YG1eSckDsaZlYjvblu+KldyoIIwaheMDa7HIPakAgQO672JBPSoMMyAkDHbmp4lyxLH5STj2qInecdhxkUxEe7J2mmbipyp+op74G1Qeh5qNuMe9MBr4UBQMkk9PSouxJ6U9lwcnmmEUAMOc89PemnkHI6U7HBzTTyaBCfiab2p54bim0wGkYzTSPWnnA7fmKbjJOaQDcZooPBooAO1H4UUUwE+tFLSc0ABzS0UlABRSikoAkP0oP8A+uigUhh9aM5o6+tLxQAmKO9KKKAE/SiloxzQAn86B1pT7cmg4zj9aAE7Y7UUUUAFHbPNLxSfSgAoo9aBQAduKKMUUAGKBzRS9qAEo70vSigBOlHFGOlL/KgBOvajNFLQAlHPc0Zo56jmgA6c0UUtACDjp196KXvSfWgAoxRiloAQj0o6Uv1oxQAgopcc0fyoAQ0YpRk0hHGKADtQOaO1L9KAEoo9elL1oASilNJQAUdaKXpQAlH9aWkNABRilpPSgA70UUGgABpKXFH4GgBKX8aKPpQAe9H4UH+VFACUUuKMdaAE6UtHSj2oATHFFLijmgBKKWigBM0f56UtFACDmiilxxTEJ9f50d6UUAd6AEoxS+9GKADHp6UntSjvR3oASlo2nPFBGOvSgBKKWkoAOKDRil/xoGIetFL3pKBAOlFL34oHpQAlFOwe1J9aQCdKPwpe1KFJzigBtHenshAzTPpTAKO9LSfWgA6Ud+RR0o6fSgAzRzS9qKAEopaUDqaAG49aO3WnsuBTeozQAlB/lSgZ6VJsJ+lAEVGKcyEDNJ16UAJ3oo5paQCZo96Xv6UUwE4ope1HWgBKWl2k/T0pMYoASlpe9IOnvQAlL/Wl2nFJigA5o6dOtH0oFACjr0p/amgYPHan/SgBKOtFKP8APFMBPxo6fjSjg0Y9BQAlFBFKO9ACClxxRg4o+lAB+NFB4o680AHYHt0oox+VFAgo44opRzQAmKOMUUtMYlHvRg9KO1IAI5xTTTyTimHNADT14pKO9HSkAUdDR/OigAooooAX1zxSGlozzSAAKBwaOvFAoGL9KX8aTp7UdDmgB1KOab2zTqAEPTinDO3IpB1paYE9rJ5MoYdfWuihlBiDIMtnOMZzmuXzwBitnRrhQ21vv5GB60mCNAqDE87Y4ONoOCT6UwkOhLA9aViSHlbIbOSPakRTJli2EpDIyu7gcKTQckMg7dDSyFidgHy+wpGO0mMDJzy1AhkhcDaPvZpjHYBnl2NOUBS3OWP6Uu0ZLH5vrQBFyG3SdOpprsCnP3c5xSlcgOx6HpTeMHjjrxQA18uAoIA9qY390cY60EkkgVGSQfc0AI+McDmo2BA+vp2qWUKuccsepqI9jTAjPrzmmHk+1P8AU+nIptAEfXpTWGDx+dPPWmtTENHr+dIaXtSGgBDnvTT+tO7GgDPtQAw89aSlOc0lIAooopgHWk+tLR9KACijtij3oGFFH86KALAiYikeIoMsOPWtLyWikVZFOWHcYNXXtkzCNud55BFIDnccd6MYrX1XSnt18+JcxE4IA+7WSc9KAEoHFFL7YoAKTFO7UDpQAgFLsO3AqSOMHk1ctIFmmVOeTjjtTEZtKOlbCacs5ePBU4+U1lvG0cpjkGGXrSGR7fSl2NjODViFM5GDntVy3h3SbCPm9KYGRjJ9KXFa9zpjvaNcQKfk+8o5yKyBg9OlIAo4ooHTjtQAUD2NFOxkUAJ1+tFFSRx7uSOKAGhST0ppXFadlCJbhYyOp4q3qGmIHAQAZFAGDzilCFhmnyQvFcNFIMFTVq2h8xguOM0AU/KbFMPFb5tAksY7MazL+2+zzHHTJ5FAinxSZ9OtO70UDEo7Ud/Wl+lACDpS0UGgAxTlXccCgDp71ajXC8D8aAFtbFrklFOCFLflVWWJonKv1Fb+ijbPIx/uEfSo9Qs/Ntp7hVIZTuAA7UgMIDJqRI9zfWkUZwOtW4Iy7BR1qkJkMlq6KOOvT3qqRg11k1uBHHxgrz+FYmr2JhdbgDCSEjr3pAjOo70vek/OgYf4UdqMUUAHajHrS4oAoAAO3epkgDELnk8UIo61bhA8yMY5LAfrTAo3EEkEmyRSCKZjn3ro9XtBciWROGjXcRg/jXOLyAaQChSTUwt8pk0IMitiygElowbkMCM0CMB1KNgim4rS1a2MKxSDlWwpPvWdigYn6UYpcUUAJS4o+lFAAQaULkigc1KgyPSgBBCWUleoFQgVp2igXEe4Aqxxis912Suh6qxFAhv86fsJHPem+4qdQSik/nTAhZCFphrRjhWS3lPJKoWH1FZw6UAFHtRRSGA6UU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Bộ lập lich

