SiWaSim

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Chapter 1

Class Index

1.1 Class List

Here are the classes, structs, unions and interfaces with brief descriptions:

Chapter 2

File Index

2.1 File List

Here is a list of all files with brief descriptions:

Chapter 3

Class Documentation

3.1 Configuration Class Reference

```
#include <Configuration.hpp>
```

Public Member Functions

- Configuration (std::string path)
- ∼Configuration ()
- void loadConfiguration ()

Public Attributes

- LoadCellMode cellMode = LoadCellMode::NORMAL

    Loadcell mode to be simulated.
- SYSTEM_TYPE systemType = SYSTEM_TYPE::NORMAL

    System type to be simulated.
- float exc_voltage = 10.f

    Nominal EXC voltage ouputted by the SIWAREX module.
- float load_weight = 20.f

    Nominal Load Weight of the cell in kg.
- float initial_weight = 10.f

    Initial weight (for manual / non-auto mode)
- float addvol_ratio = 500

    Inverted OpAmp gain (e.g.: At 10V Aout the added / subtracted voltage is 20mV --> ratio = 10V / 20mV = 500)
- float max_diff_voltage = 40

    Maximum Differential Voltage of SIG+-.
- float cellCharecteristic = 4

    Characteristic in mV/V.
- float speedAt100 = 5

    Belt velocity in m/s at 100% speed.
- float freqAt100 = 10000

    Belt encoder frequency at 100% speed.

3.1.1 Constructor & Destructor Documentation

3.1.1.1 Configuration()

```
Configuration::Configuration (
            std::string path )
```

Creates a new configuration that stores all configuration settings needed for the Simulator. IMPORTANT: Should only be created once, since there is only one valid configuration for the simulator!

Parameters

path	The path to the configuration file on the filesystem

3.1.1.2 ∼Configuration()

```
Configuration::∼Configuration ( )
```

3.1.2 Member Function Documentation

3.1.2.1 loadConfiguration()

```
void Configuration::loadConfiguration ( )
```

Loads a configuration file from the file system (specified by path in Configuration(std::string path)) and parses all settings to their respective variables

3.1.3 Member Data Documentation

3.1.3.1 addvol_ratio

```
float Configuration::addvol_ratio = 500
```

Inverted OpAmp gain (e.g.: At 10V Aout the added / subtracted voltage is 20mV --> ratio = 10V / 20mV = 500)

3.1.3.2 cellCharecteristic

```
float Configuration::cellCharecteristic = 4
```

Characteristic in mV/V.

3.1.3.3 cellMode

```
LoadCellMode Configuration::cellMode = LoadCellMode::NORMAL
```

Loadcell mode to be simulated.

3.1.3.4 exc_voltage

```
float Configuration::exc_voltage = 10.f
```

Nominal EXC voltage ouputted by the SIWAREX module.

3.1.3.5 freqAt100

```
float Configuration::freqAt100 = 10000
```

Belt encoder frequency at 100% speed.

3.1.3.6 initial_weight

```
float Configuration::initial_weight = 10.f
```

Initial weight (for manual / non-auto mode)

3.1.3.7 load_weight

```
float Configuration::load_weight = 20.f
```

Nominal Load Weight of the cell in kg.

3.1.3.8 max_diff_voltage

```
float Configuration::max_diff_voltage = 40
```

Maximum Differential Voltage of SIG+-.

3.1.3.9 speedAt100

```
float Configuration::speedAt100 = 5
```

Belt velocity in m/s at 100% speed.

3.1.3.10 systemType

```
SYSTEM_TYPE Configuration::systemType = SYSTEM_TYPE::NORMAL
```

System type to be simulated.

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/Configuration.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/Configuration.cpp

3.2 GPIO Class Reference

```
#include <GPIO.hpp>
```

Public Member Functions

- GPIO ()
- ~GPIO ()
- void setPWM (int pin, float dutyCycle, float frequency)
- void setPinMode (uint8_t pin, uint8_t mode)
- void writePin (uint8_t pin, bool state)
- bool readPin (uint8_t pin)

3.2.1 Constructor & Destructor Documentation

3.2.1.1 GPIO()

```
GPIO::GPIO ( )
```

3.2.1.2 ∼GPIO()

```
GPIO::∼GPIO ( )
```

3.2.2 Member Function Documentation

3.2.2.1 readPin()

```
bool GPIO::readPin (
             uint8_t pin )
```

3.2.2.2 setPinMode()

```
void GPIO::setPinMode (
             uint8_t pin,
             uint8_t mode )
```

