

DESIGN DOCUMENT

OBSTACLE AVOIDANCE CAR DESIGN



Prepared By:

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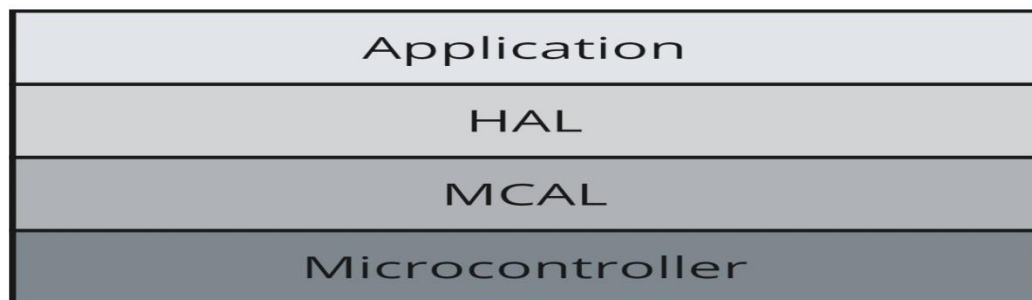
1. Project introduction:	2
2. High Level Design:	2
a. Layered Architectures:	2
b. Modules description:	3
i. MCAL:	3
ii. HAL:	3
iii. Application:	3
c. Drivers' documentation:-	4
i. DIO Driver:	4
Description:	4
Functions:	4
ii. Timer Driver:	4
Description:	4
Functions:	4
iii. Interrupt Driver:	5
Description:	5
Functions:	5
iv. Button Driver:	5
Description:	5
Functions:	5
v. LCD Driver:	خطأ! الإشارة المرجعية غير معروفة.
Description:	5
Functions:	5
vi. Motor Driver:	6
Description:	6
Functions:	6
3. Low Level Design:	6
a. Flow Charts :	6
1. MCAL Layer:	6
i. DIO Functions:	6
ii. External Interrupt Functions	7
iii. Timers Function	9
2. HAL Layer:	12
i. LCD Functions:	12
ii. Button Functions:	16
iii. Motor Functions:	17
iv. Key Pad Functions:	19
b. Configurations:-	20
i. Dio:	20
ii. EX_Interrupt:	22
iii. Timers:	23
iv. LCD:	24

1. Project introduction:

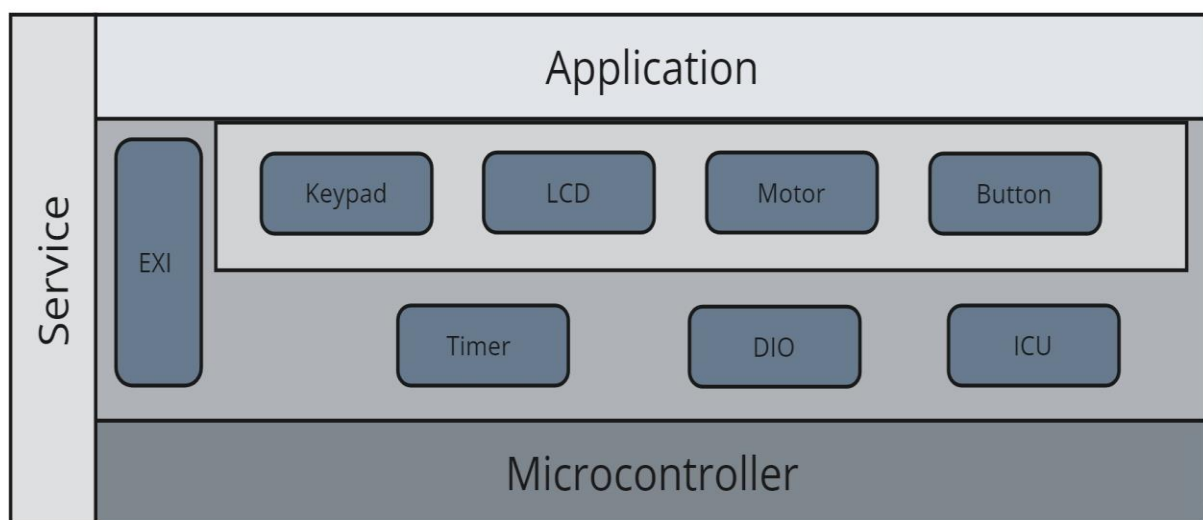
The aim of this project is to design a four wheels driving car that has the ability to avoid any type of obstacle with a self-enhancing mechanism that changes speed and direction according to the circumstances

2. High Level Design:

a. Layered Architectures:



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b. Modules description:

- i. MCAL:** *It is a software module that directly accesses on-chip MCU peripheral modules and external devices that are mapped to memory, and makes the upper software layer independent of the MCU.*

- ii. HAL:** *It is a layer of programming that allows The Application Layer to interact with a hardware device at a general or abstract level rather than at a detailed hardware level.*

- iii. Application:** *Application Layer: This is the topmost layer of the software stack, which contains the actual application logic. It interacts with the lower layers to perform its tasks. It is responsible for implementing the desired functionality of the system.*

c. Drivers' documentation:-

i. DIO Driver:

Description: *The DIO (Digital Input Output) driver is responsible for setting up the digital pins of the microcontroller to either input or output mode. This driver will be used to control the buttons and LEDs.*

Functions:

```
DIO_ERROR_TYPE DIO_INITPIN(DIO_PIN_TYPE PIN,DIO_PINSTATUS_TYPE STATUS);
DIO_ERROR_TYPE DIO_WRITEPIN(DIO_PIN_TYPE PIN,DIO_VOLTAGE_TYPE VOLTAGE);
DIO_ERROR_TYPE DIO_READPIN(DIO_PIN_TYPE PIN,DIO_VOLTAGE_TYPE* VOLT);
void DIO_TogglePin(DIO_PIN_TYPE pin);
```

ii. Timer Driver:

Description: *The Timer driver is responsible for setting up and controlling the timers of the microcontroller. This driver will be used to create the timing delays required in the project.*

Functions:

//timer 0 prototypes

```
Timer_ErrorStatus TIMER_0_init(Timer_Mode mode);
Timer_ErrorStatus TIMER_0_start(Timer_Prescaler prescaler);
void TIMER_0_stop(void);
Timer_ErrorStatus TIMER_0_setIntialValue(uint8_t value);
Timer_ErrorStatus TIMER_0_OvfNum(double overflow);
void TIMER_0_DELAY_MS(double _delay);
```

//timer 2 prototypes

```
Timer_ErrorStatus TIMER_2_init(Timer_Mode mode);
Timer_ErrorStatus TIMER_2_start(Timer_Prescaler prescaler);
void TIMER_2_stop(void);
Timer_ErrorStatus TIMER_2_setIntialValue(uint8_t value);
Timer_ErrorStatus TIMER_2_OvfNum(double overflow);
void TIMER_2_DELAY_MS(double _delay);
void TIMER_2_INT();
```

//PWM Function prototype

```
void TIMER_0_pwm(float intial);
```

iii. Interrupt Driver:

Description: *The Interrupt driver is responsible for setting up and controlling the interrupts of the microcontroller. This driver will be used to detect button presses.*

Functions:

```
EN_int_error_t EXI_Enable (EN_int_t Interrupt);  
EN_int_error_t EXI_Disable (EN_int_t Interrupt);  
EN_int_error_t EXI_Trigger(EN_int_t Interrupt, EN_trig trigger);  
void EXI_SetCallBack(EN_int_t Interrupt, void(*ptrf)(void));
```

iv. Button Driver:

Description: *The Button driver is responsible for setting up and controlling the buttons of the microcontroller. This driver will be used to detect button presses.*

Functions:

```
BUTTON_ERROR_TYPE Button_INIT(DIO_PIN_TYPE PIN);  
BUTTON_ERROR_TYPE Button_read(DIO_PIN_TYPE PIN, DIO_VOLTAGE_TYPE *VOLT);
```

v. LCD Driver:

Description: *This driver controls the LCD display and provides an interface between the microcontroller and the LCD hardware, allowing the microcontroller to display the temperature readings and messages to the user..*

Functions:

```
void LCD_WRITE_COMMAND(uint8_t a_COMMAND);  
void LCD_WRITE_DATA(uint8_t a_DATA);  
void LCD_INIT(void);  
void LCD_Write_String(uint8_t *a_String);  
void LCD_Write_Number(uint32_t a_number);  
void LCD_Clear(void);  
void LCD_GoTo(uint8_t a_line, uint8_t a_cell);  
void LCD_Write_Charecter(uint8_t a_char);
```

vi. Motor Driver:

Description: *The Motor driver is responsible for setting up and controlling the motors of the car. This driver will be used to control the speed and direction of the motors.*

Functions:

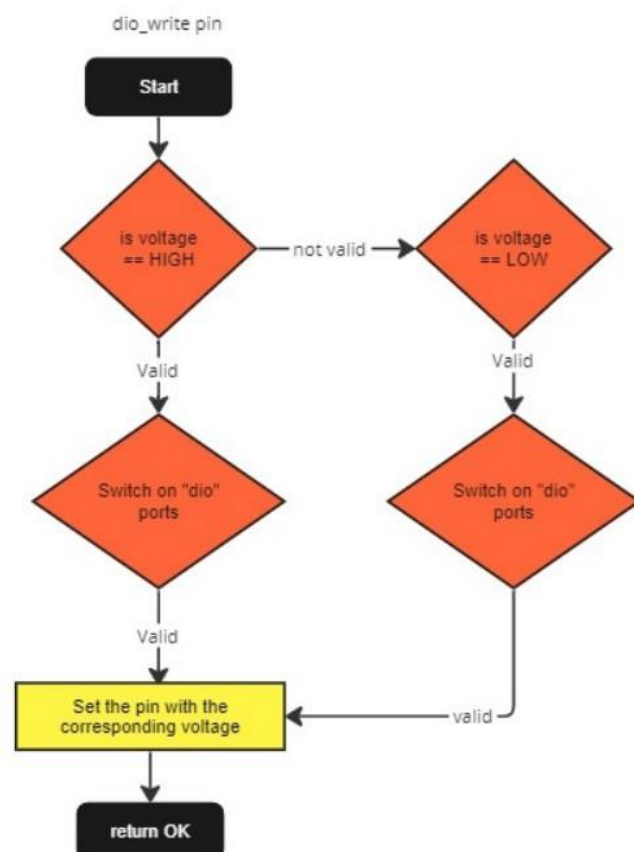
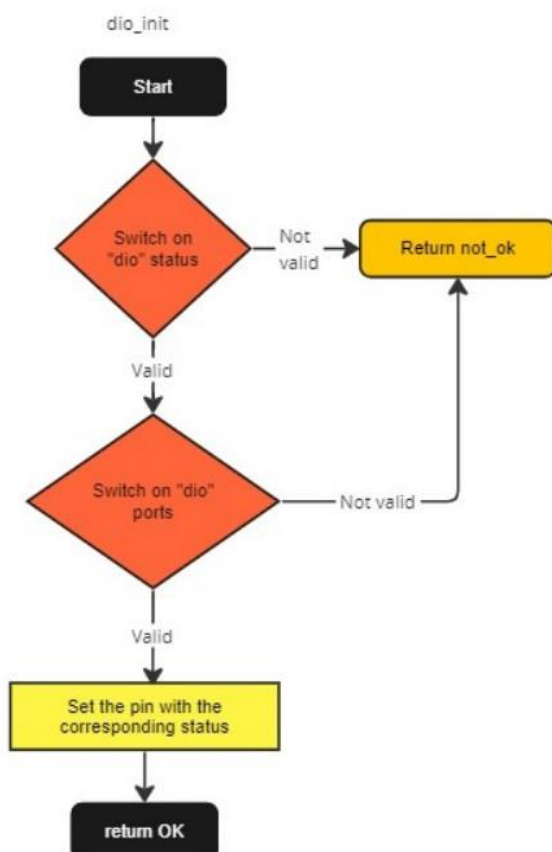
```
void Motors_init(void);  
void Motors_Start(void);  
void Motors_Rotating(void);  
void Motors_Stop(void);
```

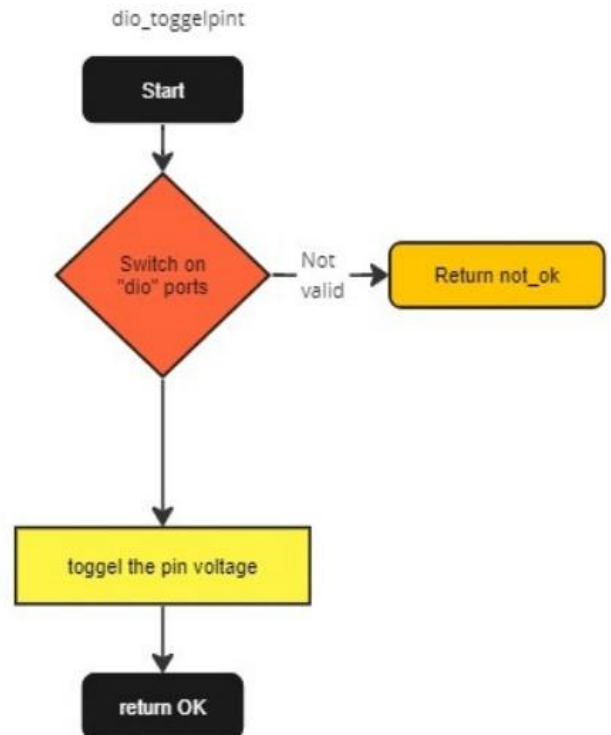
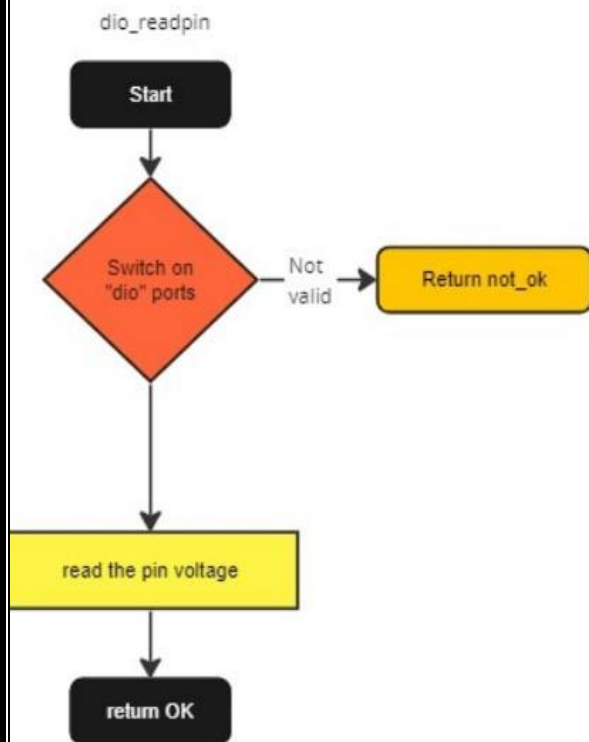
3. Low Level Design:

a. Flow Charts :

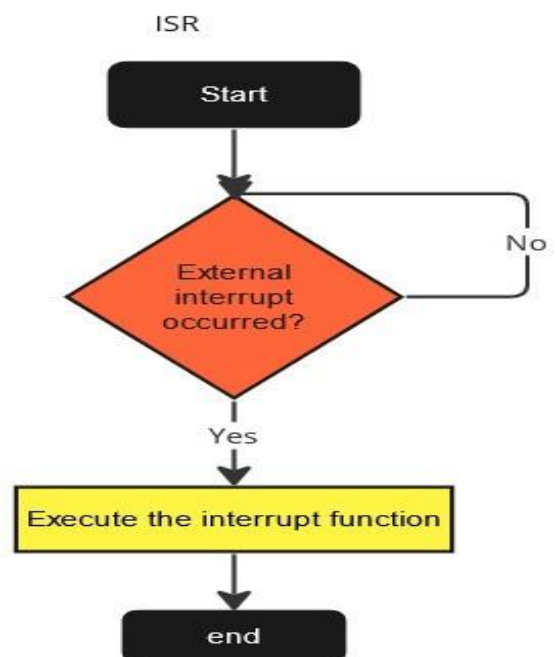
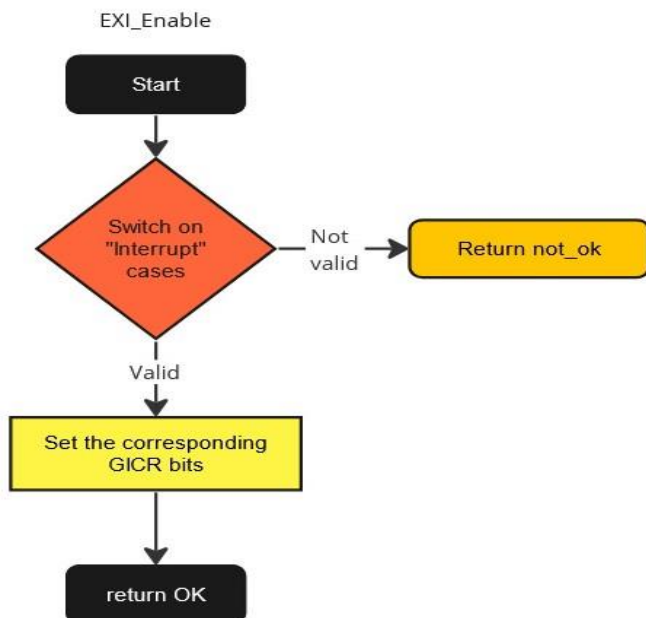
1. MCAL Layer:

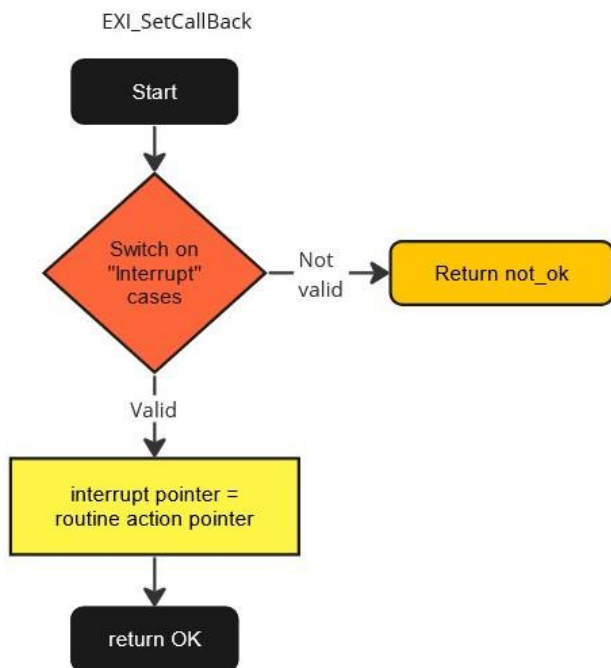
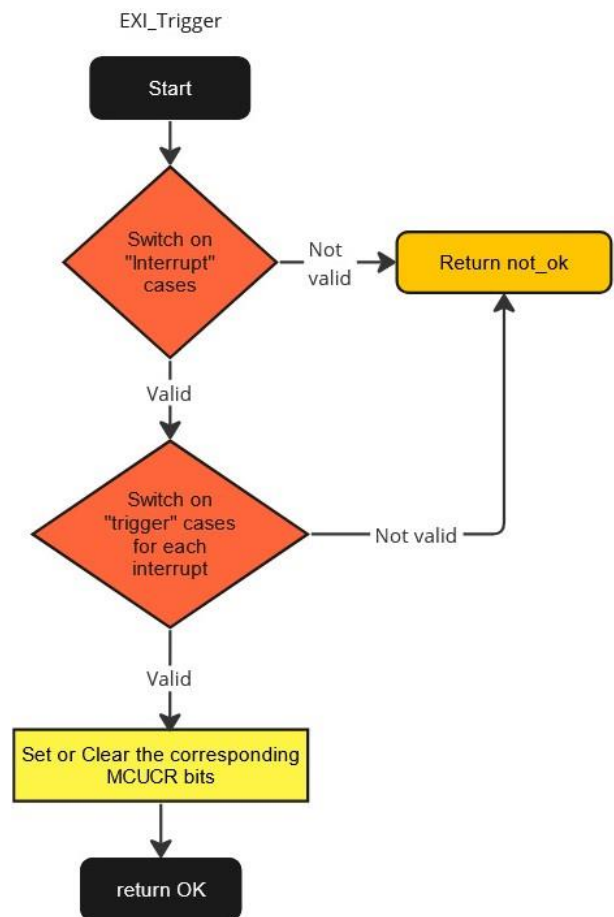
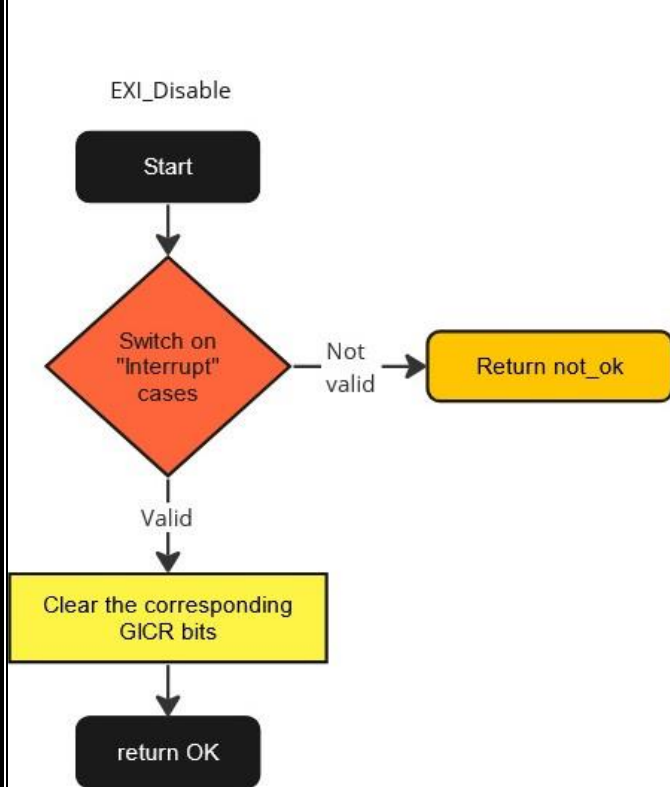
i. DIO Functions:



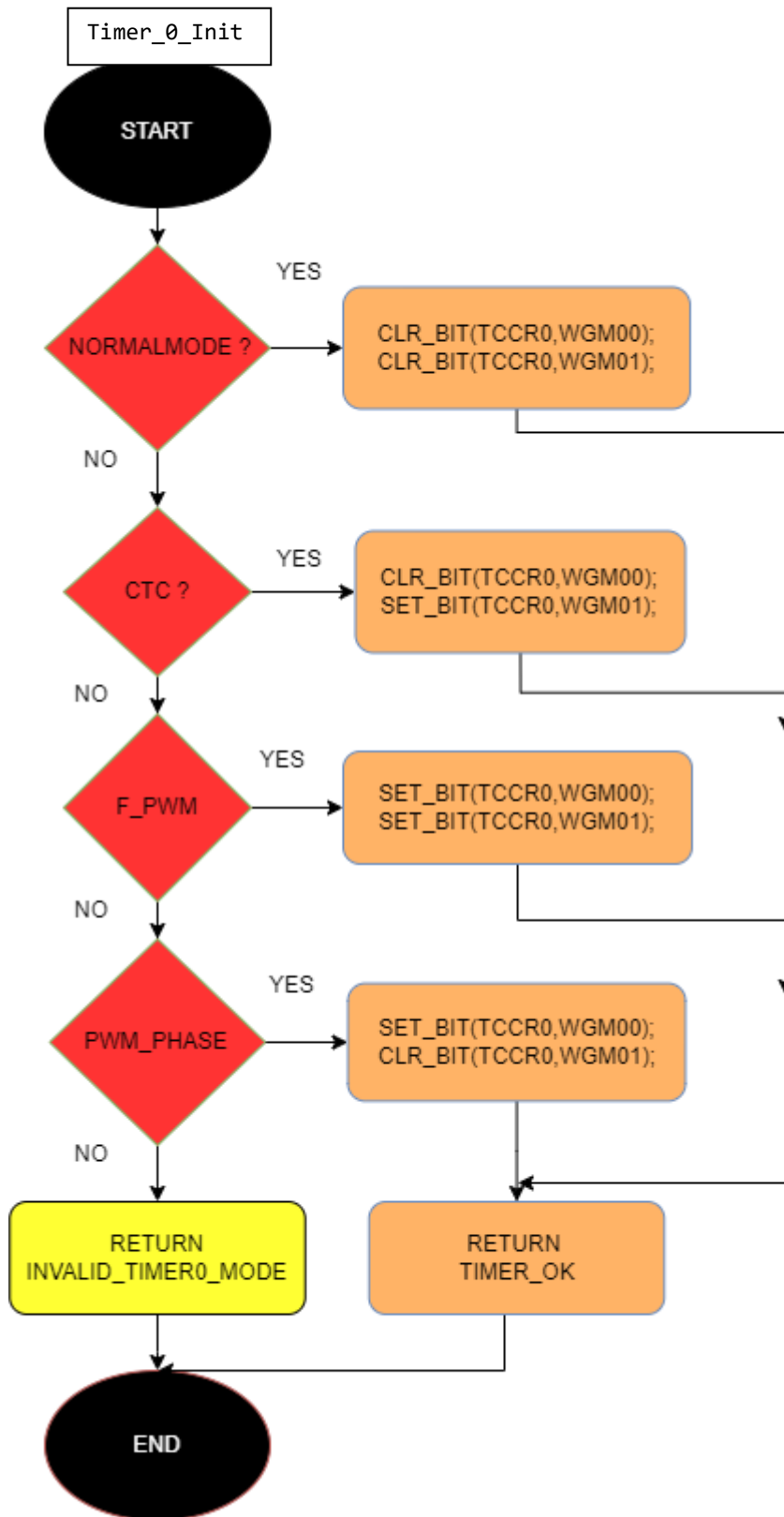


ii. External Interrupt Functions

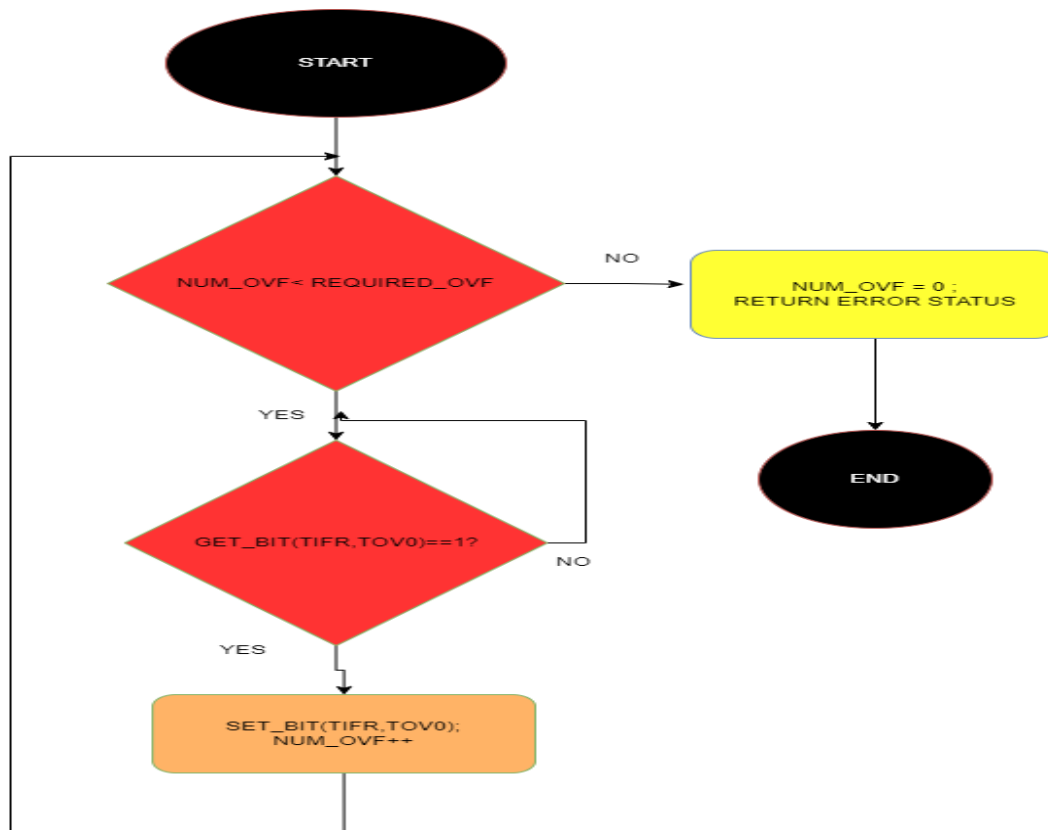




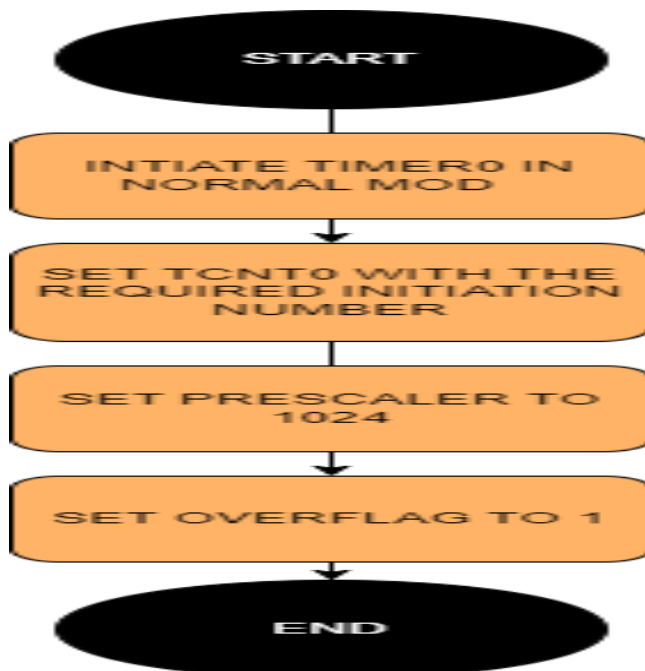
iii. Timers Function



Timer_0_OVFNum



Timer_0_PWM

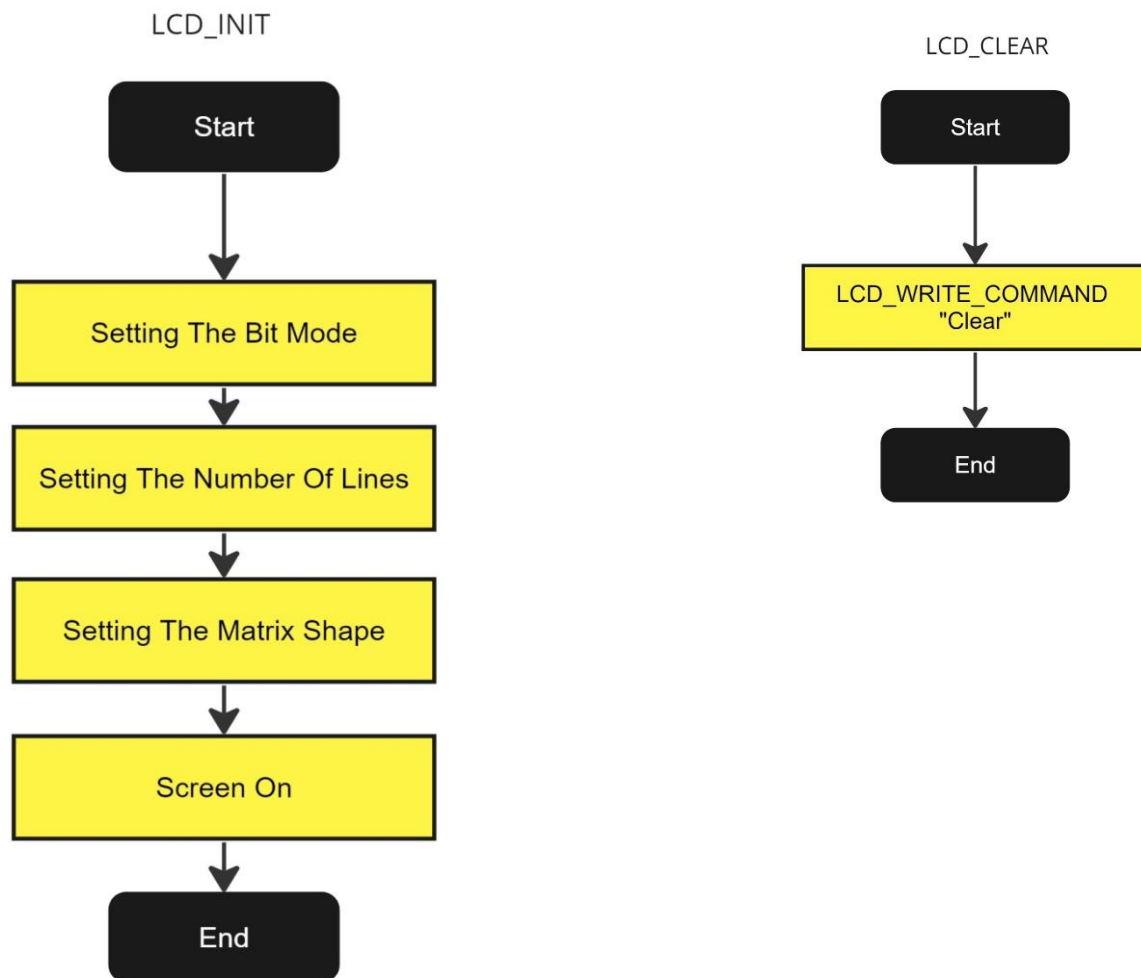


Timer_0_Start

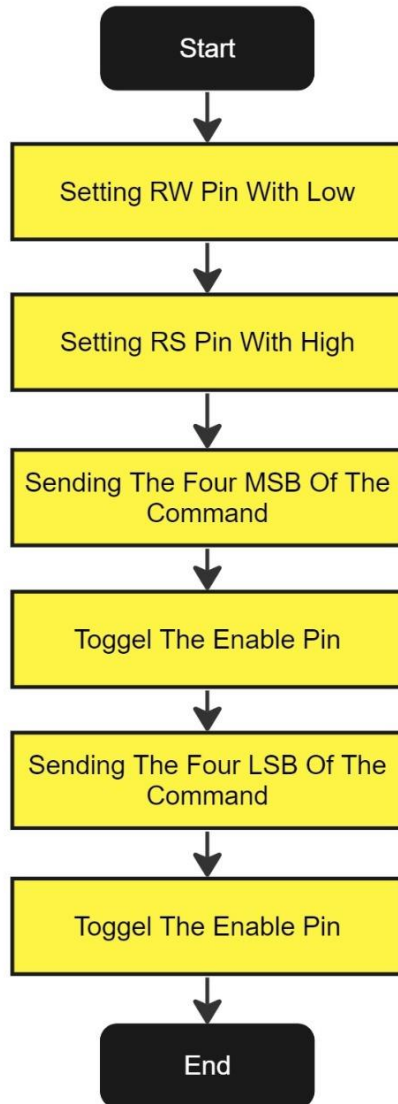


2. HAL Layer:

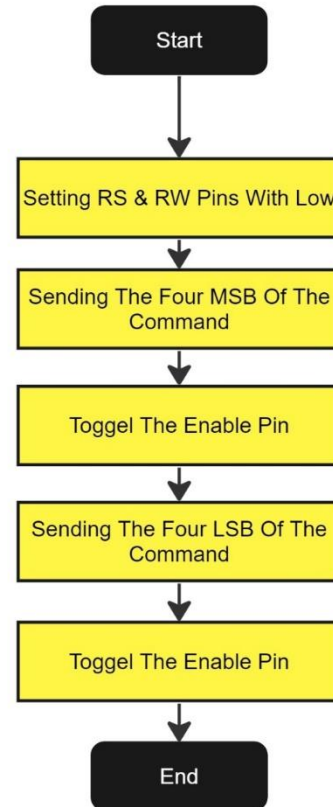
i. LCD Functions:



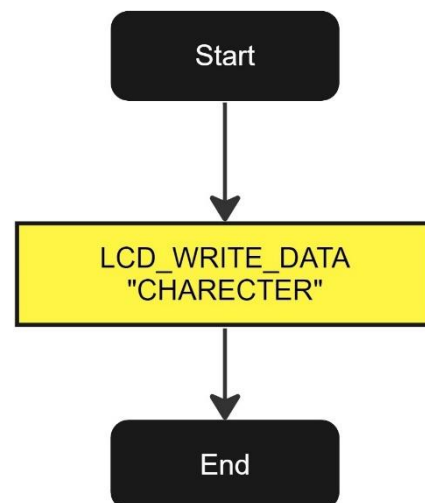
LCD_WRITE_DATA



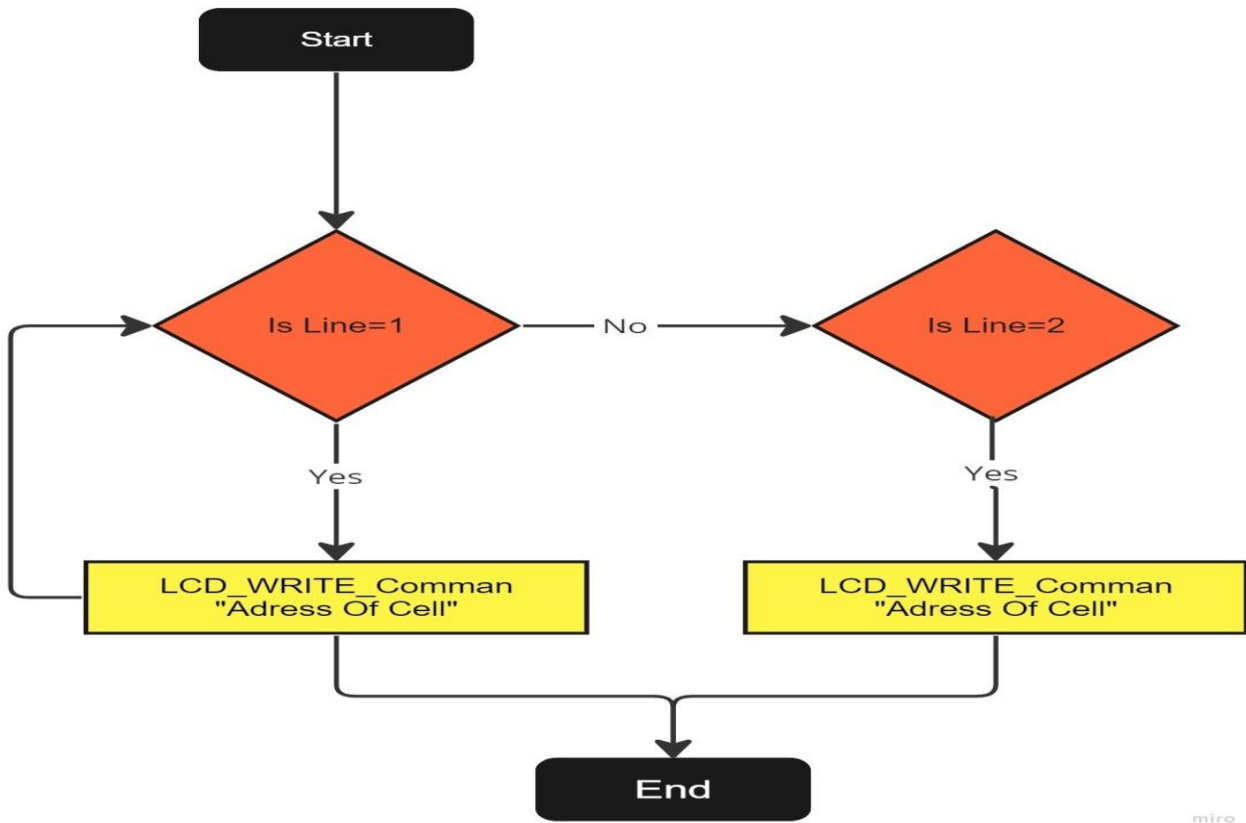
LCD_WRITE_COMMAND



LCD_Write_Charecter

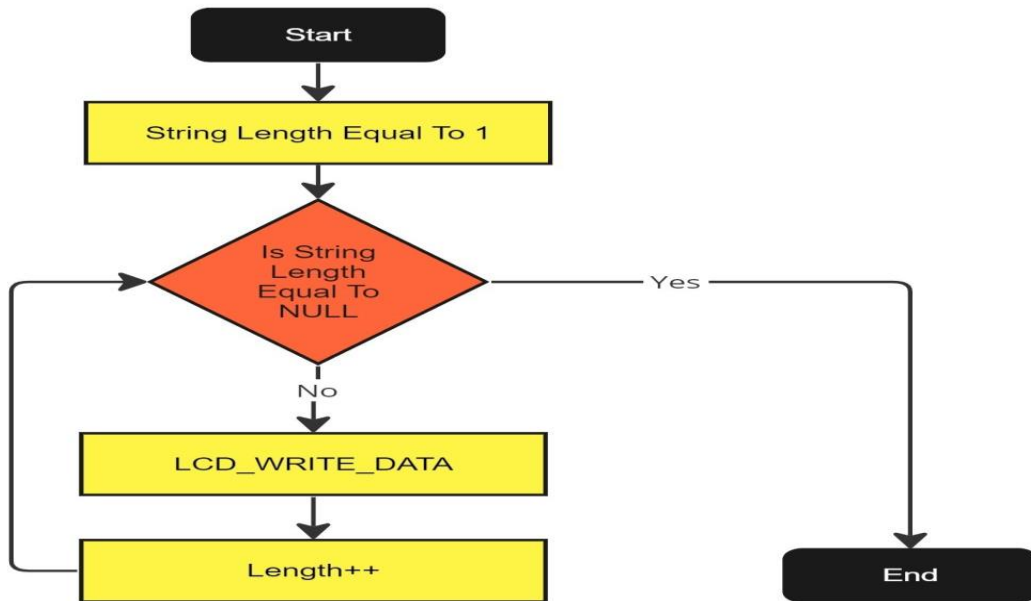


LCD_GoTo



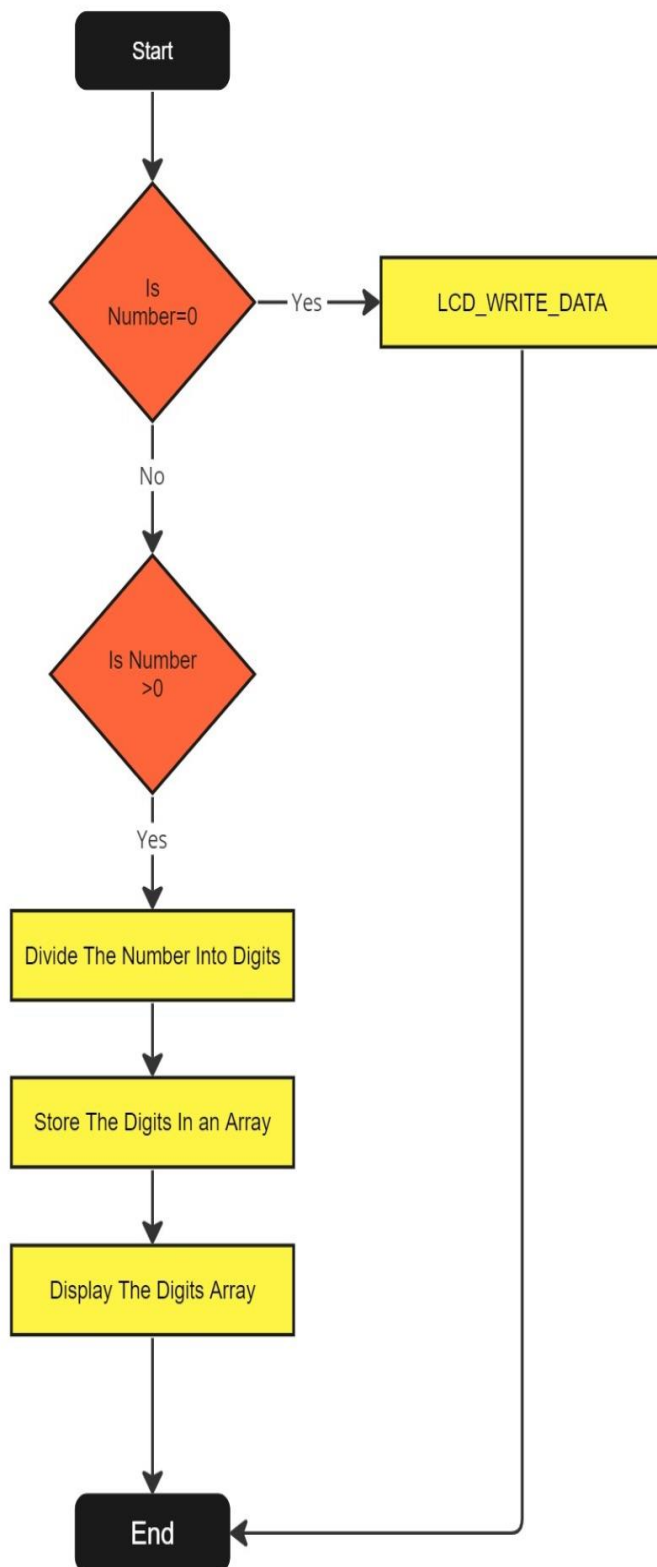