## **Phân tích, áp dụng các kỹ thuật trong lập trình đa nhiệm**

### **3.3.1. Giới thiệu và phân tích để áp dụng kỹ thuật trong FreeRTOS**

1. ***Giới thiệu hệ điều hành thời gian thực***

Hệ điều hành thời gian thực là một hệ điều hành được thiết kế đặc biệt để chạy các ứng dụng với thời gian rất chính xác và mức độ tin cậy cao. Để được coi là thời gian thực, hệ điều hành phải có thời gian tối đa đã biết cho mỗi hoạt động quan trọng mà nó thực hiện. Chương trình hệ điều hành thời gian thực giúp tổ chức chương trình với nhiều tác vụ chạy đa nhiệm gần như song song với nhau. Phân bổ chương trình thành các tác vụ, các tác vụ với các mức ưu tiên khác nhau chạy đạn xen dưới sự quản lý của bộ lập lịch, việc thêm bớt các tác vụ vào mà không gây xáo trộn chương trình, cũng như không phải xây dựng lại toàn bộ chương trình. Hệ điều hành thời gian thực thực thi các tác vụ là các vòng lặp vô hạn, đo đó nó sử dụng ngắt làm cơ chế tạm dừng tác vụ đang chạy để bộ lập lịch lựa chọn tác vụ có mức ưu tiên cao nhất ở trạng thái sẵn sàng để chạy tiếp theo sau. Ngắt này có thể sinh ra bởi ngắt của các ngoại vi được người dùng xây dựng cho chương trình, ngoài ra thì hệ điều hành trang bị bộ đếm ngắt theo chu kì giúp bộ lập lịch lên hoạt động các tác vụ. Một số hệ điều hành thời gian thực phổ biến hiện nay: VxWorks Real-Time Operating System, QNX Neutrino, Free RTOS, Green Hills Software.

VxWorks Real-Time Operating System: VxWorks là phần mềm độc quyền và cần phải có giấy phép để sử dụng phần mềm đó. VxWorks được sử dụng rộng rãi trong lĩnh vực an toàn, bảo mật, IoT… và đây là một trong những Hệ điều hành thời gian thực nổi tiếng nhất được sử dụng cho các ứng dụng nhúng.

QNX Neutrino Real-Time Operating System: Chứa được sử dụng trong các ứng dụng tự động hóa công nghiệp, y tế và cả trong lĩnh vực robot.