3.2.2.3 setPWM()

```
void GPIO::setPWM (
             int pin,
             float dutyCycle,
             float frequency )
```

3.2.2.4 writePin()

```
void GPIO::writePin (
             uint8_t pin,
             bool state )
```

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/GPIO.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/GPIO.cpp

3.3 I2C Class Reference

```
#include <I2C.hpp>
```

Public Member Functions

- I2C (std::string dev, uint16_t address)
- ∼I2C ()
- bool begin ()
- bool writeData (uint8_t data)
- bool writeData (uint8_t ∗data, uint8_t length)
- bool readData (uint8_t ∗data, uint8_t length)
- uint8_t readData ()

3.3.1 Constructor & Destructor Documentation

3.3.1.1 I2C()

```
I2C::I2C (
            std::string dev,
            uint16_t address )
```

3.3.1.2 ∼I2C()

```
I2C::∼I2C ( )
```

3.3.2 Member Function Documentation

3.3.2.1 begin()

```
bool I2C::begin ( )
```

3.3.2.2 readData() [1/2]

```
uint8_t I2C::readData ( )
```

3.3.2.3 readData() [2/2]

```
bool I2C::readData (
             uint8_t * data,
             uint8_t length )
```

3.3.2.4 writeData() [1/2]

```
bool I2C::writeData (
             uint8_t * data,
             uint8_t length )
```

3.3.2.5 writeData() [2/2]

```
bool I2C::writeData (
             uint8_t data )
```

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/I2C.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/I2C.cpp

3.4 IABoard Class Reference

```
#include <IABoard.hpp>
```

Public Member Functions

- IABoard ()
- ∼IABoard ()
- bool detectBoard ()
- uint8_t digitalRead ()
- bool digitalRead (uint8_t channel)
- uint16_t readTransistions (uint8_t channel)
- TRANSITION getTransistionType (uint8_t channel)
- void setTransistionType (uint8_t channel, TRANSITION tran)
- void resetTransitions (uint8_t channel)
- float getAnalogVolOut (uint8_t channel)
- void setAnalogVolOut (uint8_t channel, float voltage)
- float getAnalogCurOut (uint8_t channel)
- void setAnalogCurOut (uint8_t channel, float current)
- float getOpenDrainPWM (uint8_t channel)
- void setOpenDrainPWM (uint8_t channel, float dutyCycle)
- uint8_t getOpenDrainDOUT ()
- bool getOpenDrainDOUT (uint8_t channel)
- void setOpenDrainDOUT (uint8_t channel, bool value)
- bool getLED (uint8_t channel)
- void setLED (uint8_t channel, bool value)
- void setAllLED (bool value)
- float readAnalogVolIn (uint8_t channel)
- float readAnalogVolInPM (uint8_t channel)
- float readAnalogCurIn (uint8_t channel)
- void setAllOFF ()

3.4.1 Constructor & Destructor Documentation

3.4.1.1 IABoard()

```
IABoard::IABoard ( )
```

3.4.1.2 ∼IABoard()

```
IABoard::∼IABoard ( )
```

3.4.2 Member Function Documentation

3.4.2.1 detectBoard()

```
bool IABoard::detectBoard ( )
```

3.4.2.2 digitalRead() [1/2]

```
uint8_t IABoard::digitalRead ( )
```

3.4.2.3 digitalRead() [2/2]

```
bool IABoard::digitalRead (
             uint8_t channel )
```

3.4.2.4 getAnalogCurOut()

```
float IABoard::getAnalogCurOut (
             uint8_t channel )
```

3.4.2.5 getAnalogVolOut()

```
float IABoard::getAnalogVolOut (
             uint8_t channel )
```

3.4.2.6 getLED()

```
bool IABoard::getLED (
             uint8_t channel )
```

Gets the current state of one of the on board LEDs

Parameters

channel	The LED to be read (1 - 4)

Returns

Returns the state of the LED (0 = OFF, 1 = ON)

3.4.2.7 getOpenDrainDOUT() [1/2]

```
uint8_t IABoard::getOpenDrainDOUT ( )
```

3.4.2.8 getOpenDrainDOUT() [2/2]

```
bool IABoard::getOpenDrainDOUT (
             uint8_t channel )
```

