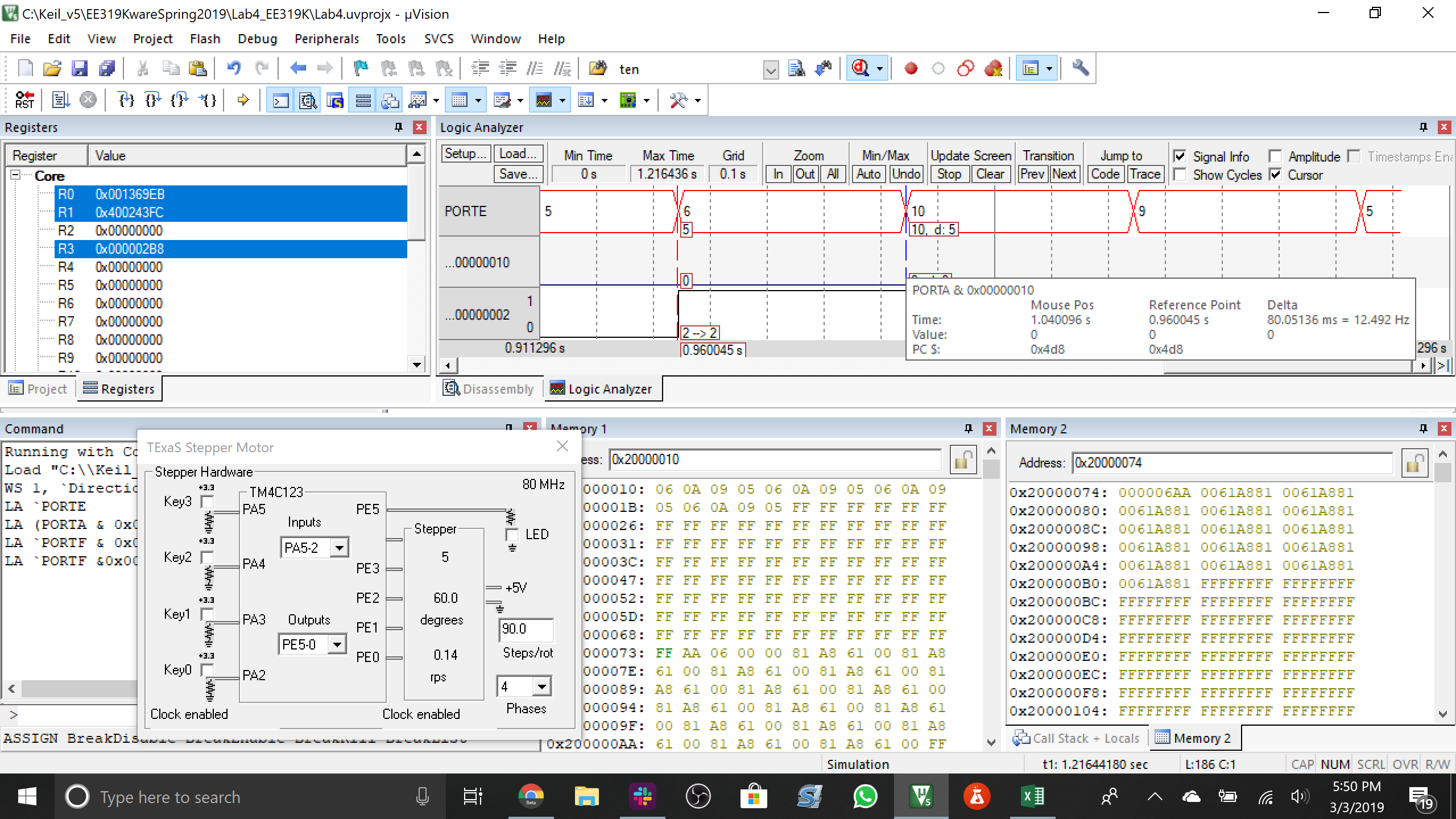
**2.** **Logic Analyzer and Memory Dump**



![A screenshot of a cell phone

Description automatically generated](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAwADAAAD/4RDoRXhpZgAATU0AKgAAAAgABAE7AAIAAAAKAAAISodpAAQAAAABAAAIVJydAAEAAAAUAAAQzOocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFJhZWQgQXNkaQAABZADAAIAAAAUAAAQopAEAAIAAAAUAAAQtpKRAAIAAAADNjEAAJKSAAIAAAADNjEAAOocAAcAAAgMAAAIlgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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**3. Assembly Program (with 4. Calculations of times elapsed)**

;\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\* main.s \*\*\*\*\*\*\*\*\*\*\*\*\*\*\*

; Program written by: \*\*-UUU-\*Raed&Trevor\*

; Date Created: 2/14/2017

; Last Modified: 3/3/2019

; You are given a simple stepper motor software system with one input and

; four outputs. This program runs, but you are asked to add minimally intrusive

; debugging instruments to verify it is running properly.