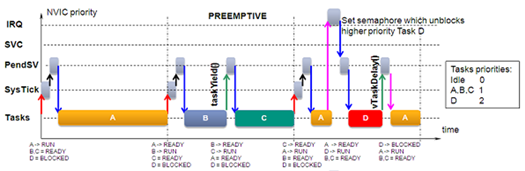
Free RTOS là một trong những hệ điều hành thời gian thực nổi tiếng với các lập trình viên. Free RTOS là một mã nguồn mở, miễn phí giúp cho lập trình viên dễ tiếp cận và sử dụng. FreeRTOS thích hợp cho những vi điều khiển có không gian chương trình bị giới hạn. Lõi FreeRTOS chiếm từ 10-15kb bộ nhớ chương trình

Phần mềm Green Hills, chủ yếu được sử dụng để bảo mật và các ứng dụng liên quan đến an toàn.

Do vậy, đối với hệ thống này, em sẽ sử dụng hệ điều hành FreeRTOS để phát triển phần mềm

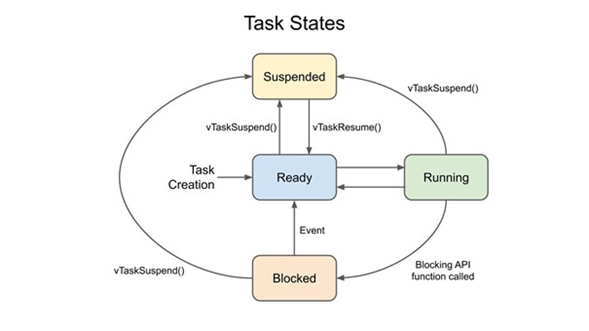
1. ***Hệ điều hành thời gian thực FreeRTOS***

Như hình trên khi xảy ra ngắt systick, tác vụ đang chạy sẽ được lưu vào ngăn xếp sau khi vào ngắt và ngay lập tức ra khỏi ngắt này, bộ lập lịch sẽ xem xét tác vụ nào có mức ưu tiên cao nhất ở trạng thái sẵn sàng để cho phép tác vụ đó được hoạt động ngay sau đó. Ở đây các tác vụ A, B, C đang ở trạng thái sẵn sàng và có mức ưu tiên ngang nhau thì bộ lập lịch sẽ lần lượt chọn đan xen các tác vụ này. Ở lần ngắt systick đầu tiên tác vụ A chạy và lần tiếp theo là tác vụ B. Tác vụ B trong quá trình hoạt động nhận API chặn tác vụ chính nó, ngay lúc này bộ lập lịch sẽ lựa chọn tác vụ tiếp theo được hoạt động lúc này là tác vụ C do cơ chế round-robin scheduling đan xen các tác vụ cùng mức ưu tiên. Các tác vụ A, B, C đan xen thực hiện cho đến khi tác vụ có mức ưu tiên cao hơn ở trạng thái sẵn sàng. Ở đây khi một ngắt diễn ra cho phép bỏ chặn tác vụ D, sau khi thực hiện xong ngắt bộ lập lịch xét các vụ mức ưu tiên cao nhất đang ở trạng thái sẵn sàng được thực hiện là tác vụ D. Khi tác vụ mưc ưu tiên cao nhất D bị chặn thì lại lần lượt các tác vụ khác có mức ưu tiên cao nhất đang sẵn sàng có thể được thực hiện.



Hình 22 . Mô hình chạy các tác vụ

1. ***Các trạng thái của tác vụ***



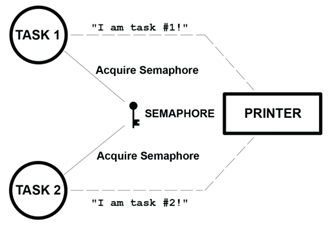
Hình 23. Mô tả trạng thái các tác vụ và chuyển đổi giữa các trạng thái

Trong RTOS thì task có 4 trạng thái:

* Ready: Task sẵn sang để có thể thực thi nhưng chưa được thực thi do các task khác với độ ưu tiên ngang bằng hoặc hơn đang chạu
* Running: Task đang thực thi
* Blocked: Task đang chờ 1 sự kiện nào đó xảy ra, sự kiện này có thể là khoảng thời gian hoặc 1 sự kiện nào đó từ task khác
* Suppended: Task ở trạng thái treo, về cơ bản thì trạng thái này cũng tương tự như Blocked. Nhưng ddiemr khác nhau là cách chuyển trạng thái hiện tại sang trạng thái Ready. Chỉ gọi hàm vTaskResume() thì task bị treo mới chuyển sang trạng thái ready để thực thi.

