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| --- | --- |
| **Title:** | **Window Lifter Controller** |

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|  |  |  |  |  |
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| 2.1 | Draft  27-Oct-17 | Rafael Sanchez | Rafael Sanchez | Add function descriptions.­­­­­­ |
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| 2.3 | Draft  29-Oct-17 | Rafael Sanchez | Rafael Sanchez | Updates function descriptions and Add flow chart to each function. |

**Table of Contents**

# Purpose

This document explains how the window lifter works and also describe each function through the layer programming method.

# Definitions and abbreviations

**Definitions**

|  |  |
| --- | --- |
| *BlueLed* | *Define to identify the port for the Blue Led* |
| *RedLed* | *Define to identify the port for the Red Led* |
| *GreenLed* | *Define to identify the port for the Green Led* |
| *UpButton* | *Define to identify the port for the push button 12* |
| *DownButton* | *Define to identify the port for the push button 13* |
| *LedBar\_1* | *Define to identify the port for the Bar’s first Led* |
| *LedBar\_2* | *Define to identify the port for the Bar’s secondary Led* |
| *LedBar\_3* | *Define to identify the port for the Bar’s third Led* |
| *LedBar\_4* | *Define to identify the port for the Bar’s fourth Led* |
| *LedBar\_5* | *Define to identify the port for the Bar’s fifth Led* |
| *LedBar\_6* | *Define to identify the port for the Bar’s sixth Led* |
| *LedBar\_7* | *Define to identify the port for the Bar’s seventh Led* |
| *LedBar\_8* | *Define to identify the port for the Bar’s eighth Led* |
| *LedBar\_9* | *Define to identify the port for the Bar’s ninth Led* |
| *LedBar\_10* | *Define to identify the port for the Bar’s tenth Led* |
| *malGPIO\_init\_void\_WDOG\_disable* | *Disable watchdog* |
| *malGPIO\_init\_void\_PORT\_init()* | *Port init* |
| *SOSC\_init\_8MHz* | *Clock of 8Mhz* |
| *SPLL\_init\_160MHz* | *Clock of 160Mhz* |
| *NormalRUNmode\_80MHz* | *Set the mode of the timer to normal with 8Mhz* |
| *malGPIO\_init\_void\_LPIT0\_init* | *Initialize timers* |
| *u32\_lpit0\_ch0\_flag\_counter* | *Variable to control timer 0* |
| *u32\_lpit0\_ch1\_flag\_counter* | *Variable to control timer 1* |
| *appUpDown\_void\_clearGPIO()* | *Function to turnoff/turnon BlueLed, GreenLed, RedLed and Ledbars* |
| *appUpDown\_u32\_PushDownButton()* | *Read if Down Button is pushed* |
| *appUpDown\_u32\_PushUpButton()* | *Read if Up Button is pushed* |
| *appUpDown\_u32\_validation10ms()* | *Validate if the button is pushed at least during 10 ms* |
| *appUpDown\_u32\_validation500ms()* | *Validate if the button is pushed at least during 500 ms* |
| *appUpDown\_void\_timer1()* | *Increase the variable u32\_lpit0\_ch1\_flag\_counter each 1 ms* |
| *appUpDown\_void\_default\_Leds(T\_U32 led)* | *Turn on/off Leds in a default phase* |
| *main\_void\_oneTouchUp()* | *Ascending turn on the LedBar leds with just one touch* |
| *main\_void\_oneTouchDown()* | *Descending turn on the LedBar leds with just one touch* |
| *main\_void\_behaviorUp()* | *Select the turn on leds behavior.* |
| *main\_void\_behaviorDown()* | *Select the turn off leds behavior.* |
| *main\_void\_antiPinch()* | *Do the antipinch action* |
| *main\_void\_idleState()* | *Put the program in an idle state* |

**Abbreviations**

|  |  |
| --- | --- |
| CH1 | Channel1 |
| CH2 | Channel2 |
| R&D | Research and Develop |

