

Goals:

In this lab you will explore the behavior of a DC motor being driven by Pulse Width Modulation (PWM) using a Drive-Brake mode. You will also gain experience implementing closed loop speed control of the DC motor.

Part 1: Driving a DC Motor Using PWM

- 1.1) To get the best performance out of the motor, it is useful to know the electrical time constant. For minimum current ripple, you will want to set the PWM frequency to at least a frequency of one over the electrical time constant. Implement the necessary software to help you to measure the electrical time constant of the motor on the lab bench. What is the time constant?
- 1.2) Implement your DC motor driver design from Part 0.1 and Event Driven software design to read the A/D converter connected to the potentiometer and adjust the speed. Hook it up to the motor and get the motor to run with the speed controlled by the potentiometer and the direction set by the digital input pin. Set the PWM frequency based on the time constant that you determined in part 1.1
- 1.3) Map the Duty Cycle vs RPM transfer function for the motor/driver combination. Create a graph to visualize the data.
- 1.4) Demonstrate your working software to a TA/Karl and get signed off on the check-out sheet.

In the report:

Include

- The schematic diagram of the circuit you used, design calculations confirming the suitability of all components used. Be sure to indicate on the schematic which bits of which ports of the PIC32 you used, and please include pin numbers.
- A description of your measurement technique and results from your time constant measurement in Part 1.1,
- A graph of the DC vs. Speed data from Part 1.3.
- A Highlighted version of the source code to the program.
- Be sure to be signed-off by a TA.

Circuit diagram included as a separate pdf.

Design calculation's part 1 attached as a separate pdf,

Design calculation's part 2

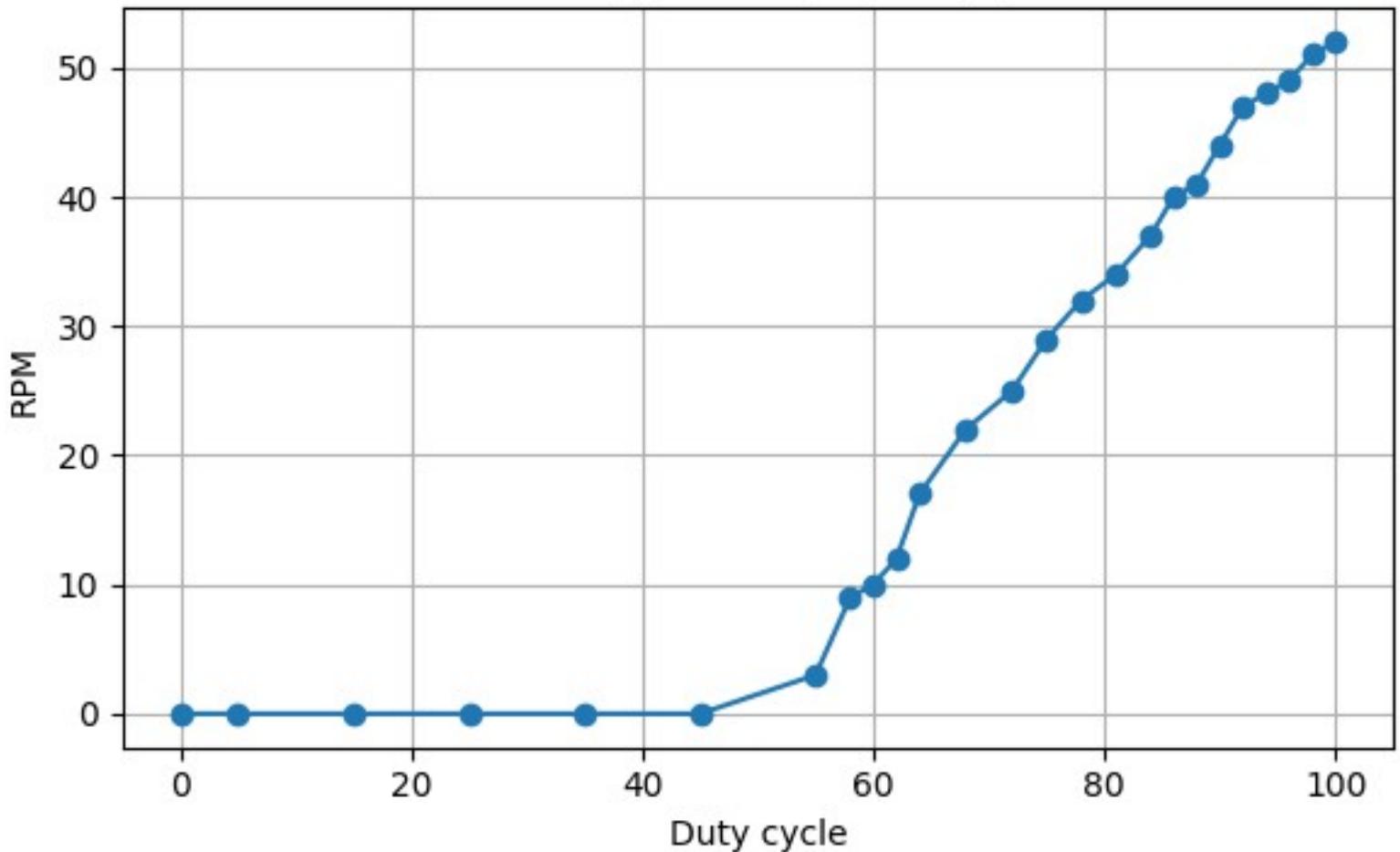
Maximum current drawn by the motor is the current at stall, which is $5/12.45 = 0.401$ Ampere