Trong dự án này nhóm sử dụng vTaskSupend này để điều khiển tác vụ hiển thị. Tác vụ hiển thị chỉ hoạt động trở lại khi cảm biến đọc xong dữ liệu, update giá trị hiển thị hoặc đến chu kì sáng của màn hình.

1. ***Quản lí truy cập tài nguyên và đồng bộ sự kiện***



Hình 24 . Mô tả hoạt động của Semaphore

Để quản lý tài nguyên hệ điều hành thời gian thực sử dụng các khóa semaphores. Có thể sử dụng song song với nhiều lượng truy cập tài nguyên cùng lúc với số lượng khóa định sẵn, cho phép số lượng tác vụ nhiều nhất thao tác tài nguyên theo số khóa mở ra. Ở trên hình ví dụ một khóa semaphore giao tiếp in ra màn hình, nếu không có khóa semaphore này các tác vụ hoạt động đan xem thì dữ liệu in ra sẽ thao tác đạ xem giữa hai tác vụ và dòng chữ hiển thị sẽ là trộn lẫn của cả hai tác vụ như vậy dữ liệu xuất ra đã bị sai thông tin. Vì thế cơ chế này tạo ra để khóa chỉ cho phép một tác vụ truy xất tới tài nguyên này và nó sẽ bị khóa không cho tác vụ khác truy xuất vào cho tới khi tác vụ kia thực hiện xong trả khóa lại cho tác vụ khác có nhu cầu vào truy xuất với tài nguyên này.

### **3.3.2. Task và Semaphore**

**a. *Task***

Với lập trình đa nhiệm, nhóm chúng em tạo ra 4 Task để xử lý, bao gồm các task:

* Đo các thông số nhiệt độ và độ ẩm từ cảm biến;
* Hiển thị các thông số đo được lên LCD và máy tính;
* Điều khiển động cơ;
* Nhận yêu cầu điều khiển và đổi chế độ từ máy tính.

Trong đó Task Nhận yêu cầu từ máy tính sẽ có mức ưu tiên cao nhất vì cần thực hiện ngay khi nhận yêu cầu. Như vậy mức ưu tiên từ cao đến cao nhất đến thấp nhất sẽ là Task nhận yêu cầu điều khiển, Task đo thông số, Task điều khiển động cơ và cuối cùng là Task hiển thị.

**b*. Semaphore***

Vì có nhiều Task cùng sử dụng chung dữ liệu nhiệt độ, độ ẩm đo được từ Task đo nhiệt độ độ ẩm từ cảm biến vì vậy dẫn dễ đến xung đột vì vậy nhóm thiết kế sử dụng Semaphore để có thể đồng bộ hóa việc truy cập vào bộ nhớ chung khi có nhiều Task sử dụng dữ liệu đó