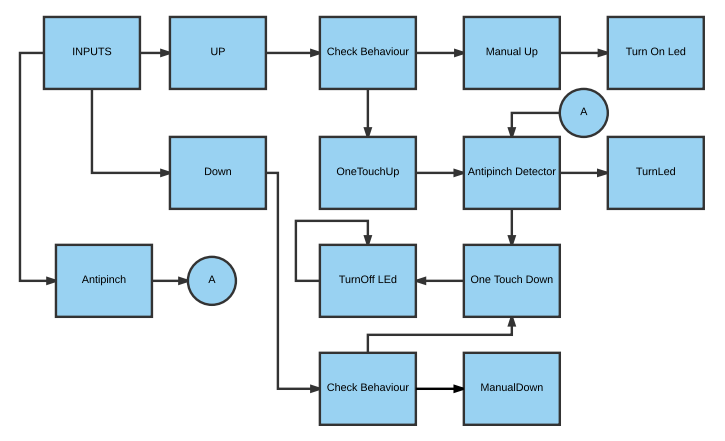
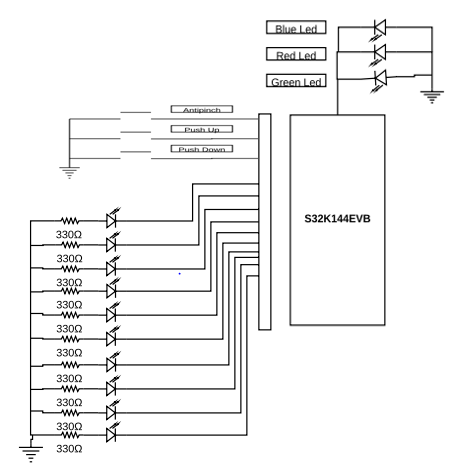
**References**

|  |  |  |
| --- | --- | --- |
| **N°** | **Document name** | **Reference** |
| *1* | *USER\_GUIDE\_S32K144* | [Link](https://www.nxp.com/products/microcontrollers-and-processors/arm-based-processors-and-mcus/s32-automotive-processors-and-microcontrollers/32-bit-automotive-general-purpose-microcontrollers:S32K?tab=Documentation_Tab) |
| 2 | [***S32K14x Series Reference Manual***](https://www.nxp.com/docs/en/reference-manual/S32K-RM.pdf) |
| 3 | [***S32K1xx Data Sheet***](https://www.nxp.com/docs/en/data-sheet/S32K-DS.pdf) |
| 4 | ***AN5413, s32k14x Series Cookbook*** |

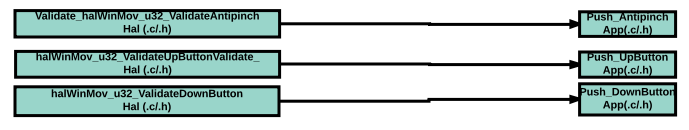
# Realization constraints and targets

The objective of the task is to achieve to lift and down a window car simulated by 10 red LedBar regarding to the customer request. The development of the project must be on the Development Kit Platform S32K144EVB NXP microcontroller provided by Continental R&D.

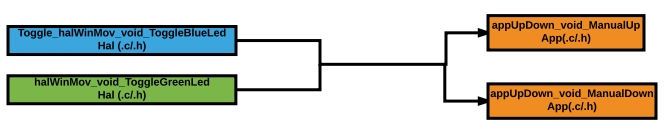
# SW Conceptual design



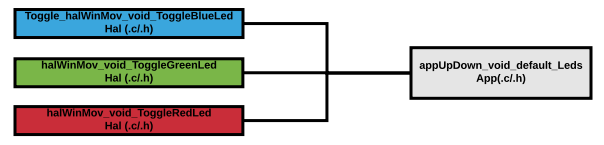
1. **SW Component internal breakdown**
   1. **Diagrams by component**



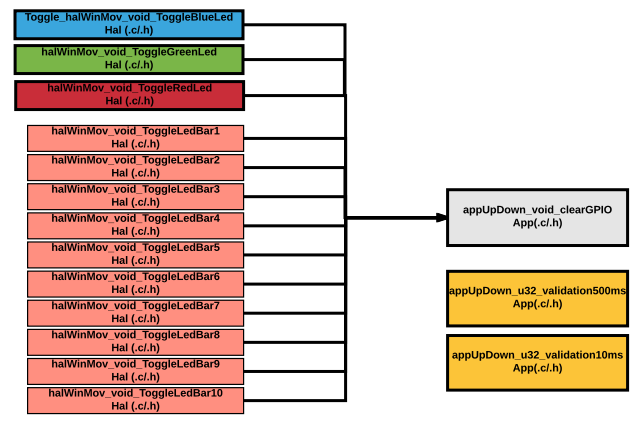
* **Validate\_Antipinch function to validate the push in Push\_Antipinch function in App.**
* **Validate\_UpButton function to validate the push in Push\_UpButton function in App.**
* **Validate\_DownButton function works to validate the push in Push\_DownButton function in App.**



* **Toggle functions execute the functionality to turn on or turn off the led’s, called by either Manual\_Up or Manual\_Down functions in App.**

