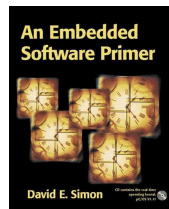


AVR Interrupts

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Readings

- Read Chap 4 of Simon, D. E. (1999). An Embedded Software Primer
- Topics
 - Assembly language
 - Saving and restoring context
 - Data-shared problem
 - Atomicity and critical section
 - The volatile keyword



Limitation of CPU timers

```

1 #include <avr/io.h>
2 int main() {
3     uint8_t count=0;
4     DDRB |= (1<<PB1)
5     ASSR |= (1<<AS0); //use ext oscillator
6     TCCR0 |= (1<<CS00); //normal mode, no prescaling
7     while(1) {
8         while (! (TIFR & (1<<TOV0))) { /*Wait until
9             overflow occurs*/
10            TIFR |= (1<<TOV0); //clear by writing a one to
11            TOV0
12            count++; //extend counter
13            if((count % 64) == 0) { //toggle PB0 every 64
14                overflows
15                PORTB ^= (1<<PB1);
16            }
17    }

```

Limitation of the timer programs

- What if we are to generate two delays at the same time?
 - Example: Toggle bit PB5 every 1s and PB4 every 0.5s
- What if there are some task to be done simultaneously with the timers?
 - Example: (1) read the contents of port A, process the data, and send them to port D continuously, (2) toggle bit PB.5 every 1s, and (3) PB.4 every 0.5s.

What is an interrupt?

- Interrupts are triggered when certain events occur in the hardware¹.
- e.g. when a serial chip has sent data to a microprocessor and wants it to read it from its pin, it sends an interrupt to the processor, usually by sending a signal to one of the processor's IRQ (interrupt request) pins.
- On receiving an interrupt, the microprocessor stops its current execution, saves the address of the next instruction on the stack and jumps to an interrupt service routine (ISR) or interrupt handler.
- The ISR is basically a subroutine written by the user to perform certain operations to handle the interrupt with a RETURN instruction at the end. It is a good practice to save register state and reset the interrupt in ISRs.
- ISRs are similar to a CALL except that the call to the ISR is automatically made.

What is an interrupt?

- An interrupt is a way for an external (or, sometimes, internal) event to pause the current processor's activity, so that it can complete a brief task before resuming execution where it left



FIG 1. Principle of an interrupt

- For example, one can set up the processor so that it is looking for a specific external event (like a pin going high or a timer overflowing) to become true, while it goes on and performs other tasks.
- When these even occur, we stop the current task, handle the event, and resume back the previous tasks.

What is an interrupt?

- An interrupt is an exception, a change of the normal progression, or interruption in the normal flow of program execution.
- An interrupt is essentially a hardware generated function call.
- Interrupts are caused by both internal and external sources.
- An interrupt causes the normal program execution to halt and for the interrupt service routine (ISR) to be executed.
- At the conclusion of the ISR, normal program execution is resumed at the point where it was last.

In short, with an interrupt, there is no need for the processor to monitor the status of the devices and events. Instead, the events notify the processor when they occur by sending an interrupt signal to processor

Interrupts vs. polling

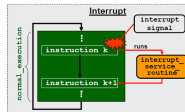
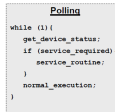
```
1 #include <avr/io.h>
2 int main(void) {
3     // Initialization code left out for clarity
4     while (1) {
5         if ((PINB & (1 << SWITCH_PIN)) ==
6             NOT_PRESSED ) {
7             // Turn off the Led
8             PORTB |= (1<<LED_PIN); // Set PB1 to HIGH
9         }
10        else {
11            // Turn on the led
12            PORTB &= ~(1<<LED_PIN); // Set PB1 to LOW
13        }
14    }
15    return 0;
16 }
```