3.4.2.9 getOpenDrainPWM()

```
float IABoard::getOpenDrainPWM (
             uint8_t channel )
```

3.4.2.10 getTransistionType()

```
TRANSITION IABoard::getTransistionType (
             uint8_t channel )
```

3.4.2.11 readAnalogCurIn()

```
float IABoard::readAnalogCurIn (
             uint8_t channel )
```

Reads the Analog Input Current of a channel

Parameters

channel	The channel as marked on the IABoard-PCB (1 - 4)

Returns

Returns the measured current in mA

3.4.2.12 readAnalogVolIn()

```
float IABoard::readAnalogVolIn (
            uint8_t channel )
```

Reads the Analog Input Voltage of a channel if the jumper is not set

Parameters

channel	The channel as marked on the IABoard-PCB (1 - 4)

Returns

Returns the measured voltage in Volts from 0V to 10V

3.4.2.13 readAnalogVolInPM()

```
float IABoard::readAnalogVolInPM (
            uint8_t channel )
```

Reads the Analog Input Voltage of a channel if the jumper is set to measure negative voltages

Parameters

channel	The channel as marked on the IABoard-PCB (1 - 4)

Returns

Returns the measured voltage in Volts from -10V to 10V

3.4.2.14 readTransistions()

```
uint16_t IABoard::readTransistions (
            uint8_t channel )
```

3.4.2.15 resetTransitions()

```
void IABoard::resetTransitions (
            uint8_t channel )
```

3.4.2.16 setAllLED()

```
void IABoard::setAllLED (
            bool value )
```

Sets all IABoard-LEDs to the same state

Parameters

value	The wanted state of all the LEDs (0 = OFF, 1 = ON)

3.4.2.17 setAllOFF()

```
void IABoard::setAllOFF ( )
```

Sets all digital and analog outputs to OFF / 0V

3.4.2.18 setAnalogCurOut()

```
void IABoard::setAnalogCurOut (
            uint8_t channel,
            float current )
```

3.4.2.19 setAnalogVolOut()

```
void IABoard::setAnalogVolOut (
            uint8_t channel,
            float voltage )
```

3.4.2.20 setLED()

```
void IABoard::setLED (
            uint8_t channel,
            bool value )
```

Sets on of the four on board LEDs to a certain state

Parameters

channel	The LED to be toggled (1 - 4)
value	The wanted state of the LED (0 = OFF, 1 = ON)

3.4.2.21 setOpenDrainDOUT()

```
void IABoard::setOpenDrainDOUT (
             uint8_t channel,
             bool value )
```

Sets on of the four digital outputs

Parameters

channel	The Open Drain Pin to be toggled (1 - 4)
value	The wanted state of the channel

3.4.2.22 setOpenDrainPWM()

```
void IABoard::setOpenDrainPWM (
             uint8_t channel,
             float dutyCycle )
```

3.4.2.23 setTransistionType()

```
void IABoard::setTransistionType (
             uint8_t channel,
             TRANSITION tran )
```

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/IABoard.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/IABoard.cpp

3.5 PCB Class Reference

```
#include <PCB.hpp>
```

Public Member Functions

- PCB (Configuration ∗config)
- ∼PCB ()
- void ledFault (bool state)
- void ledBusy (bool state)
- void ledReady (bool state)
- void setImpedance (IMPEDANCE impedance)
- void setEXTRASW1 (bool state)
- void setEXTRASW2 (bool state)
- void setPOWERSW1 (bool state)
- void setPOWERSW2 (bool state)
- void setLoadcellVoltage (float voltage)
- void setLoadcellDCVoltage (float voltage)
- void setSENVoltage (float voltage)
- float getEXCVoltage ()
- float getSENVoltage ()
- void setPWM (float frequency, float dutyCycle)
- void reloadConfig ()