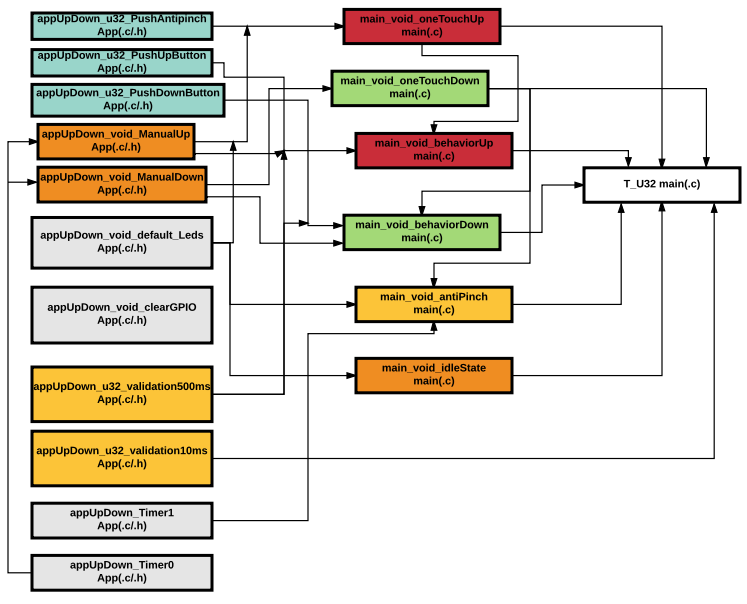


* **The Clear\_Leds function Works to condition if the leds should to be on or off.**



* **The Clear\_GPIO only Works to clear all the inputs and outputs used in the program.**

## Complete Diagram



## Functional Decomposition

## 

## 

## 

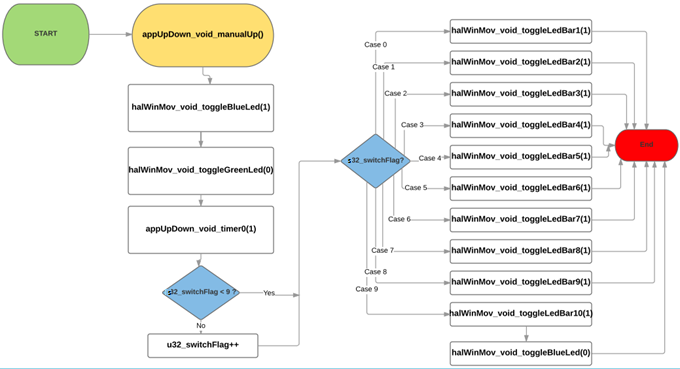
## 

* 1. **Function Description and Dynamic Behavior**

## Function void appUpDown\_void\_manualUp()

|  |  |
| --- | --- |
| **Description** | Ascending Turn on the Led Bar using a switch statement, the Led number is proportional with s32\_switchFlag value. |
| **Return Value** | void |
| **Precondition** | The s32\_switchFlag has to be set with a value [-1 to 9] |
| **Post condition** | The LedBar is turned on. |
| **Error Conditions** |  |

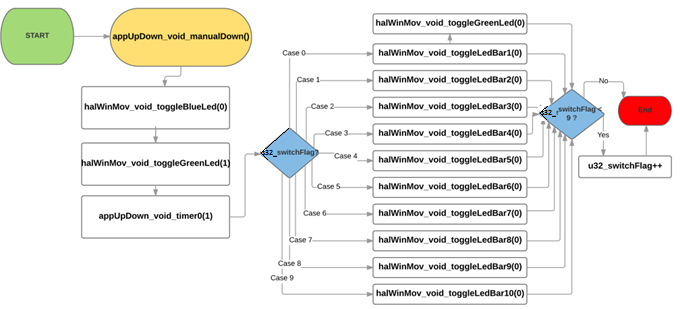
**Dynamic Behavior**

**

## Function void appUpDown\_void\_manualDown()

|  |  |
| --- | --- |
| **Description** | Descending Turn on the Led Bar using a switch statement, the Led number is proportional with s32\_switchFlag value. |
| **Return Value** | void |
| **Precondition** | The s32\_switchFlag has to be set with a value [-1 to 9] |
| **Post condition** | The ledbar is turned off. |
| **Error Conditions** |  |

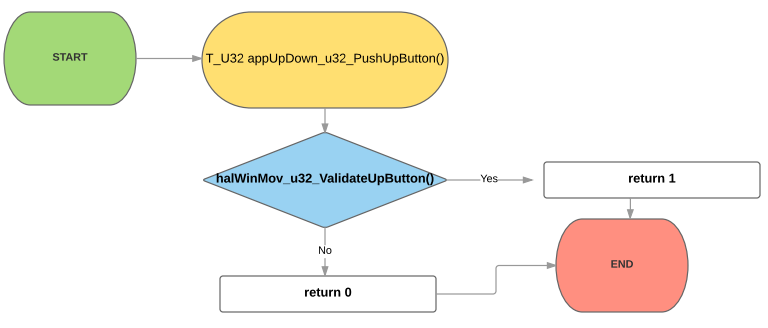
**Dynamic Behavior**



## Function T\_U32 appUpDown\_u32\_PushUpButton()

|  |  |
| --- | --- |
| **Description** | Calls halWinMov\_u32\_ValidateUpButton function, to know if the halWinMov\_u32\_ValidateUpButton()is true or false |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1 , 0 |
| **Precondition** |  |
| **Post condition** |  |
| **Error Conditions** |  |