; If the input PA4 is low, the stepper motor outputs cycle 10,6,5,9,...

; If the input PA4 is high, the stepper motor outputs cycle 5,6,10,9,...

; Insert debugging instruments which gather data (state and timing)

; to verify that the system is functioning as expected.

; Hardware connections (External: One button and four outputs to stepper motor)

; PA4 is Button input (1 means pressed, 0 means not pressed)

; PE3-0 are stepper motor outputs

; PF2 is Blue LED on Launchpad used as a heartbeat

; Instrumentation data to be gathered is as follows:

; After every output to Port E, collect one state and time entry.

; The state information is the 5 bits on Port A bit 4 and Port E PE3-0

; place one 8-bit entry in your Data Buffer

; The time information is the 24-bit time difference between this output and the previous (in 12.5ns units)

; place one 32-bit entry in the Time Buffer

; 24-bit value of the SysTick's Current register (NVIC\_ST\_CURRENT\_R)

; you must handle the roll over as Current goes 3,2,1,0,0x00FFFFFF,0xFFFFFE,

; Note: The size of both buffers is 100 entries. Once you fill these

; entries you should stop collecting data

; The heartbeat is an indicator of the running of the program.

; On each iteration of the main loop of your program toggle the

; LED to indicate that your code(system) is live (not stuck or dead).

SYSCTL\_RCGCGPIO\_R EQU 0x400FE608

NVIC\_ST\_CURRENT\_R EQU 0xE000E018

GPIO\_PORTA\_DATA\_R EQU 0x400043FC

GPIO\_PORTA\_DIR\_R EQU 0x40004400

GPIO\_PORTA\_DEN\_R EQU 0x4000451C

GPIO\_PORTE\_DATA\_R EQU 0x400243FC

GPIO\_PORTE\_DIR\_R EQU 0x40024400

GPIO\_PORTE\_DEN\_R EQU 0x4002451C

GPIO\_PORTF\_DATA\_R EQU 0x400253FC

GPIO\_PORTF\_DIR\_R EQU 0x40025400

GPIO\_PORTF\_DEN\_R EQU 0x4002551C

; RAM Area

AREA DATA, ALIGN=2

Index SPACE 4 ; index into Stepper table 0,1,2,3

Direction SPACE 4 ; -1 for CCW, 0 for stop 1 for CW

;place your debug variables in RAM here

DataBuffer SPACE 100

TimeBuffer SPACE 400

Data\_Pt SPACE 4

Time\_Pt SPACE 4

Prev\_Time SPACE 4

; ROM Area

IMPORT TExaS\_Init

IMPORT SysTick\_Init

;-UUU-Import routine(s) from other assembly files (like SysTick.s) here

AREA |.text|, CODE, READONLY, ALIGN=2

THUMB

Stepper DCB 5,6,10,9

EXPORT Start

Start

;Heartbeat Instrument: ENABLE

;Enable Port F

LDR R1, =SYSCTL\_RCGCGPIO\_R

LDR R0, [R1]

ORR R0, R0, #0x20 ; Clock for F

STR R0, [R1]

NOP

NOP

LDR R0, =GPIO\_PORTF\_DIR\_R

LDR R1, [R0]

ORR R1, #0x02 ; Output on PF1

STR R1, [R0]

LDR R0, =GPIO\_PORTF\_DEN\_R

LDR R1, [R0]

ORR R1, #0x02 ; enable PF1

STR R1, [R0]

; TExaS\_Init sets bus clock at 80 MHz

; PA4, PE3-PE0 out logic analyzer to TExasDisplay

LDR R0,=SendDataToLogicAnalyzer

ORR R0,R0,#1

BL TExaS\_Init ; logic analyzer, 80 MHz

;place your initializations here

BL Stepper\_Init ; initialize stepper motor

BL Switch\_Init ; initialize switch input

;\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*

BL Debug\_Init ;(you write this)