Interrupts vs. polling

```
1 #include<avr/io.h>
2 #include<avr/interrupt.h>
3 #define F_CPU (1000000UL * 16UL) //16MHz clock
4 ISR (TIMER1_OVF_vect){
5     PORTD ^= (1 << PD0);
6     TCNT1 = 63974;    // for 100ms at 16 MHz
7 }
8 int main(){
9     DDRD = (1 << PD0);
10    TCNT1 = 63974;    // for 100ms at 16 MHz
11    TCCR1A = 0x00;
12    TCCR1B = (1<<CS10)|(1<<CS12); // Timer mode with
13        1024 prescaler
14    TIMSK = (1 << TOIE1); // Enable timer1 overflow
15        interrupt
16    sei();    // Enable global interrupts
```

Interrupt vs. polling

- Using polling, the CPU must continually check the device's status
- Using interrupt:
 - A device will send an interrupt signal when needed.
 - In response, the CPU will perform an interrupt service routine, and then resume its normal execution.
 - Allows low response latency
 - Determinism (in many cases anyways!). Determinism is the consistency of the response time



Interrupt vs polling

- Polling uses a lot of CPU horsepower
 - checking whether the peripheral is ready or not
 - Wait until the peripheral is ready (but wait for how long?)
 - interrupts use the CPU only when work is to be done
- Polled code is generally messy and unstructured
 - big loop with often multiple calls to check and see if peripheral is ready
 - necessary to keep peripheral from waiting
 - ISRs concentrate all peripheral code in one place (encapsulation)
- Polled code leads to variable latency in servicing peripherals
 - whether if branches are taken or not, timing can vary
 - interrupts give highly predictable servicing latencies

What causes an interrupt?

- Timers —there are at least two interrupts for each time: one for an overflow and another for the compare match
- Interrupts set for external hardware interrupts. For the ATmega128, the external interrupts are triggered by the INT7:0 pins.
- Serial communication interrupts
- Serial Peripheral Interface (SPI) interrupts
- Analog-to-digital converter (ADC) interrupts
- etc

Why use an interrupt?

- To detect pin changes (eg. rotary encoders, button presses)
- Watchdog timer (eg. if nothing happens after 8 seconds, interrupt me)
- Timer interrupts - used for comparing/overflowing timers
- ADC conversions (analog to digital)
- EEPROM ready for use
- Flash memory ready

Saving and Restoring the Context

- Due to limited number of registers, the ISRs and task codes usually have to work with same registers.
- As shown in Fig. 2, the task code has no idea of the changes taking place in registers like R1 or R2 in the ISR.

```
...  
MOVE R1, R7  
MUL R1, 5  
ADD R1, R2  
DIV R1, 2  
JCND ZERO, END  
SUBTRACT R1, R3  
...  
END: MOVE R7, R1  
...  
PUSH R1  
PUSH R2  
...  
;ISR code comes here  
...  
POP R2  
POP R1  
RETURN
```

FIG 2. Example of assembly code of ISR

- Hence if R1 is modified by the ISR, we might get an incorrect final result.
- To solve this problem it is common practice to save the register contents onto the stack (saving the context) and restoring them at the end of the ISR.

Disabling Interrupts

- Most microprocessors allow programs to disable interrupts.
- In most cases the program can select which interrupts to disable during critical operations and which to keep enabled by writing corresponding values into a special register.
- **Nonmaskable** interrupts however cannot be disabled and are normally used to indicate power failures or other serious event.
- Certain processors assign **priorities** to interrupts, allowing programs to specify a threshold priority so that only interrupts having higher priorities than the threshold are enabled and the ones below it are disabled.

The Shared-Data Problem

- In many cases the ISRs need to communicate with the task codes through shared variables.
- **Listing 4** shows the classic shared-data problem. The code continuously monitors two temperatures and sets off an alarm if they are different.
- An ISR reads the temperatures from the hardware. The interrupt might be invoked through a timer or through the temperature sensing hardware itself.
- The code is buggy because it sets off the alarm when it should not.