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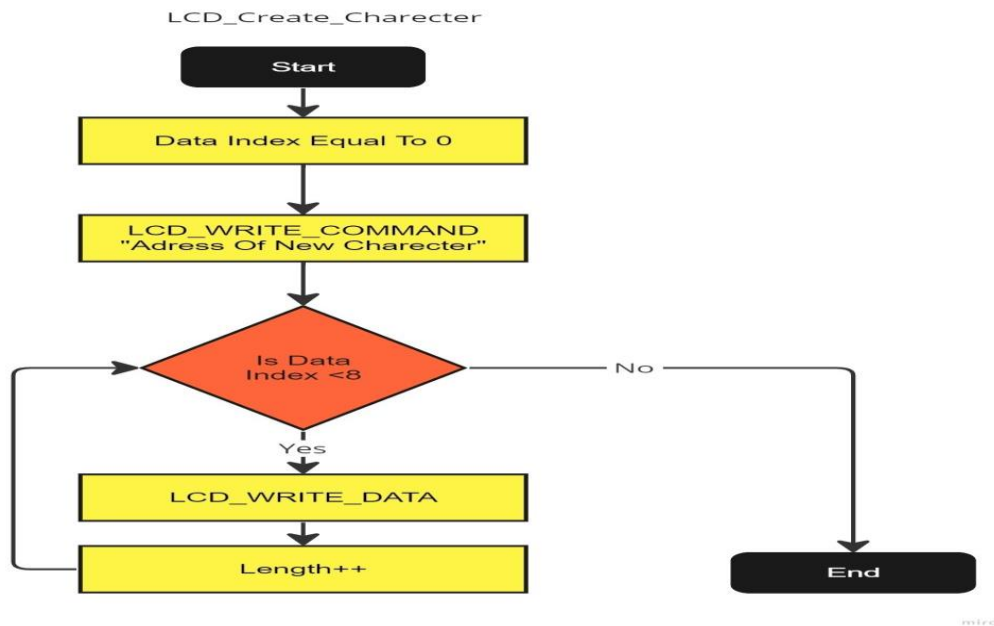
LCD_Write_String



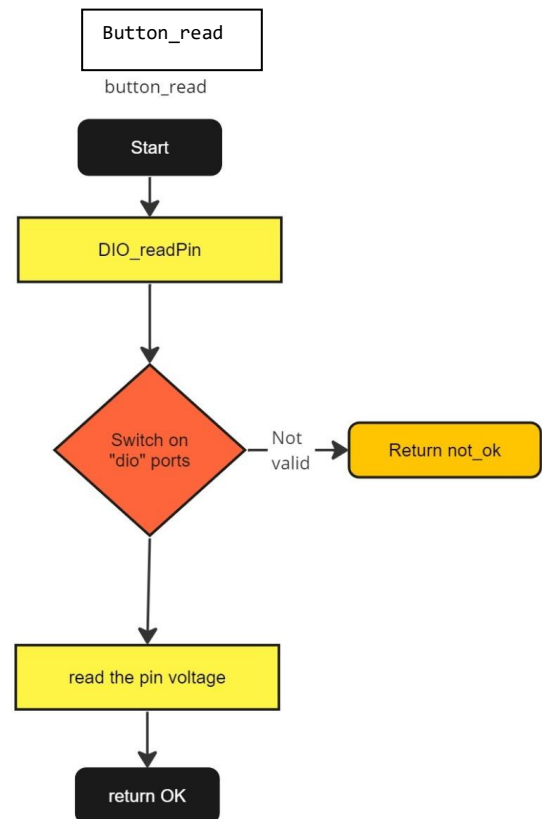
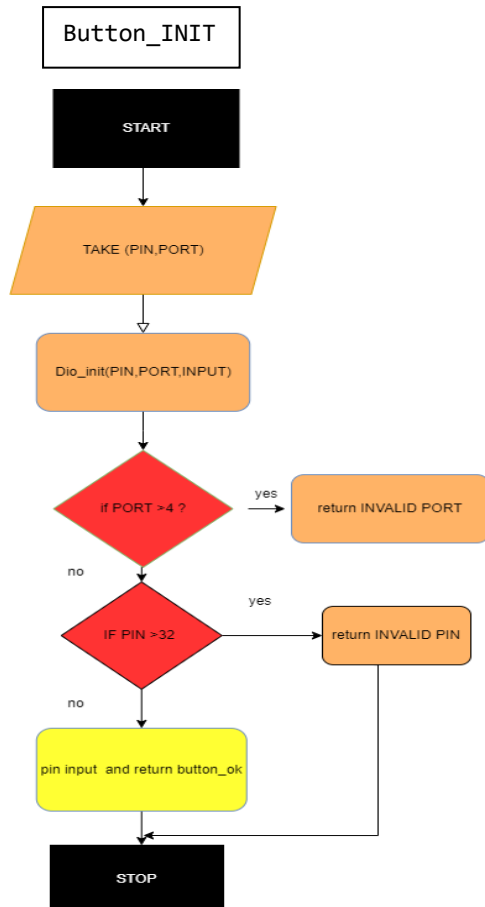
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LCD_WRITE_NUMBER