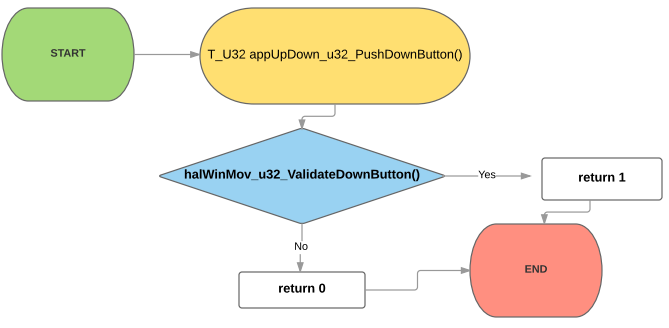
**Dynamic Behavior**



## Function T\_U32 appUpDown\_u32\_PushDownButton()

|  |  |
| --- | --- |
| **Description** | Calls Calls halWinMov\_u32\_ValidateDownButton() function, to know if the Calls halWinMov\_u32\_ValidateDownButton()is true or false |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1 , 0 |
| **Precondition** |  |
| **Post condition** |  |
| **Error Conditions** |  |

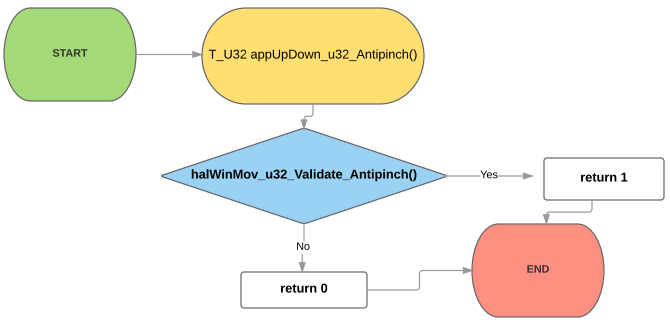
**Dynamic Behavior**



## Function T\_U32 appUpDown\_u32\_PushAntipinch()

|  |  |
| --- | --- |
| **Description** | Calls halWinMov\_u32\_ValidateAntipinch() function, to know if the halWinMov\_u32\_ValidateUpButton()is true or false |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1 , 0 |
| **Precondition** |  |
| **Post condition** |  |
| **Error Conditions** |  |

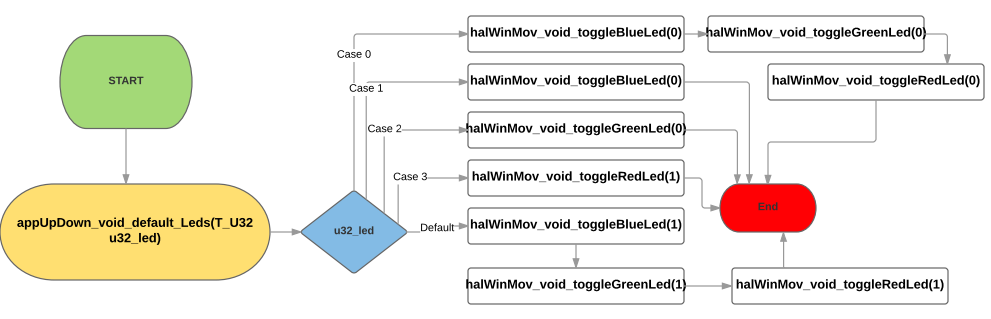
**Dynamic Behavior**



## Function void appUpDown\_void\_default\_Leds(T\_U32 led)

|  |  |
| --- | --- |
| **Description** | Using T\_U32 led, with a switch statement, select case 0,1,2,3 and default.  case 0 → Turn off Blue, Green and Red Led.  case 1 → Turn off Blue.  case 2 → Turn off Green.  case 3 → Turn on Red.  default → Turn on Blue, Green and Red Led. |
| **Parameter 1** <input| output| inout> | input T\_U32 |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** |  |
| **Post condition** |  |
| **Error Conditions** |  |