H bridge has a maximum current output rating of 1 A so it will be able to drive the motor

Table of which bits and which ports is located in the Kicad

Description of measurement technique and time constant values attached as a separate document

RPM (y) vs Duty cycle (x)



Source code to the programs in part 1

```
*****
Module
TimeConstantService.c

Revision
1.0.2

Description
This service generates a square wave on RA2 (pin 10) to help measure
the motor's electrical time constant.

Notes
- Controls:
  't' - Start toggling
  's' - Stop toggling

History
When      Who      What/Why
-----  -----
01/28/2026  karthi24  Started coding service to find time constant
01/16/12 09:58 jec    began conversion from TemplateFSM.c
*****/
----- Include Files -----
/* include header files for this state machine as well as any machines at the
next lower level in the hierarchy that are sub-machines to this machine
*/
#include "ES_Configure.h"
#include "ES_Framework.h"
#include "TimeConstantService.h"
#include "dbprintf.h"

----- Module Defines -----
// Pin definitions for RA2 (pin 10)
#define SQUARE_WAVE_TRIS    TRISAbits.TRISA2
#define SQUARE_WAVE_LAT     LATAbits.LATA2

// Timer settings
#define INITIAL_HALF_PERIOD_MS 500      // Start with 100ms half-period (5 Hz square wave)

----- Module Functions -----
/* prototypes for private functions for this service. They should be functions
relevant to the behavior of this service
*/

----- Module Variables -----
// with the introduction of Gen2, we need a module level Priority variable
static uint8_t MyPriority;
// States for the state machine
typedef enum {
    IDLE,
    TOGGLING
} ServiceState_t;

static ServiceState_t CurrentState;
static uint8_t PinState;
static uint16_t HalfPeriodMS;

----- Module Code -----
*****
```

Function**InitTimeConstantService****Parameters**

uint8_t : the priority of this service

Returns

bool, false if error in initialization, true otherwise

Description

Saves away the priority, and does any
other required initialization for this service

Notes**Author**

J. Edward Carryer, 01/16/12, 10:00

```
*****
bool InitTimeConstantService(uint8_t Priority)
{
    ES_Event_t ThisEvent;

    MyPriority = Priority;
    // in here you write your initialization code
    // ****
    CurrentState = IDLE;
    PinState = 0;
    HalfPeriodMS = INITIAL_HALF_PERIOD_MS;

    // Configure RA2 as digital output
    SQUARE_WAVE_TRIS = 0;      // Set as output
    SQUARE_WAVE_LAT = 0;        // Initialize low

    DB_printf("\r\n==== Time Constant Measurement Service ===\r\n");
    DB_printf("Commands:\r\n");
    DB_printf("  't' - Start square wave\r\n");
    DB_printf("  's' - Stop square wave\r\n");
    DB_printf("Current half-period: %d ms (%.1f Hz)\r\n",
              HalfPeriodMS, 1000.0 / (2.0 * HalfPeriodMS));
    DB_printf("=====*\r\n\r\n");

    // post the initial transition event
    ThisEvent.EventType = ES_INIT;
    if (ES_PostToService(MyPriority, ThisEvent) == true)
    {
        return true;
    }
    else
    {
        return false;
    }
}
```

```
*****
Function
PostTimeConstantService

Parameters
EF_Event_t ThisEvent ,the event to post to the queue
```

Returns

```
    bool false if the Enqueue operation failed, true otherwise
```

Description

```
    Posts an event to this state machine's queue
```

Notes**Author**

```
    J. Edward Carryer, 10/23/11, 19:25
```

```
*****
bool PostTimeConstantService(ES_Event_t ThisEvent)
{
    return ES_PostToService(MyPriority, ThisEvent);
}
```

```
*****
Function
    RunTimeConstantService
```

Parameters

```
    ES_Event_t : the event to process
```

Returns

```
    ES_Event, ES_NO_EVENT if no error ES_ERROR otherwise
```

Description

```
    Implements the state machine for square wave generation
```

Notes**Author**

```
    J. Edward Carryer, 01/15/12, 15:23
```

```
*****
ES_Event_t RunTimeConstantService(ES_Event_t ThisEvent)
{
    ES_Event_t ReturnEvent;
    ReturnEvent.EventType = ES_NO_EVENT; // assume no errors
}*****
```

```
    in here you write your service code
*****
```

```
switch (CurrentState){
    case IDLE:
        if (ThisEvent.EventType == ES_NEW_KEY)
        {
            char key = (char)ThisEvent.EventParam;

            if (key == 't' || key == 'T')
            {
                // Start toggling
                DB_printf("Starting square wave...\r\n");

                // Set pin high and start timer
                PinState = 1;
                SQUARE_WAVE_LAT = 1;
                ES_Timer_InitTimer(TIME_CONST_TIMER, HalfPeriodMS);

                CurrentState = TOGLGING;
            }
        }
}
```

```

break;

case TOGLLING:
    if (ThisEvent.EventType == ES_TIMEOUT &&
        ThisEvent.EventParam == TIME_CONST_TIMER)
    {
        // Toggle the pin
        if (PinState == 1)
        {
            PinState = 0;
            SQUARE_WAVE_LAT = 0;
        }
        else
        {
            PinState = 1;
            SQUARE_WAVE_LAT = 1;
        }

        // Restart timer for next toggle
        ES_Timer_InitTimer(TIME_CONST_TIMER, HalfPeriodMS);
    }
    else if (ThisEvent.EventType == ES_NEW_KEY)
    {
        char key = (char)ThisEvent.EventParam;

        if (key == 's' || key == 'S')
        {
            // Stop toggling
            DB_printf("Stopping square wave.\r\n");

            // Set pin low and stop timer
            SQUARE_WAVE_LAT = 0;
            PinState = 0;
            ES_Timer_StopTimer(TIME_CONST_TIMER);

            CurrentState = IDLE;
        }
    }
    break;
}
return ReturnEvent;
}

/*****************
private functions
*****************/
/*----- Footnotes -----*/
/*----- End of file -----*/