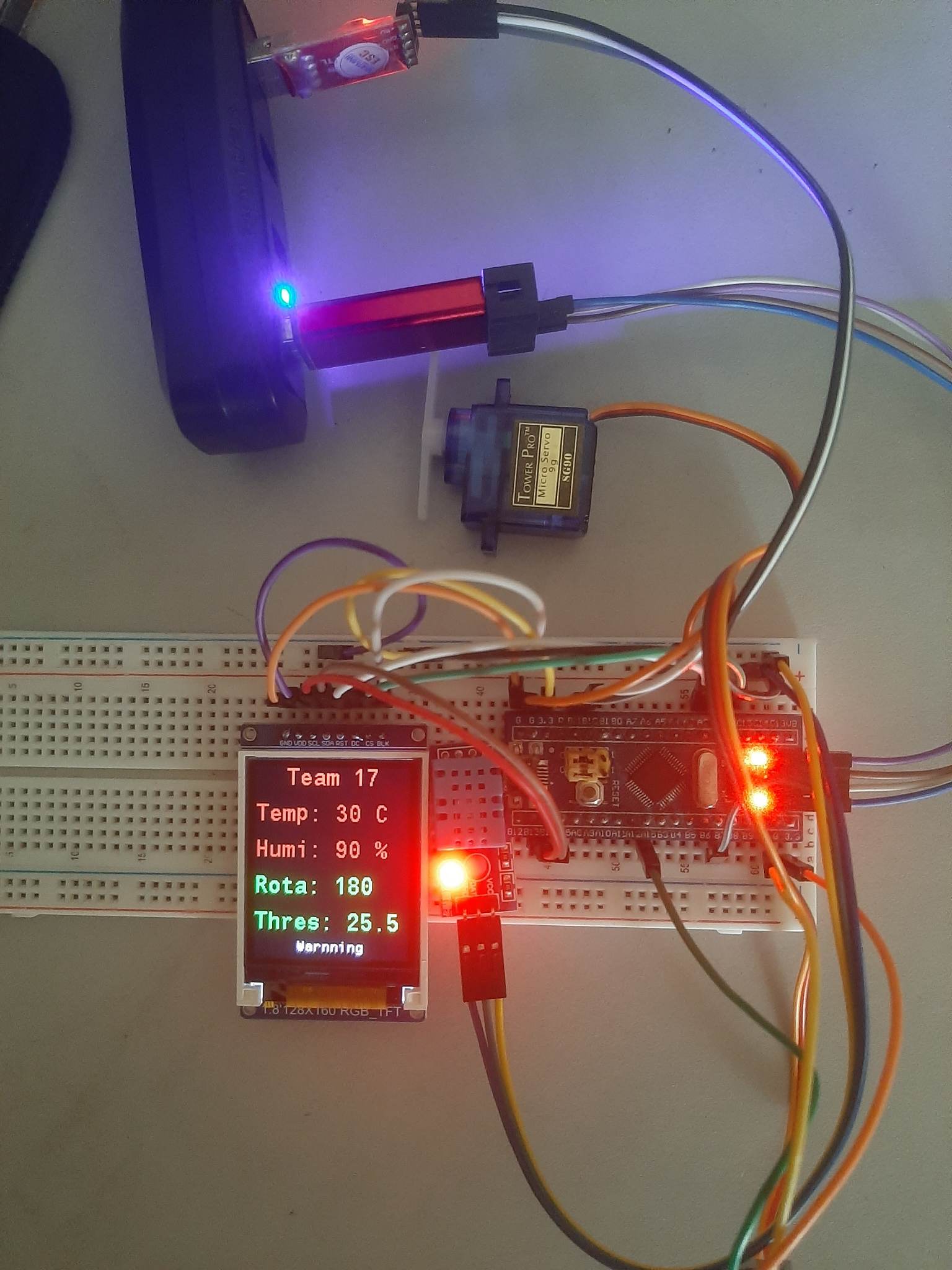
Khi đó :

+ Khi Task đo thông số từ cảm biến thực hiện xong sẽ Release Semaphore cho task hiển thị

+ Task hiển thị sẽ đợi Semaphore được giải phóng bởi task đọc thông số trước đó để có thể sử dụng dữ liệu nhiệt độ và độ ẩm

**CHƯƠNG 4: KẾT QUẢ VÀ ĐÁNH GIÁ**

## **Kết quả đạt được**



Hình 25. Màn hình hiển thị

Sau quá trình lập trình và sửa lỗi, thiết bị đã hoạt động đúng với tính toán và thiết kế, hình trên là hình ảnh của màn hình LCD TFT hiển thị toàn bộ các thông số nhiệt độ và độ ẩm đo được từ cảm biến là 2 dòng màu đỏ Temp và Humi, 2 dòng màu xanh phía dưới hiển thị góc quay của động cơ và ngưỡng nhiệt độ, dòng màu trắng ở dưới cùng là cảnh báo Warning khi nhiệt độ đo được vượt ngưỡng, và phía trên cùng là số nhóm.