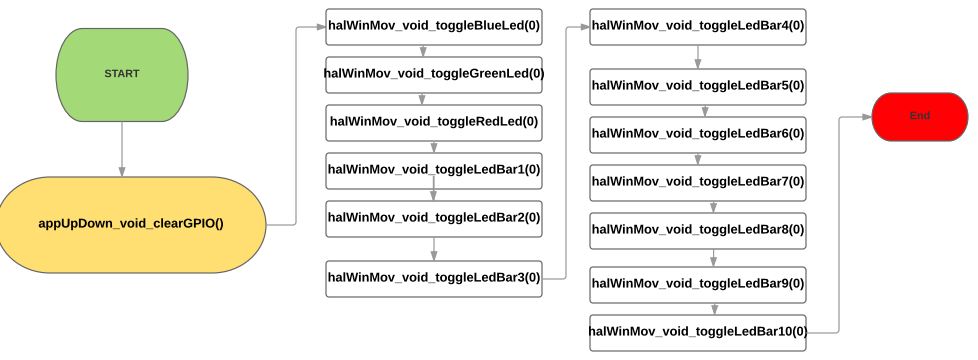
**Dynamic Behavior**



## Function void appUpDown\_void\_clearGPIO()

|  |  |
| --- | --- |
| **Description** | Turn off Blue Led, Green Led, Red Led and LedBar# |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** |  |
| **Post condition** |  |
| **Error Conditions** |  |

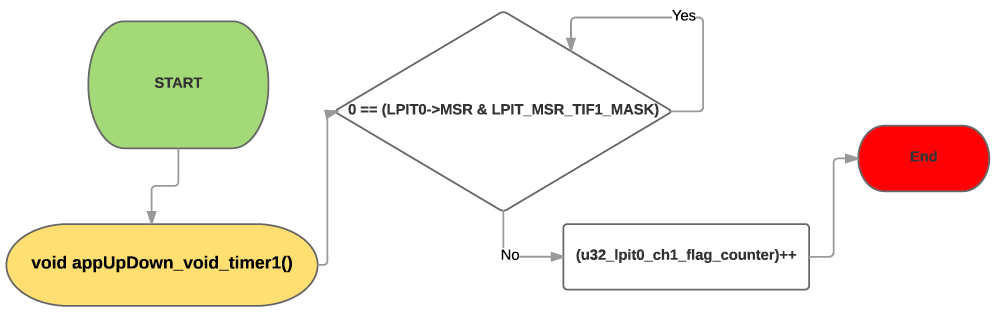
**Dynamic Behavior**



## Function void appUpDown\_void\_timer1()

|  |  |
| --- | --- |
| **Description** | After 40000 cycles has occurred increment u32\_lpit0\_ch1\_flag\_counter variable. (1 ms) |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** | The LPIT\_MSR\_TIF1\_MASK timer should be configured and initialized |
| **Post condition** | The LPIT\_MSR\_TIF1\_MASK timer has been cleared |
| **Error Conditions** |  |

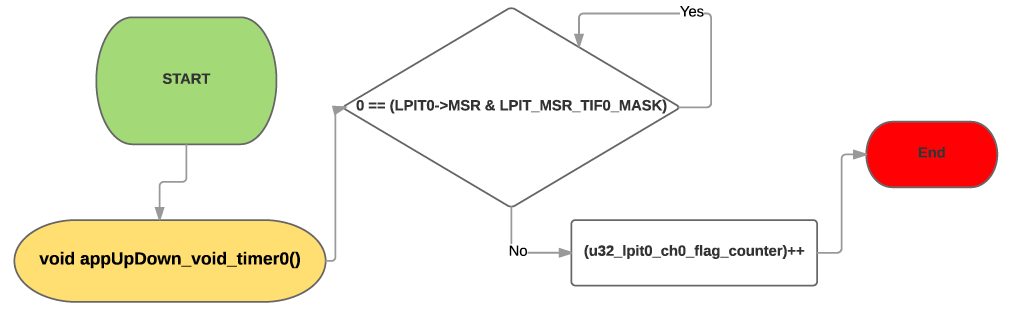
**Dynamic Behavior**



## Function void appUpDown\_void\_timer0()

|  |  |
| --- | --- |
| **Description** | After 16 000 000 cycles has occurred increment u32\_lpit0\_ch0\_flag\_counter variable. (400 ms) |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** | The LPIT\_MSR\_TIF0\_MASK timer should be configured and initialized |
| **Post condition** | The LPIT\_MSR\_TIF0\_MASK timer has been cleared |
| **Error Conditions** |  |