```

```
*****
Module
TemplateService.c

Revision
1.0.2

Description
This service implements PWM motor control with encoder feedback for Lab 7
Part 1.

Notes
*
* Drive-Brake Mode:
- Forward: IN 1A = 0, IN 2A = PWM
- Reverse: IN 1A = 1, IN 2A = inverted PWM (use 100% - duty cycle)

History
When      Who      What/Why
-----
01/28/2026  karthi24  started coding up part 1 of lab 7
01/16/12 09:58 jec      began conversion from TemplateFSM.c
*****
```

```
----- Include Files -----
/* include header files for this state machine as well as any machines at the
   next lower level in the hierarchy that are sub-machines to this machine
*/
#include "ES_Configure.h"
#include "ES_Framework.h"
#include "MotorService.h"
#include "PIC32_AD_Lib.h"
#include "dbprintf.h"
#include <xc.h>
#include <sys/attribs.h>
----- Module Defines -----
#define PWM_PRESCALE    0b010      // 1:4 prescaler
#define PWM_PERIOD       1249       // For 4000 Hz PWM

#define IC_TIMER_PRESCALE 0b011     // 1:8 prescaler

#define RPM_NUMERATOR    49656

#define ADC_UPDATE_TIME_MS    100      // 10 Hz ADC reading
#define PRINT_UPDATE_TIME_MS   500      // 2 Hz terminal printing

// Direction Control Pin to the motor driver (RB2, pin 6) - IN 1A
#define DIR_1A_TRIS        TRISBbits.TRISB2
#define DIR_1A_ANSEL        ANSELBbits.ANSB2
#define DIR_1A_LAT          LATBbits.LATB2

// Direction Input Pin changed by user (RA1, pin 3)
#define DIR_INPUT_TRIS      TRISAbits.TRISA1
#define DIR_INPUT_ANSEL      ANSELAbits.ANSA1
#define DIR_INPUT_PORT       PORTAbits.RA1

// PWM Output Pin (RB13, pin 24) - IN 2A via OC4
#define PWM_PIN_TRIS        TRISBbits.TRISB13
#define PWM_PIN_ANSEL        ANSELBbits.ANSB13
----- Module Functions -----
```

```

/* prototypes for private functions for this service. They should be functions
   relevant to the behavior of this service
*/
static void InitPWM(void);
static void InitDirectionPins(void);
static void InitInputCapture(void);
static void SetDutyCycle(uint8_t dutyPercent);

/*----- Module Variables -----*/
// with the introduction of Gen2, we need a module level Priority variable
static uint8_t MyPriority;

// Shared with IC ISR (volatile)
static volatile uint16_t CurrentPeriod = 0;
static volatile uint16_t LastCapture = 0;

static uint8_t CurrentDutyCyclePercent = 0;

/*----- Module Code -----*/
/********************* Function
   InitTemplateService

Parameters
   uint8_t : the priority of this service

Returns
   bool, false if error in initialization, true otherwise

Description
   Saves away the priority, and does any
   other required initialization for this service
Notes

Author
   J. Edward Carryer, 01/16/12, 10:00
*******/
bool InitMotorService(uint8_t Priority)
{
    ES_Event_t ThisEvent;

    MyPriority = Priority;
    /*
     * in here you write your initialization code
     */
    InitDirectionPins();

    ADC_ConfigAutoScan(BIT0HI);

    InitPWM();

    InitInputCapture();

    // Print startup message
    DB_printf("\r\n== Motor Control Service (For part 1) ==\r\n");
    DB_printf("RA1 input controls direction\r\n");
    DB_printf("===== \r\n");
    DB_printf("\r\nDuty%%, RPM\r\n"); // CSV header for data collection
}

```

```

    ES_Timer_InitTimer(MOTOR_ADC_TIMER, ADC_UPDATE_TIME_MS);

    // Start periodic timer for terminal printing (2 Hz)
    ES_Timer_InitTimer(MOTOR_PRINT_TIMER, PRINT_UPDATE_TIME_MS);

    // post the initial transition event
    ThisEvent.EventType = ES_INIT;
    if (ES_PostToService(MyPriority, ThisEvent) == true)
    {
        return true;
    }
    else
    {
        return false;
    }
}

/*****
Function
    PostMotorService

Parameters
    EF_Event_t ThisEvent ,the event to post to the queue

Returns
    bool false if the Enqueue operation failed, true otherwise

Description
    Posts an event to this state machine's queue
Notes

Author
    J. Edward Carryer, 10/23/11, 19:25
*****/

bool PostMotorService(ES_Event_t ThisEvent)
{
    return ES_PostToService(MyPriority, ThisEvent);
}

/*****
Function
    RunTemplateService

Parameters
    ES_Event_t : the event to process

Returns
    ES_Event, ES_NO_EVENT if no error ES_ERROR otherwise

Description
    Handles ADC reading, direction control, and RPM reporting
Notes

Author
    J. Edward Carryer, 01/15/12, 15:23
*****/
ES_Event_t RunMotorService(ES_Event_t ThisEvent)