;\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*

CPSIE I ; TExaS logic analyzer runs on interrupts

MOV R5,#0 ; last PA4

loop

;Heartbeat Instrument toggle

LDR R0,=GPIO\_PORTF\_DATA\_R

LDR R1, [R0]

EOR R1, #0x02

STR R1, [R0]

LDR R1,=GPIO\_PORTA\_DATA\_R

LDR R4,[R1] ;current value of switch

AND R4,R4,#0x10 ; select just bit 4

CMP R4,#0

BEQ no ; skip if not pushed

CMP R5,#0

BNE no ; skip if pushed last time

; this time yes, last time no

LDR R1,=Direction

LDR R0,[R1] ; current direction

ADD R0,R0,#1 ;-1,0,1 to 0,1,2

CMP R0,#2

BNE ok

MOV R0,#-1 ; cycles through values -1,0,1

ok STR R0,[R1] ; Direction=0 (CW)

no MOV R5,R4 ; setup for next time

BL Stepper\_Step

LDR R0,=1600000

BL Wait ; time delay fixed but not accurate

B loop

;Initialize stepper motor interface

Stepper\_Init

MOV R0,#1

LDR R1,=Direction

STR R0,[R1] ; Direction=0 (CW)

MOV R0,#0

LDR R1,=Index

STR R0,[R1] ; Index=0

; activate clock for Port E

LDR R1, =SYSCTL\_RCGCGPIO\_R

LDR R0, [R1]

ORR R0, R0, #0x10 ; Clock for E

STR R0, [R1]

NOP

NOP ; allow time to finish activating

; set direction register

LDR R1, =GPIO\_PORTE\_DIR\_R

LDR R0, [R1]

ORR R0, R0, #0x0F ; Output on PE0-PE3

STR R0, [R1]

; enable digital port

LDR R1, =GPIO\_PORTE\_DEN\_R

LDR R0, [R1]

ORR R0, R0, #0x0F ; enable PE3-0

STR R0, [R1]

BX LR

;Initialize switch interface

Switch\_Init

; activate clock for Port A

LDR R1, =SYSCTL\_RCGCGPIO\_R

LDR R0, [R1]

ORR R0, R0, #0x01 ; Clock for A

STR R0, [R1]

NOP

NOP ; allow time to finish activating

; set direction register

LDR R1, =GPIO\_PORTA\_DIR\_R

LDR R0, [R1]

BIC R0, R0, #0x10 ; Input on PA4

STR R0, [R1]

; 5) enable digital port

LDR R1, =GPIO\_PORTA\_DEN\_R

LDR R0, [R1]

ORR R0, R0, #0x10 ; enable PA4

STR R0, [R1]

BX LR

; Step the motor clockwise

; Direction determines the rotational direction

; Input: None

; Output: None

Stepper\_Step

PUSH {R4,LR}

LDR R1,=Index

LDR R2,[R1] ; old Index

LDR R3,=Direction

LDR R0,[R3] ; -1 for CCW, 0 for stop 1 for CW

ADD R2,R2,R0

AND R2,R2,#3 ; 0,1,2,3,0,1,2,...

STR R2,[R1] ; new Index

LDR R3,=Stepper ; table

LDRB R0,[R2,R3] ; next output: 5,6,10,9,5,6,10,...

LDR R1,=GPIO\_PORTE\_DATA\_R ; change PE3-PE0

STR R0,[R1]

BL Debug\_Capture

POP {R4,PC}

; inaccurate and inefficient time delay

Wait

SUBS R0,R0,#1 ; outer loop

BNE Wait

BX LR

Debug\_Init

PUSH {R0-R4,LR}

BL SysTick\_Init

LDR R0, =DataBuffer

MOV R2, #0

Dloop ;Set all entries of DataBuffer to 0xFF

MOV R4, #0xFF

STRB R4, [R0,R2]

ADD R2, #1

CMP R2, #99

BLS Dloop

LDR R1, =Data\_Pt

LDR R0, =DataBuffer

STR R0, [R1]

LDR R0, =TimeBuffer

MOV R2, #0

Tloop ;Set all entries of TimeBuffer to 0xFFFFFFFF

MOV R4, #0xFFFFFFFF

STR R4, [R0,R2]