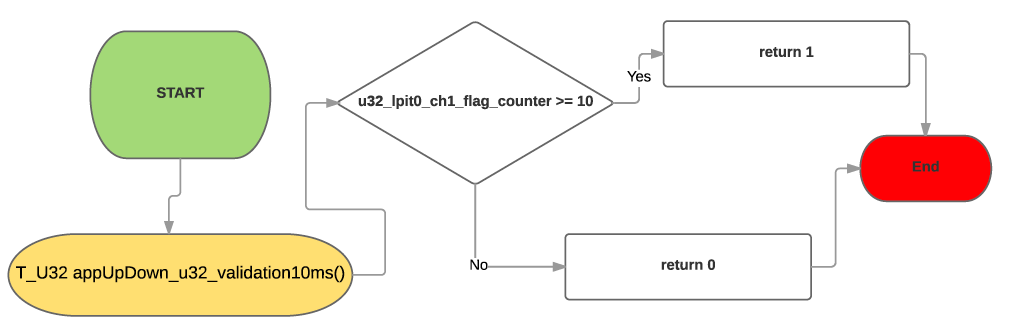
**Dynamic Behavior**



## Function T\_U32 appUpDown\_u32\_validation10ms()

|  |  |
| --- | --- |
| **Description** | Check when u32\_lpit0\_ch1\_flag\_counter is equal or higher to 10. This mean that 10 ms are occurred. |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1,0 |
| **Precondition** | The LPIT\_MSR\_TIF1\_MASK timer should be configured and initialized, u32\_lpit0\_ch0\_flag should be 0 at the beginning |
| **Post condition** |  |
| **Error Conditions** |  |

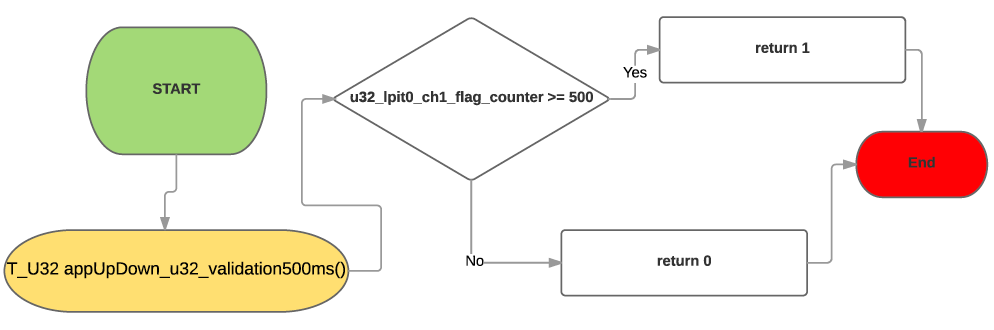
**Dynamic Behavior**



## Function T\_U32 appUpDown\_u32\_validation500ms()

|  |  |
| --- | --- |
| **Description** | Check when u32\_lpit0\_ch1\_flag\_counter is equal or higher to 500. |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1,0 |
| **Precondition** | The LPIT\_MSR\_TIF1\_MASK timer should be configured and initialized, u32\_lpit0\_ch1\_flag should be 0 at the beginning |
| **Post condition** |  |
| **Error Conditions** |  |

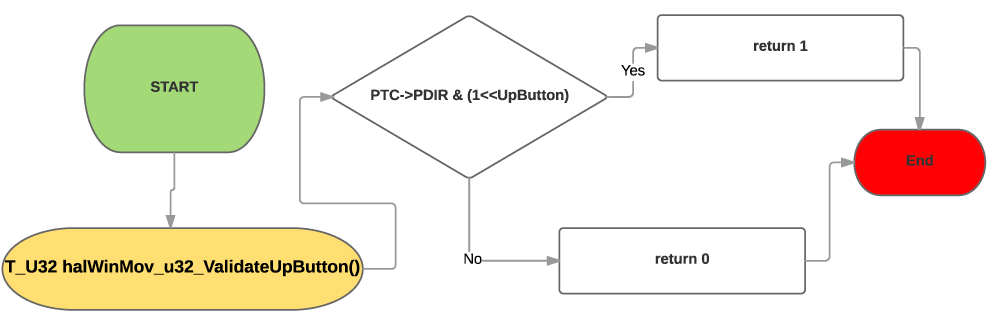
**Dynamic Behavior**



## Function T\_U32 halWinMov\_u32\_ValidateUpButton()

|  |  |
| --- | --- |
| **Description** | Check if PORT C12 value is in High or Low and returns 1 if is High and 0 if is Low |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1,0 |
| **Precondition** | The PORTD C12 should be configured as input |
| **Post condition** |  |
| **Error Conditions** |  |