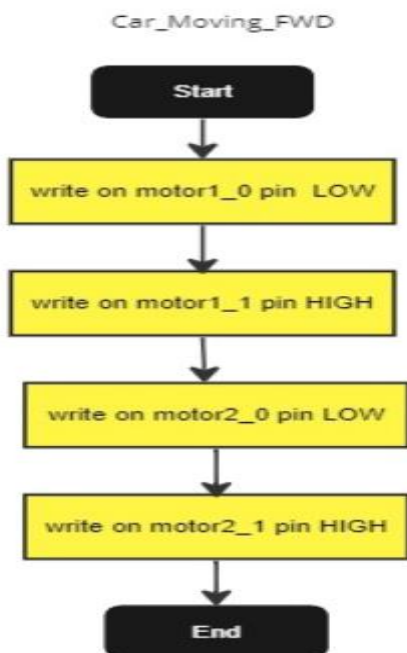
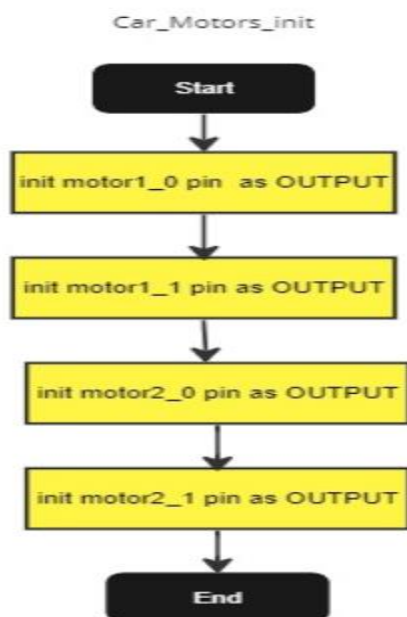




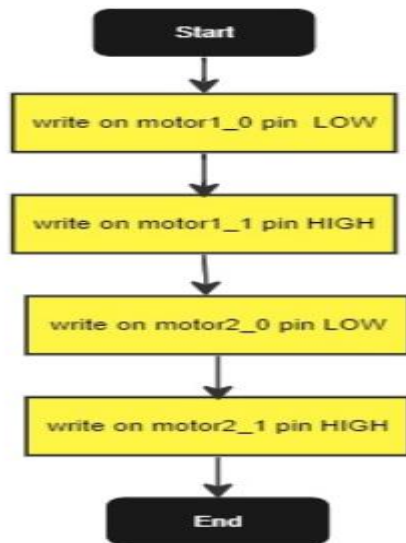
ii. Button Functions:



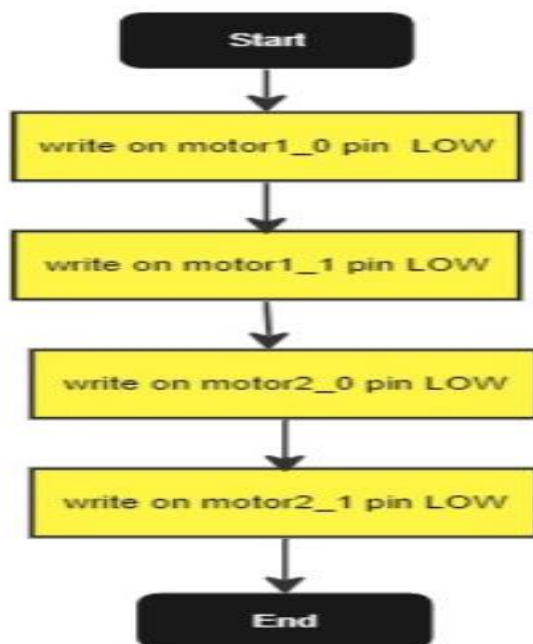
iii. Motor Functions:



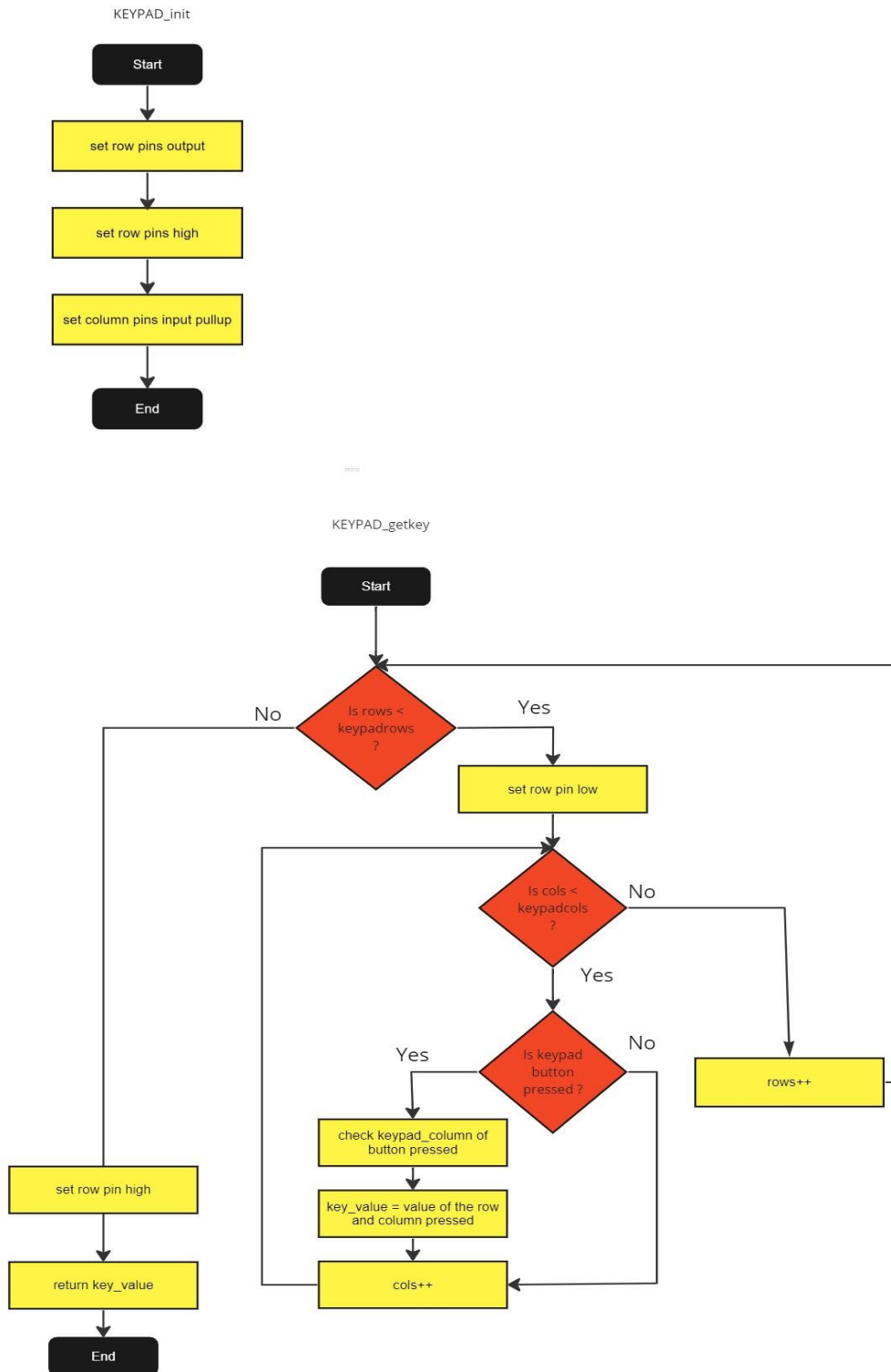
Car_Rotating



Car_Stop



iv. Key Pad Functions:



b.Configurations:-

i. Dio:

```
typedef enum
{
    PINA0=0,
    PINA1,
    PINA2,
    PINA3,
    PINA4,
    PINA5,
    PINA6,
    PINA7,
    PINB0,
    PINB1,
    PINB2,
    PINB3,
    PINB4,
    PINB5,
    PINB6,
    PINB7,
    PINC0,
    PINC1,
    PINC2,
    PINC3,
    PINC4,
    PINC5,
    PINC6,
    PINC7,
    PIND0,
    PIND1,
    PIND2,
    PIND3,
    PIND4,
    PIND5,
    PIND6,
    PIND7,
    TOTAL_PINS=32
}DIO_pinType;

typedef enum
{
    OUTPUT=0,
    INPLUP,
    INFREE
}DIO_PinStatus_Type;
```

```
typedef enum
{
    OUTPUT=0,
    INPLUP,
    INFREE
}DIO_PinStatus_Type;

typedef enum
{
    LOW=0,
    HIGH
}DIO_VoltType;

typedef enum
{
    PA=0,
    PB,
    PC,
    PD
}DIO_PortType;

void DIO_InitPin(DIO_pinType pin,DIO_PinStatus_Type status
void DIO_WritePin(DIO_pinType pin,DIO_VoltType volt);
DIO_VoltType DIO_ReadPin(DIO_pinType pin);
void DIO_TogglePin(DIO_pinType pin);
void DIO_WritePort(DIO_PortType port ,u8 data);
u8 DIO_ReadPort(DIO_PortType port);
extern const DIO_PinStatus_Type PinsStatusArray[TOTAL_PINS
void DIO_Init(void);

#endif /* DIO_H_ */
```

```

const DIO_PinStatus_Type PinsStatusArray[TOTAL_PINS]=
{
    OUTPUT,    /* PINA0 - ADC0 */
    OUTPUT,    /* PINA1 - ADC1 */
    OUTPUT,    /* PINA2 - ADC2 */
    OUTPUT,    /* PINA3 - ADC3 */
    OUTPUT,    /* PINA4 - ADC4 */
    OUTPUT,    /* PINA5 - ADC5 */
    OUTPUT,    /* PINA6 - ADC6 */
    OUTPUT,    /* PINA7 - ADC7 */
    OUTPUT,    /* PINB0 -      */
    OUTPUT,    /* PINB1 -      */
    OUTPUT,    /* PINB2 - INT2 */
    OUTPUT,    /* PINB3 - OC0  */
    OUTPUT,    /* PINB4 - SS   */
    INPLUP,    /* PINB5 - MOSI */
    INPLUP,    /* PINB6 - MISO */
    OUTPUT,    /* PINB7 - SCK  */
    OUTPUT,    /* PINC0 -      */
    OUTPUT,    /* PINC1 -      */
    OUTPUT,    /* PINC2 -      */
    OUTPUT,    /* PINC3 -      */
    OUTPUT,    /* PINC4 -      */
    OUTPUT,    /* PINC5 -      */
    INFREE,    /* PINC6 -      */
    OUTPUT,    /* PINC7 -      */
    OUTPUT,    /* PIND0 - RX   */
    OUTPUT,    /* PIND1 - TX   */
    OUTPUT,    /* PIND2 - INT0 */
    OUTPUT,    /* PIND3 - INT1 */
    OUTPUT,    /* PIND4 - OC1B */
    OUTPUT,    /* PIND5 - OC1A */
    INFREE,    /* PIND6 - ICP1 */
    OUTPUT,    /* PIND7 - OC2  */
};

```

ii. EX Interrupt:

```
typedef enum
{
    EX_INT0=0,
    EX_INT1,
    EX_INT2
} EXInterruptSource_type ;

typedef enum
{
    LOW_LEVEL0=0,
    ANY_LOGIC_CHANGE,
    FALLING_EDGE,
    RISING_EDGE
} TriggerEdge_type ;

typedef struct
{
    EXInterruptSource_type EX_INT0;
    TriggerEdge_type      ANY_LOGIC_CHANGE;
} ST_EXI_Config ;
```

iii. Timers:

```
/* Timer0 */
typedef enum
{
    TIMER0_NORMAL_MODE=0,
    TIMER0_PHASE_CORRECT_MODE,
    TIMER0_CTC_MODE,
    TIMER0_FASTPWM_MODE
}Timer0Mode_type;

typedef enum
{
    TIMER0_STOP=0,
    TIMER0_SCALER_1,
    TIMER0_SCALER_8,
    TIMER0_SCALER_64,
    TIMER0_SCALER_256,
    TIMER0_SCALER_1024,
    TIMER0_EXTERNAL_FALLING,
    TIMER0_EXTERNAL_RISING
}Timer0SCALER_type;

typedef enum
{
    OC0_DISCONNECTED=0,
    OC0_TOGGLE,
    OC0_NON_INVERTING,
    OC0_INVERTING
}OC0Mode_type;

typedef struct
{
    Timer0Mode_type          TIMER0_NORMAL_MODE;
    Timer0SCALER_type        TIMER0_SCALER_8;
    OC0Mode_type             OC0_DISCONNECTED
}ST_Timer_Config;
```

iv. LCD:

```
/****** config******/
#define _4_bit_mode 0
#define _8_bit_mode 1
#define LCD_Mode _4_bit_mode

#define LCD_PORT PC

#define D4 pinc0
#define D5 pinc1
#define D6 pinc2
#define D7 pinc3

#define RS pinc6
#define RW pinc5
#define EN pinc4

/*******/
/*****
PROTOTYPES
*****/

void LCD_WRITE_COMMAND(uint8_t a_COMMAND);
void LCD_WRITE_DATA(uint8_t a_DATA);

void LCD_INIT(void);
void LCD_Write_String(uint8_t*a_String);
void LCD_Write_Number(uint32_t a_number);
void LCD_Clear(void);
void LCD_GoTo(uint8_t a_line,uint8_t a_cell);
void LCD_Write_Charecter(uint8_t a_char);
void LCD_Create_Charecter(uint8_t*a_Pattern,uint8_t a_Address);
/*****
#endif /* LCD_H_ */
```

```
#if (LCD_Mode==_8_bit_mode)
/*****
8_bit_mode
*****/
/*DESCRIPTION:-
This Function Send a Command To The LCD MicroController To Be Executed
*/
void LCD_WRITE_COMMAND(uint8_t a_COMMAND)
{
    DIO_WRITEPIN(RS,LOW);
    DIO_WRITEPIN(RW,LOW);
    DIO_WritePort(LCD_PORT,a_COMMAND);
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
}

/*****
/*DESCRIPTION:-
This Function Send Data To The LCD MicroController To Be displayed
*/
void LCD_WRITE_DATA(uint8_t a_DATA)
{
    DIO_WRITEPIN(RS,HIGH);
    DIO_WRITEPIN(RW,LOW);
    DIO_WritePort(LCD_PORT,a_DATA);
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
}

/*****
/*DESCRIPTION:-
This Function Initializes The LCD With the required Configuration
*/
void LCD_INIT(void)
{
    _delay_ms(50);

    LCD_WRITE_COMMAND(0x38); /* THIS IS FOR UNCTION SET IN THE DATA SHEET 8BIT MODE, 2LINE, 5*7*/
    _delay_ms(1);
    LCD_WRITE_COMMAND(0x0c); /*SCREEN ON, CURSOR OFF*/
    _delay_ms(1);
    LCD_WRITE_COMMAND(0x01); /*CLEAR SCREEN*/
    _delay_ms(2);
    LCD_WRITE_COMMAND(0x06);
    _delay_ms(1);
}
```

```

    #elif (LCD_Mode==_4_bit_mode)

    /*****
        4_bit_mode
    *****/

void LCD_WRITE_COMMAND(uint8_t a_COMMAND)
{
    DIO_WRITEPIN(RS,LOW);
    DIO_WRITEPIN(RW,LOW);
    /**for the 4 most significant bits**/
    DIO_WRITEPIN(D4,read_bit(a_COMMAND,4));
    DIO_WRITEPIN(D5,read_bit(a_COMMAND,5));
    DIO_WRITEPIN(D6,read_bit(a_COMMAND,6));
    DIO_WRITEPIN(D7,read_bit(a_COMMAND,7));
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
    /**for the 4 least significant bits**/
    DIO_WRITEPIN(D4,read_bit(a_COMMAND,0));
    DIO_WRITEPIN(D5,read_bit(a_COMMAND,1));
    DIO_WRITEPIN(D6,read_bit(a_COMMAND,2));
    DIO_WRITEPIN(D7,read_bit(a_COMMAND,3));
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
}

/*****/

void LCD_WRITE_DATA(uint8_t a_DATA)
{
    DIO_WRITEPIN(RS,HIGH);
    DIO_WRITEPIN(RW,LOW);
    /**for the 4 most significant bits**/
    DIO_WRITEPIN(D4,read_bit(a_DATA,4));
    DIO_WRITEPIN(D5,read_bit(a_DATA,5));
    DIO_WRITEPIN(D6,read_bit(a_DATA,6));
    DIO_WRITEPIN(D7,read_bit(a_DATA,7));
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
    /**for the 4 least significant bits**/
    DIO_WRITEPIN(D4,read_bit(a_DATA,0));
    DIO_WRITEPIN(D5,read_bit(a_DATA,1));
    DIO_WRITEPIN(D6,read_bit(a_DATA,2));
    DIO_WRITEPIN(D7,read_bit(a_DATA,3));
    DIO_WRITEPIN(EN,HIGH);
    _delay_ms(1);
    DIO_WRITEPIN(EN,LOW);
    _delay_ms(1);
}

/*****/

```