Các số liệu, thông số được hiển thị rõ ràng trên LCD TFT. Động cơ quay đúng góc theo thông số nhiệt độ, cảnh báo được hiển thị lên màn hình khi đo được thông số nhiệt độ vượt ngưỡng, thông số và trạng thái hoạt động của hệ thống được truyền lên máy tính. Chuyển được chế độ từ auto sang manual để điều khiển được động cơ theo yêu cầu từ máy tính và thay đổi ngưỡng nhiệt độ.

Ảnh có chứa văn bản

Mô tả được tạo tự động

Hình 26 . Thông số đẩy lên máy tính

Hình ảnh trên terminal ở chế độ auto, hiển thị các thông số nhiệt độ, độ ẩm, góc quay và task đang được thực thi của hệ thống

Ảnh có chứa văn bản

Mô tả được tạo tự động

Hình 27. Gửi yêu cầu từ máy tính

Hình trên ở phần chữ màu hồng là phần gửi yêu cầu từ máy tính xuống:

+ “manual” là đổi từ chế độ auto sang manual để có thể điều khiển từ máy tính

+ “Rota 90” là thực hiện điều khiển động cơ quay góc 90 độ

+ “Threshold 25” là thay đổi ngưỡng nhiệt độ thành 25 độ

+“auto” là đổi từ chế độ manual sang auto để hệ thống có thể tự điều khiển

Ảnh có chứa văn bản, panen điều khiển

Mô tả được tạo tự động

Hình 28 . Thông số được cập nhật

Ta có thể thấy sau khi thay đổi các thông số điều khiển theo yêu cầu từ máy tính, màn hình hiển thị đã cập nhật những thông số đó lên một cách chính xác.

## **4.2 Phân tích và đánh giá kết quả**

Phân tích và đánh giá

* Ở cả phần lập trình đơn nhiệm và đa nhiệm chương trình đều đảm bảo tính thời gian thực của hệ thống.
* Hệ thống hoạt động ổn định, đúng với yêu cầu, các tác vụ hoạt động độc lập, không gây ra tình trạng trì hoãn hệ thống
* Hệ thống phản hồi nhanh với yêu cầu điều khiển được gửi từ máy tính
* Có khả năng mở rộng thêm các tính năng nâng cao

## **4.3 Thống kê công việc và mức độ đóng góp**

|  |  |  |  |
| --- | --- | --- | --- |
| STT | Họ và tên - MSSV | Công việc | Đánh giá mức độ đóng góp |
| 1 | Nguyễn Quang Huy - 20191894 | + Code giao tiếp giữa module phần cứng với STM32 như: cảm biến,  điều khiển động cơ, truyền thông số lên máy tính và nhận yêu cầu điều khiển.  + Xây dựng thuật toán cho chương trình  +Lập trình đơn nhiệm  + Lập trình FreeRTOS, áp dụng các kỹ thuật như task, semaphore  + Thử nghiệm và đánh giá | 10/10 |
| 2 | Nguyễn Huy Hoàng - 20191855 | +Code giao tiếp giữa module phần cứng với STM32 như: cảm biến,  điều khiển động cơ, truyền thông số lên máy tính và nhận yêu cầu điều khiển, hiển thị LCD  + Xây dựng thuật toán cho chương trình  + Lập trình đơn nhiệm  + Lập trình FreeRTOS, áp dụng các kỹ thuật như task, semaphore  + Thử nghiệm và đánh giá | 10/10 |
| 3 | Đặng Trung Hiếu - 20191829 | + Code giao tiếp với cảm biến, điều khiển động cơ với STM32  + Lập trình đa nhiệm cho task đọc cảm biến, điều khiển động cơ  + Thử nghiệm và đánh giá | 9/10 |
| 4 | Phạm Tiến Mạnh - 20191954 | + Code truyền thông số và nhận tín hiệu điều khiển từ máy tính  + Lập trình đa nhiệm cho task truyền thông số lên máy tính và nhận yêu cầu  + Thử nghiệm và đánh giá | 8/10 |

# **CHƯƠNG 5: LINK SHARE THƯ MỤC LẬP TRÌNH**

Github: https://github.com/huyhoanghust/Embedded-System-Design\_HUST\_20221