ADD R2, #4

CMP R2, #396

BLS Tloop

LDR R1, =Time\_Pt

LDR R0, =TimeBuffer

STR R0, [R1]

POP {R0-R4,PC}

;Debug capture

;ESTIMATED TIME ELAPSED - (750ns)

;INTRUSIVENESS - (0.001875%)

Debug\_Capture

PUSH {R0-R6,LR}

;Check if Data Array is full, if true, then do not write

LDR R0, =DataBuffer

LDRB R1, [R0, #99]

CMP R1, #0xFF

BNE Done

;Timing Dump

LDR R0, =Time\_Pt

LDR R1, [R0] ;R1=Time pointer

LDR R3, =Prev\_Time

LDR R3, [R3] ;R3=Previous Time

LDR R2, =NVIC\_ST\_CURRENT\_R

LDR R2, [R2] ;R2=Current Time

SUB R4, R3, R2

AND R4, #0x00FFFFFF ;Mask to complete 24 bit substraction

STR R4, [R1]

LDR R3, =Prev\_Time

STR R2, [R3] ;Store Current in Previous

ADD R1, #4 ;Increment Pointer by 4 (32 bit array)

STR R1, [R0]

;Data Dump

LDR R0, =Data\_Pt

LDR R1, [R0] ;R1=Data pointer

LDR R2, =GPIO\_PORTE\_DATA\_R

LDR R2, [R2] ;R2=PORT E Data

AND R2, #0x0F ;Isolate PE0-3

LDR R3, =GPIO\_PORTA\_DATA\_R

LDR R3, [R3] ;R3=PORT A Data

AND R3, #0x10 ;Isolate PA4

ORR R2, R3 ;Combine states together

STRB R2, [R1] ;Store in Data Array

ADD R1, #1 ;Increment pointer by 1 (8 bit array)

STR R1, [R0]

Done POP {R0-R6,PC}

; edit the following only if you need to move pins from PA4, PE3-0

; logic analyzer on the real board

PA4 equ 0x40004040

PE30 equ 0x4002403C

UART0\_DR\_R equ 0x4000C000

SendDataToLogicAnalyzer

LDR R1,=PA4

LDR R1,[R1] ; read PA4

LDR R0,=PE30 ; read PE3-PE0

LDR R0,[R0]

ORR R0,R0,R1 ;combine into one 5-bit value

ORR R0,R0,#0x80

LDR R1,=UART0\_DR\_R

STR R0,[R1] ; send data at 10 kHz

BX LR

ALIGN ; make sure the end of this section is aligned

END ; end of file

; SysTick.s

; Module written by: \*\*-UUU-\*Raed&Trevor\*

; Date Created: 2/14/2017

; Last Modified: 3/3/2019

; Brief Description: Initializes SysTick

NVIC\_ST\_CTRL\_R EQU 0xE000E010

NVIC\_ST\_RELOAD\_R EQU 0xE000E014

NVIC\_ST\_CURRENT\_R EQU 0xE000E018

AREA |.text|, CODE, READONLY, ALIGN=2

THUMB

; -UUU- You add code here to export your routine(s) from SysTick.s to main.s

EXPORT SysTick\_Init

;------------SysTick\_Init------------

; ;-UUU-Complete this subroutine

; Initialize SysTick running at bus clock.

; Make it so NVIC\_ST\_CURRENT\_R can be used as a 24-bit time

; Input: none

; Output: none

; Modifies: ??

SysTick\_Init

; \*\*-UUU-\*\*Implement this function\*\*\*\*

PUSH {R0, R1}

LDR R0, =NVIC\_ST\_CTRL\_R ;Clear CTRL

MOV R1, #0

STR R1, [R0]

LDR R0, =NVIC\_ST\_CURRENT\_R ;Clear Current

MOV R1, #0

STR R1, [R0]

LDR R0, =NVIC\_ST\_RELOAD\_R ;set Reload to max

MOV R1, #0xFFFFFF

STR R1, [R0]

LDR R0, =NVIC\_ST\_CTRL\_R ;Activate CTRL

LDR R1, [R0]

ORR R1, #0x05

STR R1, [R0]

POP {R0, R1}

BX LR ; return

ALIGN ; make sure the end of this section is aligned

END ; end of file