The Shared-Data Problem

- Suppose all temperatures have been 20 °C for a while
- Suppose now that the CPU execute the following code

```
1 reactor1Temperature = temperatures[0];
```

- Suppose now that an interrupt occurs and that both temperature have increased to 21 °C degrees
- Thus, the ISR will assign 21 to all elements of the temperatures array.
- When the ISR ends , the MCU will continue with the next line of code

```
1 reactor2Temperature = temperatures[1];
```

- Since the ISR has set all elements of the temperatures array to 21, the reactor2Temperature=21.
- However, the variable reactor1Temperature is still 20 since

```
1 static int temperatures [2];
2 void interrupt ReadTemperature(void) {
3     temperatures[0] = ReadTemperatureSensor(0);
4     temperatures[1] = ReadTemperatureSesnor(1);
5 }
6 void main (void){
7     int room1Temperature, room2Temperature;
8     while(true){
9         reactor1Temperature = temperatures[0];
10        reactor2Temperature = temperatures[1];
11        if(room1Temperature != room2Temperature){
12            // Set off an alarm and alert
13            plant operators
14        }
15    }
```

LISTING 4: Industrial temperature monitoring

The code is part of an industrial plant control firmware. The software monitors

The Shared-Data Problem

```
1 static int temperatures [2];
2 void interrupt ReadTemperature(void) {
3     temperatures[0] = ReadTemperatureSensor(0);
4     temperatures[1] = ReadTemperatureSesnor(1);
5 }
6 void main (void){
7     int room1Temperature, room2Temperature;
8     while(true){
9         if(temperatures[0] != temperatures[1]){
10            // Set off an alarm and alert
11            plant operators
12        }
13    }
```

LISTING 5: Industrial temperature monitoring—Much harder to catch bug

This code is similar to that in Listing 4 except that the program does not store the sensors data into local copies. Instead, it directly compares values in the

- Remember, C statements are terse and hide lots of information
- The assembly code in Listing 6 shows if an interrupt occurs between the two MOVES, this translates into the same problem we had before and the alarm goes off when it shouldn't have.

```
1 // Other code omitted fro brevity
2 MOVE R1, temperatures[0]
3 MOVE R1, temperatures[1]
4 SUBTRACT R1, R2
5 //
6 //Set off the alarm
7 //
8 JCOND 0, __IS_TEMPERATURE_OK;
9 //
10 //Other instruction if the temperature matches
11 //
```

LISTING 6: Assembly language equivalent of the code in Listing 5

Characteristics of the shared-data bug

- Very hard to find because they do not occur every time to code runs
- They, in fact, appear random

Solving the shared-data problem

- The problem can be solved by disabling the interrupts during the instructions that use the shared variable and re-enabling them later

```
1 while (true) {
2     // Disable interrupts
3     interrupt_disable();
4     reactor1Temperature = temperatures[0];
5     reactor2Temperature = temperatures[1];
6     // Re-enable interrupts
7     interrupt_enable();
8     ...
9     // Continue with the remaining code
10    ...
}
```

Atomic operations

- An operation (or set of operations) is atomic, linearizable, indivisible or uninterruptible if it appears to the rest of the system to occur instantaneously. Atomicity is a guarantee of isolation from concurrent processes.
- Hence the code between `disable()` and `enable()` above is atomic

Consider an ISR that code in Listing 9 that updates *hours*, *minutes*, and *seconds* every second through a hardware timer interrupt. Is this code **atomic**?

```
1 long calculateSecondsSinceMidnight (void) {
2     long result = 0;
3     interrupt_disable();
4     result = (long) (hours * 3600 + minutes * 60 +
5                     seconds);
6     interrupt_enable();
7 }
```

Atomic operations

```
1 static int seconds, minutes, hours;
2 void interrupt updateTime(void) {
3     ++seconds;
4     if (seconds >= 60) {
5         seconds = 0;
6         ++minutes;
7         if (minutes >= 60) {
8             minutes = 0;
9             ++hours;
10            if (hours >= 24) {
11                hours = 0;
12            }
13        }
14    }
15 }
```

LISTING 9: Interrupt to update the elapsed time

Atomic operations

- What would happen `calculateSecondsSinceMidnight (void)` function is called somewhere else from a critical section that has disabled interrupts?
- In this case, the function will incorrectly enable interrupts on return.
- Listing 11 provides a better solution to this problem

```
1 long calculateSecondsSinceMidnight (void) {
2     long result = 0;
3     bool isInterruptAlreadyDisabled = false;
4     interrupt_disable();
5     isInterruptAlreadyDisabled = true;
6     result = (long) (hours * 3600 + minutes * 60 +
7                     seconds);
8     if (isInterruptAlreadyDisabled) {
9         interrupt_enable();
10    }
11 }
```

How about this solution?

```
1 static long int seconds;
2 int SECONDS_IN_DAY = 60*60*24;
3 void interrupt updateTime(void){
4     // Code omitted for brevity
5     ++seconds;
6     if(seconds == SECONDS_IN_DAY){
7         seconds = 0L;
8     }
9     // Code omitted for brevity
10 }
11 long calculateSecondsSinceMidnight (void){
12     return seconds;
13 }
```

LISTING 11: A risky function to compute the number of seconds since midnight

How about this solution?