```

```

{
    ES_Event_t ReturnEvent;
    ReturnEvent.EventType = ES_NO_EVENT; // assume no errors
    //*****
    // in here you write your service code
    //*****
    switch(ThisEvent.EventType){
        case ES_TIMEOUT:
            if (ThisEvent.EventParam == MOTOR_ADC_TIMER)
            {
                // --- Read Potentiometer ---
                uint32_t adcResult[1];
                ADC_MultiRead(adcResult);

                // Calculate duty cycle percentage (0-100)
                CurrentDutyCyclePercent = (adcResult[0] * 100) / 1023;

                // --- Read Direction Input ---
                uint8_t directionInput = DIR_INPUT_PORT;

                // --- Apply Direction and Duty Cycle ---
                if (directionInput == 0) // Forward
                {
                    DIR_1A_LAT = 0;
                    SetDutyCycle(CurrentDutyCyclePercent);
                }
                else // Reverse
                {
                    DIR_1A_LAT = 1;
                    // Invert duty cycle for Drive-Brake with IN1A = 1
                    SetDutyCycle(100 - CurrentDutyCyclePercent);
                }

                // Restart ADC timer
                ES_Timer_InitTimer(MOTOR_ADC_TIMER, ADC_UPDATE_TIME_MS);
            }
        else if (ThisEvent.EventParam == MOTOR_PRINT_TIMER)
        {
            // --- Calculate and Print RPM ---
            // Safely read volatile period
            __builtin_disable_interrupts();
            uint16_t periodSnapshot = CurrentPeriod;
            __builtin_enable_interrupts();

            if (periodSnapshot > 0)
            {
                uint32_t rpm = RPM_NUMERATOR / periodSnapshot;

                // Print in CSV format for easy data collection
                DB_printf("%d, %d\r\n", CurrentDutyCyclePercent, rpm);
            }
            else
            {
                // Motor stopped or no encoder pulses
                DB_printf("%d, 0\r\n", CurrentDutyCyclePercent);
            }

            // Restart print timer
            ES_Timer_InitTimer(MOTOR_PRINT_TIMER, PRINT_UPDATE_TIME_MS);
        }
    }
}

```

```

        }
        break;
    }
    return ReturnEvent;
}

/********************* ISR: Input Capture 2 *********************/
void __ISR(_INPUT_CAPTURE_2_VECTOR, IPL6AUTO) IC2_ISR(void)
{
    uint16_t ThisCapture;

    // Drain the FIFO - read all buffered captures, keep only the last one
    while (IC2CONbits.ICYNE)
    {
        ThisCapture = IC2BUF;
    }

    // Calculate period (unsigned subtraction handles 16-bit rollover)
    CurrentPeriod = ThisCapture - LastCapture;

    // Save for next edge
    LastCapture = ThisCapture;

    // Clear interrupt flag
    IFS0CLR = _IFS0_IC2IF_MASK;
}

/********************* private functions *********************/
/********************* Function ****************************/
Function
    InitPWM

Description
    Initializes Timer2 and OC4 for PWM output on RB13 at 4000 Hz
/********************* static void InitPWM(void) ********************/
{
    // ===== Timer2 Setup =====
    T2CONbits.ON = 0;           // Disable Timer2
    T2CONbits.TCS = 0;          // Select internal PBCLK
    T2CONbits.TCKPS = PWM_PRESCALE; // 1:4 prescaler
    TMR2 = 0;                  // Clear timer register
    PR2 = PWM_PERIOD;          // Set period for 4000 Hz
    // No need to clear interrupt flags since we are not using them
    T2CONbits.ON = 1;          // Enable Timer2

    // ===== OC4 Setup =====
    OC4CONbits.ON = 0;          // Disable OC4 during setup

    // Set initial duty cycle to 0%
    OC4R = 0;
    OC4RS = 0;

    // Disable analog on PWM pin
    PWM_PIN_ANSEL = 0;
}

```

```

// Map OC4 to RB13 (pin 24)
RPB13R = 0b0101;

// Configure OC4 for PWM mode
OC4CONbits.OCTSEL = 0;           // Use Timer2 as clock source
OC4CONbits.OCM = 0b110;          // PWM mode, fault pin disabled

// Enable OC4
OC4CONbits.ON = 1;
}

/*********************************************
Function
    InitDirectionPins

Description
    Initializes the direction control output (RB2) and direction input (RA1)
*****************************************/
static void InitDirectionPins(void)
{
    // --- Direction Control Output (RB2, IN 1A) ---
    DIR_1A_ANSEL = 0;             // Disable analog
    DIR_1A_TRIS = 0;              // Set as output
    DIR_1A_LAT = 0;               // Initialize low (forward direction)

    // --- Direction Input (RA1) ---
    DIR_INPUT_ANSEL = 0;          // Disable analog
    DIR_INPUT_TRIS = 1;            // Set as input
}

/*********************************************
Function
    InitInputCapture

Description
    Initializes Timer3 (maximum period) and IC2 for encoder period measurement
*****************************************/
static void InitInputCapture(void)
{
    // ===== Timer3 Setup (free-running for Input Capture) =====
    T3CONbits.ON = 0;              // Disable Timer3
    T3CONbits.TCS = 0;              // Select internal PBCLK
    T3CONbits.TCKPS = IC_TIMER_PRESCALE; // 1:8 prescaler
    TMR3 = 0;                      // Clear timer register
    PR3 = 0xFFFF;                  // Max period
    IFS0CLR = _IFS0_T3IF_MASK;     // Clear Timer3 interrupt flag
    T3CONbits.ON = 1;               // Enable Timer3

    // ===== Input Capture 2 Setup =====
    // Map IC2 input to RB9 (pin 18)
    IC2R = 0b0100;

    // Disable IC2 during setup
    IC2CONbits.ON = 0;

    // Configure IC2
    IC2CONbits.ICTMR = 0;          // Use Timer3 (ICTMR=0 means Timer3)
    IC2CONbits.ICI = 0b00;          // Interrupt on every capture event
}