3.5.1 Constructor & Destructor Documentation

3.5.1.1 PCB()

```
PCB::PCB (
            Configuration ∗ config )
```

3.5.1.2 ∼PCB()

```
PCB::∼PCB ( )
```

3.5.2 Member Function Documentation

3.5.2.1 getEXCVoltage()

```
float PCB::getEXCVoltage ( )
```

3.5.2.2 getSENVoltage()

```
float PCB::getSENVoltage ( )
```

3.5.2.3 ledBusy()

```
void PCB::ledBusy (
             bool state )
```

3.5.2.4 ledFault()

```
void PCB::ledFault (
             bool state )
```

3.5.2.5 ledReady()

```
void PCB::ledReady (
             bool state )
```

3.5.2.6 reloadConfig()

```
void PCB::reloadConfig ( )
```

3.5.2.7 setEXTRASW1()

```
void PCB::setEXTRASW1 (
             bool state )
```

3.5.2.8 setEXTRASW2()

```
void PCB::setEXTRASW2 (
             bool state )
```

3.5.2.9 setImpedance()

```
void PCB::setImpedance (
            IMPEDANCE impedance )
```

3.5.2.10 setLoadcellDCVoltage()

```
void PCB::setLoadcellDCVoltage (
            float voltage )
```

3.5.2.11 setLoadcellVoltage()

```
void PCB::setLoadcellVoltage (
            float voltage )
```

3.5.2.12 setPOWERSW1()

```
void PCB::setPOWERSW1 (
            bool state )
```

3.5.2.13 setPOWERSW2()

```
void PCB::setPOWERSW2 (
            bool state )
```

3.5.2.14 setPWM()

```
void PCB::setPWM (
            float frequency,
            float dutyCycle )
```

3.5.2.15 setSENVoltage()

```
void PCB::setSENVoltage (
             float voltage )
```

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/PCB.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/PCB.cpp

3.6 Simulator Class Reference

```
#include <Simulator.hpp>
```

Public Member Functions

- Simulator ()
- ∼Simulator ()
- void setWeightPER (float percentage)
- void setWeightKG (float kg)
- void setVelocity (float meterspersecond)
- void setVelocityPER (float percentage)
- void setVelocityFRQ (float frequency)
- void bootupAnimation ()
- void loadConfig ()

3.6.1 Constructor & Destructor Documentation

3.6.1.1 Simulator()

```
Simulator::Simulator ( )
```

3.6.1.2 ∼Simulator()

```
Simulator::∼Simulator ( )
```

3.6.2 Member Function Documentation

3.6.2.1 bootupAnimation()

```
void Simulator::bootupAnimation ( )
```

Starts an animation with the on board LEDs

3.6.2.2 loadConfig()

```
void Simulator::loadConfig ( )
```

3.6.2.3 setVelocity()

```
void Simulator::setVelocity (
             float metserspersecond )
```

Sets the simulated belt velocity in meters per second

Parameters

meterspersecond	Velocity in meters / second

3.6.2.4 setVelocityFRQ()

```
void Simulator::setVelocityFRQ (
             float frequency )
```

Sets the PWM output to a certain frequency to represent belt movement

Parameters

frequency	The frequency of the PWM signal

3.6.2.5 setVelocityPER()

```
void Simulator::setVelocityPER (
             float percentage )
```

Sets the simulated belt velocity from 0 - 100% of the maximal speed

Parameters

percentage	Percentage of the maximal speed from 0 to 1

3.6.2.6 setWeightKG()

```
void Simulator::setWeightKG (
            float kg )
```

Set the output weight of the simulated load cell in kg

Parameters

kg	Output weight in kilograms

3.6.2.7 setWeightPER()

```
void Simulator::setWeightPER (
            float percentage )
```

Set the output weight as a percentage of the nominal load

Parameters

percentage	Percentage from 0 - 1 where 1 represents the nominal load as specified

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/Simulator.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/Simulator.cpp

3.7 UART Class Reference

```
#include <UART.hpp>
```

Public Member Functions

- UART ()
- ~UART ()
- bool begin ()
- bool transmitMSG (uint8_t ∗msg, uint16_t length)
- std::vector< uint8_t > receiveMSG ()

3.7.1 Constructor & Destructor Documentation

3.7.1.1 UART()

```
UART::UART ( )
```

3.7.1.2 ∼UART()

```
UART::∼UART ( )
```

3.7.2 Member Function Documentation

3.7.2.1 begin()

```
bool UART::begin ( )
```

3.7.2.2 receiveMSG()

```
std::vector< uint8_t > UART::receiveMSG ( )
```

3.7.2.3 transmitMSG()

```
bool UART::transmitMSG (
            uint8_t * msg,
            uint16_t length )
```

The documentation for this class was generated from the following files:

- F:/GITHUB/SiWaSIM-PiSoftware/src/UART.hpp
- F:/GITHUB/SiWaSIM-PiSoftware/src/UART.cpp

Chapter 4

File Documentation

4.1 F:/GITHUB/SiWaSIM-PiSoftware/src/Configuration.cpp File Reference

```
#include "Configuration.hpp"
```

4.2 F:/GITHUB/SiWaSIM-PiSoftware/src/Configuration.hpp File Reference

```
#include <string>
#include <iostream>
#include <fstream>
#include "nlohmann/json.hpp"
```

Classes

- class Configuration

Typedefs

- using json = nlohmann::json

Enumerations

- enum LoadCellMode { NORMAL = 0x00 , OVERLOAD = 0x01 , INVERTED = 0x02 }
- enum IMPEDANCE { OPEN = 0x00 , NOMINAL = 0x01 , SHORT = 0x02 }
- enum SYSTEM_TYPE { DOSING_SCALE = 0x01 , BELT_SCALE = 0x02 }

4.2.1 Typedef Documentation

4.2.1.1 json

```
using json = nlohmann::json
```

4.2.2 Enumeration Type Documentation

4.2.2.1 IMPEDANCE

```
enum IMPEDANCE
```

Types of impedances of the load cell that can be simulated. Is equivilant with the impedance between EXC+ and EXC-

Enumerator

OPEN	Open circuit, high impedance.
NOMINAL	Nominal impedance of approx. 350 ohms.
SHORT	Short circuit, approx. zero impedance.

4.2.2.2 LoadCellMode

```
enum LoadCellMode
```

Enumerator

NORMAL	Positive differential voltage from 0 - 100% nominal load.
OVERLOAD	Positive differential voltage from 0 - 120% nominal load.
INVERTED	Negative differential voltage from 0 - 100% nominal load.

4.2.2.3 SYSTEM_TYPE

```
enum SYSTEM_TYPE
```

Type of the system represented by the simulator

Enumerator

DOSING_SCALE	Dosing Scale.
BELT_SCALE	Belt Scale.

4.3 Configuration.hpp

Go to the documentation of this file.

```
#pragma once
#include <string>
#include <iostream>
#include <fstream>
#include "nlohmann/json.hpp"

using json = nlohmann::json;

enum LoadCellMode
{
    NORMAL = 0x00,
    OVERLOAD = 0x01,
    INVERTED = 0x02,

} typedef LoadCellMode;

enum IMPEDANCE
{
    OPEN = 0x00,
    NOMINAL = 0x01,
    SHORT = 0x02,

} typedef IMPEDANCE;

enum SYSTEM_TYPE
{
    DOSING_SCALE = 0x01,
    BELT_SCALE = 0x02,
} typedef SYSTEM_TYPE;

class Configuration
{
public:
    Configuration(std::string path);
    ~Configuration();

    void loadConfiguration();

    // SETTING VARIABLES
    LoadCellMode cellMode = LoadCellMode::NORMAL;
    SYSTEM_TYPE systemType = SYSTEM_TYPE::NORMAL;
    float exc_voltage = 10.f;
    float load_weight = 20.f;
    float initial_weight = 10.f;
    float addvol_ratio = 500;
    float max_diff_voltage = 40;
    float cellCharecteristic = 4;
    float speedAt100 = 5;
    float freqAt100 = 10000;

private:
    void parseJSON();
    std::string _path;
};
```

4.4 F:/GITHUB/SiWaSIM-PiSoftware/src/GPIO.cpp File Reference

```
#include "GPIO.hpp"
```

4.5 F:/GITHUB/SiWaSIM-PiSoftware/src/GPIO.hpp File Reference

```
#include <signal.h>
#include <pigpio.h>
#include <stdint.h>
#include <cstdio>
```

Classes

- class GPIO

4.6 GPIO.hpp

Go to the documentation of this file.

```
#pragma once
#include <signal.h>
#include <pigpio.h>
#include <stdint.h>
#include <cstdio>

class GPIO
{
public:
    GPIO();
    ~GPIO();
    void setPWM(int pin, float dutyCycle, float frequency);

    void setPinMode(uint8_t pin, uint8_t mode);

    void writePin(uint8_t pin, bool state);
    bool readPin(uint8_t pin);

private:
};
```