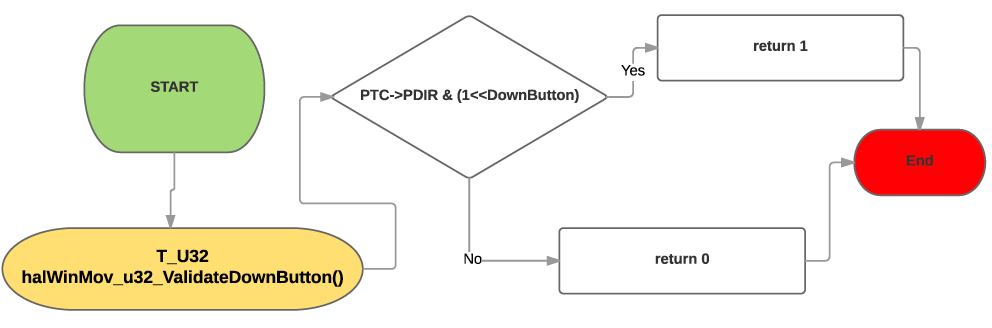
**Dynamic Behavior**



## Function T\_U32 halWinMov\_u32\_ValidateUpButton()

|  |  |
| --- | --- |
| **Description** | Check if PORT C13 value is in High or Low and returns 1 if is High and 0 if is Low |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1,0 |
| **Precondition** | The PORTD C13 should be configured as input. |
| **Post condition** |  |
| **Error Conditions** |  |

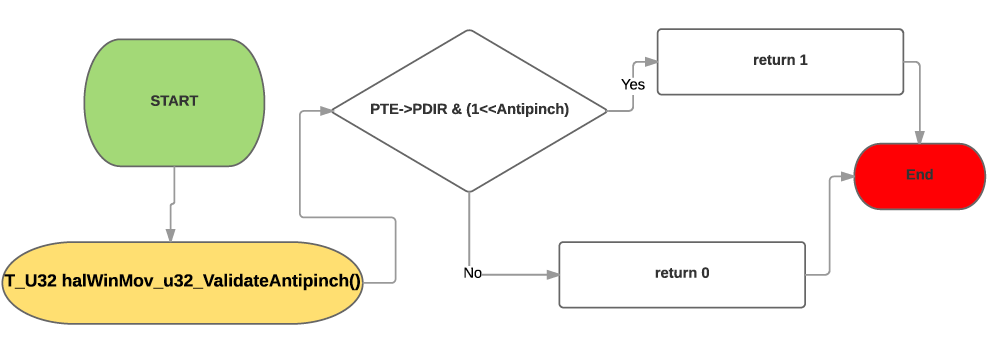
**Dynamic Behavior**



## Function T\_U32 halWinMov\_u32\_ValidateAntipinch()

|  |  |
| --- | --- |
| **Description** | Check if PORT E13 value is in High or Low and returns 1 if is High and 0 if is Low |
| **Parameter 1** <input| output| inout> |  |
| **Parameter 2..n** |  |
| **Return Value** | T\_U32 1,0 |
| **Precondition** | The PORTD E13 should be configured as input. |
| **Post condition** |  |
| **Error Conditions** |  |

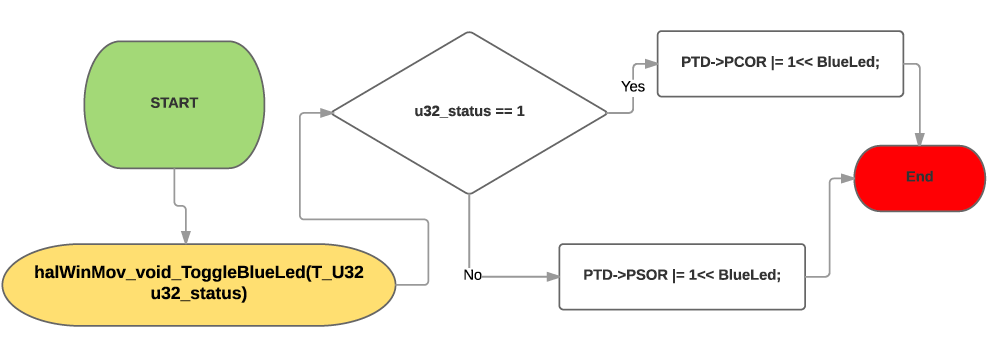
**Dynamic Behavior**



## Function void halWinMov\_void\_ToggleBlueLed(T\_U32 u32\_status)

|  |  |
| --- | --- |
| **Description** | Write in PORT D0:  - High if int status = 1.  - Low if int status = 0. |
| **Parameter 1** <input| output| inout> | Input T\_U32 u32\_status |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** | The PORTD D0 should be configured as output. |
| **Post condition** |  |
| **Error Conditions** |  |