```

```

IC2CONbits.ICM = 0b011; // Capture on every rising edge

// Configure IC2 interrupt
IFS0CLR = _IFS0_IC2IF_MASK; // Clear interrupt flag
IPC2bits.IC2IP = 6; // Priority 6
IPC2bits.IC2IS = 0; // Subpriority 0
IEC0SET = _IEC0_IC2IE_MASK; // Enable IC2 interrupt

// Enable Input Capture module
IC2CONbits.ON = 1;
}

/********************* Function SetDutyCycle *****************/
Parameters
    uint8_t dutyPercent - duty cycle as percentage (0-100)

Description
    Converts percentage to PWM register value and updates OC4RS
/********************* End of Function SetDutyCycle *******/

static void SetDutyCycle(uint8_t dutyPercent)
{
    // Clamp to valid range
    if (dutyPercent > 100)
    {
        dutyPercent = 100;
    }

    // Convert percentage to PWM register value
    // dutyValue = (dutyPercent * PWM_PERIOD) / 100
    uint32_t dutyValue = ((uint32_t)dutyPercent * PWM_PERIOD) / 100;

    // Write to OC4RS (double-buffered, updates on next period match)
    OC4RS = dutyValue;
}

/*----- Footnotes -----*/
/*----- End of file -----*/

```

Part 2: Implementing Closed Loop Speed Control

- 2.1) Using your code from Part 1 as a base, add a periodic interrupt response routine set to fire at 2 ms intervals. In the interrupt response routine, implement a minimal proportional plus integral control law with anti-windup to calculate and program a new duty cycle every 2 ms. Be sure that you structure your code so that it does not cause you to lose an input capture interrupt (hint: make the control law interrupt a lower priority than the encoder interrupt). For calculating your control law, it is OK to use floats.
- 2.2) Tune the gains on your system to provide a quick and stable startup and maintain speed in the presence of an external disturbance (dragging a finger on the wheel attached to the motor). See Appendix B for suggestions on how to gather data to implement Ziegler-Nichols tuning.
- 2.3) Add code to your program that will take the A/D converter input as a speed command.
- 2.4) Explore the ability of the system to maintain a constant speed in the face of disturbances across the speed range.
- 2.5) Add a few instructions to your code from Part 2.4 to raise an I/O line immediately upon entry to the ISR and lower it immediately before exiting. How long did it spend in the ISR? What fraction of the execution time does that represent?
- 2.6) Demonstrate the working system to a TA/Coach/Ed. They will want to see the ability to vary the commanded speed and to maintain that speed in the presence of a disturbance.

In the report:

Include a Highlighted version of the source code to the program that you wrote for Part 2.1 and the measurements from 2.5. Be sure to be signed-off by a coach or TA. This quarter, we will be using Gradescope for your code submissions as well. Look for a Gradescope assignment entitled Lab 7 Code and submit the raw .C files (not Highlighted). Note, you will complete 1 code submission (including the files for all parts) when you submit, so save this step to the last. Please make sure that your files are named such that we can tell which files go with which parts of the lab.

Source code for part 2

```
*****
```

Module

TemplateService.c

Revision

1.0.2

Description

This service implements closed-loop PI speed control of a DC motor. The potentiometer sets the commanded RPM, and a PI controller running at 2ms intervals adjusts the duty cycle to maintain the target speed.

Notes

No more direction control via input pin.