4.7 F:/GITHUB/SiWaSIM-PiSoftware/src/I2C.cpp File Reference

```
#include "I2C.hpp"
```

4.8 F:/GITHUB/SiWaSIM-PiSoftware/src/I2C.hpp File Reference

```
#include <stdio.h>
#include <unistd.h>
#include <string>
#include <stdint.h>
#include <sys/stat.h>
#include <fcntl.h>
#include <sys/ioctl.h>
#include <linux/i2c.h>
#include <linux/i2c-dev.h>
```

Classes

- class I2C

4.9 I2C.hpp

Go to the documentation of this file.

```
#pragma once
#include <stdio.h>
#include <unistd.h>
#include <string>
#include <stdint.h>
#include <sys/stat.h>
#include <fcntl.h>
#include <sys/ioctl.h>
#include <linux/i2c.h>
#include <linux/i2c-dev.h>

class I2C
{
public:
   I2C(std::string dev, uint16_t address);
   ~I2C();
   bool begin();
   bool writeData(uint8_t data);
   bool writeData(uint8_t *data, uint8_t length);
   bool readData(uint8_t *data, uint8_t length);
   uint8_t readData();

private:
   std::string _dev;
   uint16_t _address;
   int i2c0 = -1;
};
```

4.10 F:/GITHUB/SiWaSIM-PiSoftware/src/IABoard.cpp File Reference

```
#include "IABoard.hpp"
```

4.11 F:/GITHUB/SiWaSIM-PiSoftware/src/IABoard.hpp File Reference

```
#include "I2C.hpp"
#include "utility.hpp"
#include <chrono>
#include <thread>
#include <iostream>
```

Classes

- class IABoard

Macros

- #define I2C_ADDRESS 0x50

Enumerations

- enum TRANSITION {
  DISABLE = 0x00 , RISING = 0x01 , FALLING = 0x02 , BOTH = 0x03 ,
  UNDEFINED = 0x04 }

4.11.1 Macro Definition Documentation

4.11.1.1 I2C_ADDRESS

```
#define I2C_ADDRESS 0x50
```

4.11.2 Enumeration Type Documentation

4.11.2.1 TRANSITION

```
enum TRANSITION
```

Enumerator

DISABLE	
RISING	
FALLING	
BOTH	
UNDEFINED	

4.12 IABoard.hpp

Go to the documentation of this file.

```
#pragma once
#include "I2C.hpp"
#include "utility.hpp"
#include <chrono>
#include <thread>
#include <iostream>
using namespace std::chrono_literals;

#define I2C_ADDRESS 0x50

enum TRANSITION
{
   DISABLE = 0x00,
   RISING = 0x01,
   FALLING = 0x02,
   BOTH = 0x03,
   UNDEFINED = 0x04
} typedef TRANSITION;

class IABoard
{
public:
   IABoard();
   ~IABoard();

   // Check if the board is responding
   bool detectBoard();

   // Read all digital inputs
   uint8_t digitalRead();
```

```
    // Read digital input of certain channel 1 - 4
    bool digitalRead(uint8_t channel);

    // Reads the number of counted transitions (if enabled)
    uint16_t readTransistions(uint8_t channel);
    // Reads th ecurrently set transition type
    TRANSITION getTransistionType(uint8_t channel);
    // Sets the type of transistions that should be counted
    void setTransistionType(uint8_t channel, TRANSITION tran);
    // Sets the transistion counter of a channel to 0
    void resetTransitions(uint8_t channel);

    // Get the currently set analog output voltage
    float getAnalogVolOut(uint8_t channel);
    // Set the analog output voltage from 0 - 10V, voltage in volts
    void setAnalogVolOut(uint8_t channel, float voltage);

    // Get the currently set analog output current
    float getAnalogCurOut(uint8_t channel);
    // Set the analog output current from 4 - 20mA, current in mA
    void setAnalogCurOut(uint8_t channel, float current);

    // Get the PWM Duty Cycle for the Open Drain Output (if not used as digital out)
    float getOpenDrainPWM(uint8_t channel);
    // Set the PWM Duty Cycle (0 - 100%) for the Open Drain Output
    void setOpenDrainPWM(uint8_t channel, float dutyCycle);

    // Read all digital open drain outputs
    uint8_t getOpenDrainDOUT();
    // Get the currently set open drain digital out value
    bool getOpenDrainDOUT(uint8_t channel);
    // Set the digital open drain output
    void setOpenDrainDOUT(uint8_t channel, bool value);

    // Gets the state of a certain LED
    bool getLED(uint8_t channel);
    // Sets a certain LED Low or High
    void setLED(uint8_t channel, bool value);
    // Sets all LEDs ON or OFF
    void setAllLED(bool value);

    // Reads the analog input voltage of a certain channel (0-10V)
    float readAnalogVolIn(uint8_t channel);
    // Reads the analog input voltage of a certain channel (-10-10V, Jumper set)
    float readAnalogVolInPM(uint8_t channel);

    // Reads the analog input current of a certain channel (4-20mA)
    float readAnalogCurIn(uint8_t channel);

    // Turn all digital and analog outputs off
    void setAllOFF();

private:
    I2C *_i2c;

    // Delay because the IA-Board can only handle commands every few ms
    std::chrono::milliseconds _delayBetweenCommands = 9ms;
    std::chrono::time_point<std::chrono::system_clock, std::chrono::duration<double» _lastCommand;

    // Wait till the minimum time between commands has elapsed
    void waitForIA();
};
```