- This is a **risky**, **irresponsible** and **dangerous** solution
- if the CPU has registers (e.g., 32-bit registers) that are large enough to hold the up to the total number of seconds in a day (i.e., 86400), then the code would be **atomic**. The generated assembly would be atomic as shown below

```
1 MOVE R1, seconds
2 RETURN
```

- Otherwise, the generate assembly would be **non-atomic**

```
1 // Get the first byte or word
2 MOVE R1, seconds
3 // Get the second byte or word
4 MOVE R2, (seconds +1)
5 ...
6 // Code omitted for brevity
7 ...
8 RETURN
```

The volatile Keyword

- Compilers assume that the value in a variable stays in memory unless the program changes it, and they use this assumption to optimize the code.
- In embedded systems, this can lead to serious problem²
- For example, in Listing 12, the compiler might read *seconds* in one or more registers and instead of updating the value before saving it to *result*, it will read the value from the register every time instead of from memory.
- Some compilers might also remove the while-loop during optimization causing the same bug we were trying to avoid
- This is prevented by declaring *seconds* as **volatile**. This warns the C compiler that the variable might change due to interrupts or other routines and not to optimize code pertaining to it.

```
1 static volatile long int seconds;
```

²This problem may not arise during firmware development when usually the

The volatile Keyword

```
1 static long int seconds;
2 void interrupt updateTime(void){
3     ...
4     seconds++;
5     if(seconds == 60L*60L*24L){
6         seconds = 0L;
7     }
8     ...
9 }
10 long calculateSecondsSinceMidnight (void){
11     long result = 0;
12     //When we read the same value twice, it must be
13     good
14     while(result != seconds)
15         result = seconds;
16     return result;
17 }
```

Interrupt Latency

- **Interrupt latency** is the amount of time taken to respond to an interrupt.
- It depends on several factors:
 - Longest period during which the interrupt is disabled
 - Time taken to execute ISRs of higher priority interrupts
 - Time taken for the microprocessor to stop the current execution, do the necessary 'bookkeeping' and start executing the ISR
 - Time taken for the ISR to save context and start executing instructions that count as a "response"
 - The third factor is measured by knowing the instruction execution times from the processor manual, when instructions are not cached.
- Disabling interrupts increases interrupt latency so this period should be kept as short as possible

Keep ISR short and fast

- ISRs affect the normal execution of program and can block handling of other interrupts. Thus, interrupt service routine (ISR) should be short and to the point so that the primary application can resume execution.
- The real point of an interrupt is to handle an urgent event that requires the system's attention. To keep the routine short, only do the minimum of what really needs to be done at that moment. For example, if communication data is triggering the interrupt, stuff the data into a buffer, set a flag and let the main program process the data. Don't try to process it in the interrupt!
- Don't call a function from within your interrupt (unless they are inline functions). The function call overhead will kill your timing.
- Any processor intensive activity such as processing a data buffer, performing a calculation, etc. should instead set a flag

Understand ISR response time

- Not taking into consideration the interrupt response time can lead to serious bugs that are hard to find and troubleshoot.
- For example, a simple context switch into the interrupt can take between four clock cycles. For a microcontroller running at 8 MHz this can be a delay of 500 nanoseconds. This is just for one context switch into the interrupt! There is another one when leaving the interrupt!
- It is very important to understand how often your periodic and asynchronous interrupts are occurring so that you can ensure the rest of the program has an opportunity to run.
- It's also important to understand if there is an opportunity for interrupts to occur at the same time and if they do understand the latency between one finishing and the next running.

The end