History

When	Who	What/Why
01/29/2026	karthi24	started coding for part 2
01/28/2026	karthi24	started coding up part 1 of lab 7
01/16/12 09:58	jec	began conversion from TemplateFSM.c

```
*****
```

```
----- Include Files -----*/
```

```
/* include header files for this state machine as well as any machines at the
   next lower level in the hierarchy that are sub-machines to this machine
*/
```

```
#include "ES_Configure.h"
#include "ES_Framework.h"
#include "MotorService.h"
#include "PIC32_AD_Lib.h"
#include "dbprintf.h"
#include <xc.h>
#include <sys/attribs.h>
```

```
----- Module Defines -----*/
```

```
#define PWM_PRESCALE      0b010      // 1:4 prescaler
#define PWM_PERIOD         1249       // For 4000 Hz PWM
```

```
#define IC_TIMER_PRESCALE 0b011      // 1:8 prescaler
```

```
// Control Loop Timer Configuration
```

```
// Timer4 with 1:4 prescaler -> 5 MHz tick rate
```

```
#define CONTROL_TIMER_PRESCALE 0b010 // 1:4 prescaler
```

```
#define CONTROL_TIMER_PERIOD 9999    // For 2ms control loop
```

```
#define MAX_COMMANDED_RPM 50 // Used in antiwindup
```

```
#define PER2RPM        49656
```

```
#define ADC_UPDATE_TIME_MS     100      // 10 Hz ADC reading
```

```
#define PRINT_UPDATE_TIME_MS   700      // 1.42 Hz terminal printing
```

```
// (RB2, pin 6) - IN 1A - previously used for direction control. only set once for
unidirectional PI control
```

```
#define DIR_1A_TRIS          TRISBbits.TRISB2
#define DIR_1A_ANSEL          ANSELBbits.ANSB2
#define DIR_1A_LAT             LATBbits.LATB2
```

```

// PWM Output Pin (RB13, pin 24) - IN 2A via OC4
#define PWM_PIN_TRIS      TRISBbits.TRISB13
#define PWM_PIN_ANSEL     ANSELBbits.ANSB13

// Timing Pin (RA2, pin 10) - for ISR timing measurement
#define TIMING_PIN_TRIS   TRISAbits.TRISA2
#define TIMING_PIN_LAT    LATAbits.LATA2
/*----- Module Functions -----*/
/* prototypes for private functions for this service. They should be functions
   relevant to the behavior of this service
*/
static void InitPWM(void);
static void InitDirectionPins(void);
static void InitInputCapture(void);
static void InitControlTimer(void);
static void SetDuty(float dutyPercent);
/*----- Module Variables -----*/
// with the introduction of Gen2, we need a module level Priority variable
static uint8_t MyPriority;

// Shared with IC ISR (volatile)
static volatile uint16_t CurrentPeriod = 0;
static volatile uint16_t LastCapture = 0;

// PI Controller Gains (adjustable via keyboard)
static float pGain = 0.5;           // Proportional gain - start conservative
static float iGain = 0.01;          // Integral gain - start small

// PI Controller State (used by Control ISR)
static volatile float SumError = 0.0;        // Integral accumulator
static volatile float TargetRPM = 0.0;         // Commanded speed from ADC

// For display (updated by Control ISR)
static volatile float CurrentRPM = 0.0;
static volatile float LastRPMError = 0.0;
static volatile float RequestedDuty = 0.0;

/*----- Module Code -----*/
/********************* Function ********************/
Function
  InitTemplateService

Parameters
  uint8_t : the priority of this service

Returns
  bool, false if error in initialization, true otherwise

Description
  Saves away the priority, and does any
  other required initialization for this service

Notes

Author
  J. Edward Carryer, 01/16/12, 10:00
/********************* /
bool InitMotorService(uint8_t Priority)

```

```

{
    ES_Event_t ThisEvent;

    MyPriority = Priority;
    //***** in here you write your initialization code *****
    //***** *****
}

// Initialize the Timing pin
// RA2 does not have an ANSEL register (not analog-capable)
TIMING_PIN_TRIS = 0;           // Set as output
TIMING_PIN_LAT = 0;            // Initialize low

InitDirectionPins();

ADC_ConfigAutoScan(BIT0HI);

InitPWM();

InitInputCapture();

// Initialize control loop timer (Timer4, 2ms)
InitControlTimer();

// Print startup message
DB_printf("\r\n==> Motor Control Service (PI controller with anti-windup)==>\r\n");
DB_printf("Potentiometer sets commanded RPM (0-%d)\r\n", MAX_COMMANDED_RPM);
DB_printf("Initial gains: pGain = %d, iGain = %d\r\n", (int)(100 * pGain), (int)(100 *
iGain));
DB_printf("\r\nKeyboard Controls:\r\n");
DB_printf(" 'P'/'p' - increase/decrease pGain\r\n");
DB_printf(" 'I'/'i' - increase/decrease iGain\r\n");
//   DB_printf(" 'r'      - reset integral term\r\n");
DB_printf(" '?'      - show current gains\r\n");
DB_printf("=====*\r\n");
DB_printf("\r\nTargetRPM, ActualRPM, Error, Duty%\r\n");

ES_Timer_InitTimer(MOTOR_ADC_TIMER, ADC_UPDATE_TIME_MS);

// Start periodic timer for terminal printing
ES_Timer_InitTimer(MOTOR_PRINT_TIMER, PRINT_UPDATE_TIME_MS);

// post the initial transition event
ThisEvent.EventType = ES_INIT;
if (ES_PostToService(MyPriority, ThisEvent) == true)
{
    return true;
}
else
{
    return false;
}
}

//*****
Function
PostMotorService