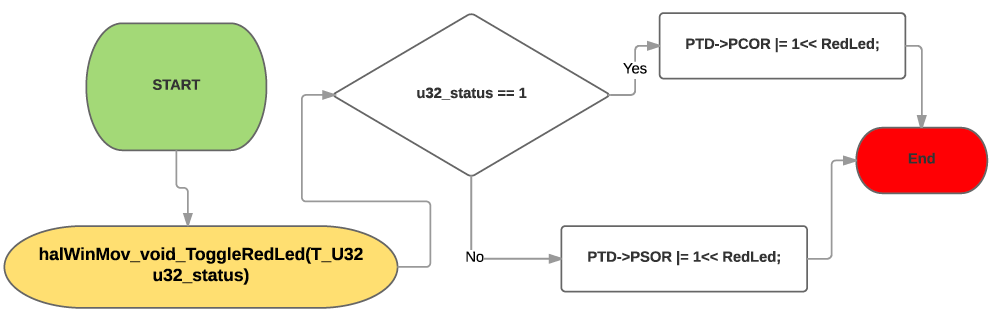
**Dynamic Behavior**



## Function void halWinMov\_void\_ToggleRedLed(T\_U32 u32\_status)

|  |  |
| --- | --- |
| **Description** | Write in PORT D15:  - High if int status = 1.  - Low if int status = 0. |
| **Parameter 1** <input| output| inout> | Input T\_U32 u32\_status |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** | The PORTD D15 should be configured as output. |
| **Post condition** |  |
| **Error Conditions** |  |

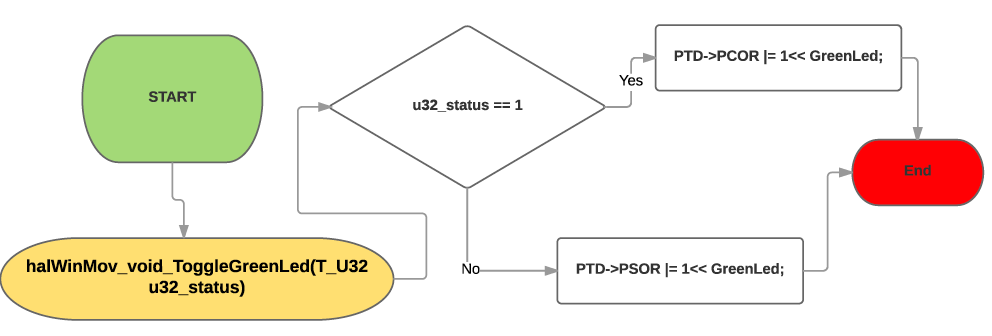
**Dynamic Behavior**



## Function void halWinMov\_void\_ToggleGreenLed(T\_U32 u32\_status)

|  |  |
| --- | --- |
| **Description** | Write in PORT D16:  - High if int status = 1.  - Low if int status = 0. |
| **Parameter 1** <input| output| inout> | Input T\_U32 u32\_status |
| **Parameter 2..n** |  |
| **Return Value** | void |
| **Precondition** | The PORTD D16 should be configured as output. |
| **Post condition** |  |
| **Error Conditions** |  |

**Dynamic Behavior**



## Function void halWinMov\_void\_ToggleLedBar#(T\_U32 u32\_status)

|  |  |  |
| --- | --- | --- |
| **Description** | Write High or Low in Led number # | |
| LedBar\_1  Write in PORT C7:  - High if int status = 1.  - Low if int status = 0.  LedBar\_2  Write in PORT B17:  - High if int status = 1.  - Low if int status = 0.  LedBar\_3  Write in PORT B14:  - High if int status = 1.  - Low if int status = 0.  LedBar\_4  Write in PORT B15:  - High if int status = 1.  - Low if int status = 0.  LedBar\_5  Write in PORT B16:  - High if int status = 1.  - Low if int status = 0. | LedBar\_6  Write in PORT C14:  - High if int status = 1.  - Low if int status = 0.  LedBar\_7  Write in PORT C3:  - High if int status = 1.  - Low if int status = 0.  LedBar\_8  Write in PORT E16:  - High if int status = 1.  - Low if int status = 0.  LedBar\_9  Write in PORT E15:  - High if int status = 1.  - Low if int status = 0.  LedBar\_10  Write in PORT E14:  - High if int status = 1.  - Low if int status = 0. |
| **Parameter 1** <input| output| inout> | Input T\_U32 u32\_status | |
| **Parameter 2..n** |  | |
| **Return Value** | void | |
| **Precondition** | Should be configured as output: | |
| PORT C7  PORT B17  PORT B14  PORT B15  PORT B16 | PORT C14  PORT C3  PORT E16  PORT E15  PORT E14 |
| **Post condition** |  | |
| **Error Conditions** |  | |

**Dynamic Behavior**