```

```

Parameters
EF_Event_t ThisEvent ,the event to post to the queue

Returns
bool false if the Enqueue operation failed, true otherwise

Description
Posts an event to this state machine's queue
Notes

Author
J. Edward Carryer, 10/23/11, 19:25
*****
bool PostMotorService(ES_Event_t ThisEvent)
{
    return ES_PostToService(MyPriority, ThisEvent);
}

/*****
Function
RunMotorService

Parameters
ES_Event_t : the event to process

Returns
ES_Event, ES_NO_EVENT if no error ES_ERROR otherwise

Description
Handles ADC reading for speed command, terminal printing, and gain tuning
Notes

Author
J. Edward Carryer, 01/15/12, 15:23
*****
ES_Event_t RunMotorService(ES_Event_t ThisEvent)
{
    ES_Event_t ReturnEvent;
    ReturnEvent.EventType = ES_NO_EVENT; // assume no errors
    *****
    in here you write your service code
    *****
    switch(ThisEvent.EventType){
        case ES_TIMEOUT:
            if (ThisEvent.EventParam == MOTOR_ADC_TIMER)
            {
                // --- Read Potentiometer for Speed Command ---
                uint32_t adcResult[1];
                ADC_MultiRead(adcResult);

                // Map ADC (0-1023) to commanded RPM (0-MAX_COMMANDED_RPM)
                TargetRPM = ((float)adcResult[0] * MAX_COMMANDED_RPM) / 1023.0;

                // Restart ADC timer
                ES_Timer_InitTimer(MOTOR_ADC_TIMER, ADC_UPDATE_TIME_MS);
            }
        else if (ThisEvent.EventParam == MOTOR_PRINT_TIMER)
        {
    }
}

```

```

// --- Print current state for monitoring ---
// Read volatile variables safely
__builtin_disable_interrupts();
float displayRPM = CurrentRPM;
float displayError = LastRPMError;
float displayDuty = RequestedDuty;
__builtin_enable_interrupts();

// Print in CSV format

DB_printf("%d, %d, %d, %d\r\n",
          (int)(TargetRPM), (int)(displayRPM), (int)(displayError),
(int)(displayDuty));

// Restart print timer
ES_Timer_InitTimer(MOTOR_PRINT_TIMER, PRINT_UPDATE_TIME_MS);
}

break;

case ES_NEW_KEY:
{
    char key = (char)ThisEvent.EventParam;

    switch (key)
    {
        case 'P': // Increase pGain
            pGain += 0.1;
            DB_printf("pGain = %d\r\n", (int)(100 * pGain));
            break;

        case 'p': // Decrease pGain
            pGain -= 0.1;
            if (pGain < 0) pGain = 0;
            DB_printf("pGain = %d\r\n", (int)(100 * pGain));
            break;

        case 'I': // Increase iGain
            iGain += 0.005;
            DB_printf("iGain = %d\r\n", (int)(100 * iGain));
            break;

        case 'i': // Decrease iGain
            iGain -= 0.005;
            if (iGain < 0) iGain = 0;
            DB_printf("iGain = %d\r\n", (int)(100 * iGain));
            break;

        // case 'r': // Reset integral term
        // case 'R':
        //     SumError = 0;
        //     DB_printf("Integral term reset (SumError = 0)\r\n");
        //     break;

        case '?': // Show current gains
            DB_printf("Current gains: pGain = %d, iGain = %d\r\n",
                      (int)(100 * pGain), (int)(100 * iGain));
            DB_printf("SumError = %d\r\n", (int)(SumError));
            DB_printf("\r\nTargetRPM, ActualRPM, Error, Duty%\r\n");
            break;
    }
}

```

```

        default:
            break;
    }
}break;

}

return ReturnEvent;
}

//*****************************************************************************
ISR: Control Loop (Timer4) - Priority 5
Runs every 2ms to calculate and apply PI control law
***** */
void __ISR(_TIMER_4_VECTOR, IPL5AUTO) Timer4_ISR(void)
{
    // Clear interrupt flag first
    IFS0CLR = _IFS0_T4IF_MASK;

    // Raise timing pin on entry
    TIMING_PIN_LAT = 1;

    // --- Local variables (static for speed) ---
    static float RPMEerror;
    static uint32_t ThisPeriod;
    static float Rpm;

    // --- Get Current Motor Speed ---
    ThisPeriod = CurrentPeriod;

    if (ThisPeriod > 0)
    {
        Rpm = (float)PER2RPM / (float)ThisPeriod;
    }
    else
    {
        Rpm = 0;
    }

    // --- Calculate Error ---
    RPMEerror = TargetRPM - Rpm;
    SumError += RPMEerror;

    // --- Calculate Requested Duty Cycle (PI Control Law) ---
    RequestedDuty = (pGain * RPMEerror) + (iGain * SumError);

    // --- Clamp Output and Apply Anti-Windup ---
    if (RequestedDuty > 100)
    {
        RequestedDuty = 100;
        SumError -= RPMEerror; // Anti-windup
    }
    else if (RequestedDuty < 0)
    {
        RequestedDuty = 0;
        SumError -= RPMEerror; // Anti-windup
    }

    // --- Update values for display ---
}

```

```

LastRPMError = RPMError;
CurrentRPM = Rpm;

// --- Apply Duty Cycle to PWM ---
SetDuty(RequestedDuty);

// Lower timing pin before exit
TIMING_PIN_LAT = 0;
}

/*****************
ISR: Input Capture 2
*****************/
void __ISR(_INPUT_CAPTURE_2_VECTOR, IPL6AUTO) IC2_ISR(void)
{
    uint16_t ThisCapture;

    // Drain the FIFO - read all buffered captures, keep only the last one
    while (IC2CONbits.ICYNE)
    {
        ThisCapture = IC2BUF;
    }

    // Calculate period (unsigned subtraction handles 16-bit rollover)
    CurrentPeriod = ThisCapture - LastCapture;

    // Save for next edge
    LastCapture = ThisCapture;

    // Clear interrupt flag
    IFS0CLR = _IFS0_IC2IF_MASK;
}

/*****************
private functions
*****************/
/*****************
Function
InitPWM
*****************/

Description
    Initializes Timer2 and OC4 for PWM output on RB13 at 4000 Hz
*****
static void InitPWM(void)
{
    // ===== Timer2 Setup =====
    T2CONbits.ON = 0;           // Disable Timer2
    T2CONbits.TCS = 0;          // Select internal PBCLK
    T2CONbits.TCKPS = PWM_PRESCALE; // 1:4 prescaler
    TMR2 = 0;                  // Clear timer register
    PR2 = PWM_PERIOD;          // Set period for 4000 Hz
    // No need to clear interrupt flags since we are not using them
    T2CONbits.ON = 1;          // Enable Timer2

    // ===== OC4 Setup =====
    OC4CONbits.ON = 0;          // Disable OC4 during setup

    // Set initial duty cycle to 0%
    OC4R = 0;
}

```

```

OC4RS = 0;

// Disable analog on PWM pin
PWM_PIN_ANSEL = 0;

// Map OC4 to RB13 (pin 24)
RPB13R = 0b0101;

// Configure OC4 for PWM mode
OC4CONbits.OCTSEL = 0;           // Use Timer2 as clock source
OC4CONbits.OCM = 0b110;          // PWM mode, fault pin disabled

// Enable OC4
OC4CONbits.ON = 1;
}

/*****************/
Function
    InitDirectionPins

Description
    Initializes the direction control output (RB2) and direction input (RA1)
/*****************/
static void InitDirectionPins(void)
{
    // --- Direction Control Output (RB2, IN 1A) ---
    DIR_1A_ANSEL = 0;           // Disable analog
    DIR_1A_TRIS = 0;            // Set as output
    DIR_1A_LAT = 0;             // Initialize low (forward direction)

}

/*****************/
Function
    InitInputCapture

Description
    Initializes Timer3 (maximum period) and IC2 for encoder period measurement
/*****************/
static void InitInputCapture(void)
{
    // ===== Timer3 Setup (free-running for Input Capture) =====
    T3CONbits.ON = 0;           // Disable Timer3
    T3CONbits.TCS = 0;           // Select internal PBCLK
    T3CONbits.TCKPS = IC_TIMER_PRESCALE; // 1:8 prescaler
    TMR3 = 0;                   // Clear timer register
    PR3 = 0xFFFF;               // Max period
    IFS0CLR = _IFS0_T3IF_MASK; // Clear Timer3 interrupt flag
    T3CONbits.ON = 1;            // Enable Timer3

    // ===== Input Capture 2 Setup =====
    // Map IC2 input to RB9 (pin 18)
    IC2R = 0b0100;

    // Disable IC2 during setup
    IC2CONbits.ON = 0;

    // Configure IC2
}

```

```

IC2CONbits.ICTMR = 0;           // Use Timer3 (ICTMR=0 means Timer3)
IC2CONbits.ICI = 0b00;          // Interrupt on every capture event
IC2CONbits.ICM = 0b011;         // Capture on every rising edge

// Configure IC2 interrupt
IFS0CLR = _IFS0_IC2IF_MASK;    // Clear interrupt flag
IPC2bits.IC2IP = 6;            // Priority 6
IPC2bits.IC2IS = 0;            // Subpriority 0
IEC0SET = _IEC0_IC2IE_MASK;    // Enable IC2 interrupt

// Enable Input Capture module
IC2CONbits.ON = 1;
}

/*****
Function
InitControlTimer

Description
Initializes Timer4 for 2ms control loop interrupt
*****/
static void InitControlTimer(void)
{
    // Disable Timer4
T4CONbits.ON = 0;

    // Select internal PBCLK
T4CONbits.TCS = 0;

    // Set prescaler (1:4)
T4CONbits.TCKPS = CONTROL_TIMER_PRESCALE;

    // Clear timer register
TMR4 = 0;

    // Set period for 2ms
    // PBCLK = 20MHz, Prescaler = 1:4 -> 5MHz tick rate
    // 2ms = 0.002s * 5,000,000 = 10,000 ticks
    // PR4 = 10000 - 1 = 9999
PR4 = CONTROL_TIMER_PERIOD;

    // Configure Timer4 interrupt - Priority 5 (LOWER than Input Capture)
IFS0CLR = _IFS0_T4IF_MASK;      // Clear interrupt flag
IPC4bits.T4IP = 5;              // Priority 5 lower than IC interrupt priority
IPC4bits.T4IS = 0;              // Subpriority 0
IEC0SET = _IEC0_T4IE_MASK;      // Enable Timer4 interrupt

    // Enable Timer4
T4CONbits.ON = 1;
}

/*****
Function
SetDutyCycle

Parameters
uint8_t dutyPercent - duty cycle as percentage (0-100)

Description
Converts percentage to PWM register value and updates OC4RS

```

```
*****static void SetDuty(float dutyPercent)
{
    // Clamp to valid range
    if (dutyPercent > 100)
    {
        dutyPercent = 100;
    }
    else if (dutyPercent < 0)
    {
        dutyPercent = 0;
    }

    // Convert percentage to PWM register value
    uint32_t dutyValue = (uint32_t)((dutyPercent * PWM_PERIOD) / 100.0);

    // Write to OC4RS (double-buffered, updates on next period match)
    OC4RS = dutyValue;
}

/*----- Footnotes -----*/
/*----- End of file -----*/
```

Measurements from part 2.5

Time spent in ISR = 27.4 microseconds

0.0137 or 1.37% of the total execution time