4.13 F:/GITHUB/SiWaSIM-PiSoftware/src/main.cpp File Reference

```
#include <iostream>
#include <string>
#include <stdio.h>
#include <stdlib.h>
#include <vector>
#include "I2C.hpp"
#include "UART.hpp"
#include "GPIO.hpp"
#include "IABoard.hpp"
#include "PCB.hpp"
#include "Simulator.hpp"
```

Functions

- int main ()

4.13.1 Function Documentation

4.13.1.1 main()

```
int main ( )
```

4.14 F:/GITHUB/SiWaSIM-PiSoftware/src/PCB.cpp File Reference

```
#include "PCB.hpp"
```

4.15 F:/GITHUB/SiWaSIM-PiSoftware/src/PCB.hpp File Reference

```
#include "utility.hpp"
#include "GPIO.hpp"
#include "IABoard.hpp"
#include "Configuration.hpp"
```

Classes

- class PCB

Macros

- #define PIN_LED_READY 23
- #define PIN_LED_BUSY 24
- #define PIN_LED_FAULT 25
- #define PWM_PIN 13
- #define PIN_POWERSW1 4
- #define PIN_POWERSW2 26
- #define PIN_IMPEDANCE1 5
- #define PIN_IMPEDANCE2 6
- #define PIN_EXTRASW1 27
- #define PIN_EXTRASW2 22
- #define ADDVOL_CHANNEL 2
- #define SUBVOL_CHANNEL 3
- #define CELL_DC 1
- #define SEN_OUT 4
- #define EXC_IN 1
- #define SEN_IN 2

4.15.1 Macro Definition Documentation

4.15.1.1 ADDVOL_CHANNEL

```
#define ADDVOL_CHANNEL 2
```

4.15.1.2 CELL_DC

```
#define CELL_DC 1
```

4.15.1.3 EXC_IN

```
#define EXC_IN 1
```

4.15.1.4 PIN_EXTRASW1

```
#define PIN_EXTRASW1 27
```

4.15.1.5 PIN_EXTRASW2

```
#define PIN_EXTRASW2 22
```

4.15.1.6 PIN_IMPEDANCE1

```
#define PIN_IMPEDANCE1 5
```

4.15.1.7 PIN_IMPEDANCE2

```
#define PIN_IMPEDANCE2 6
```

4.15.1.8 PIN_LED_BUSY

```
#define PIN_LED_BUSY 24
```

4.15.1.9 PIN_LED_FAULT

```
#define PIN_LED_FAULT 25
```

4.15.1.10 PIN_LED_READY

```
#define PIN_LED_READY 23
```

4.15.1.11 PIN_POWERSW1

```
#define PIN_POWERSW1 4
```

4.15.1.12 PIN_POWERSW2

```
#define PIN_POWERSW2 26
```

4.15.1.13 PWM_PIN

```
#define PWM_PIN 13
```

4.15.1.14 SEN_IN

```
#define SEN_IN 2
```

4.15.1.15 SEN_OUT

```
#define SEN_OUT 4
```

4.15.1.16 SUBVOL_CHANNEL

```
#define SUBVOL_CHANNEL 3
```

4.16 PCB.hpp

Go to the documentation of this file.

```
#pragma once
#include "utility.hpp"
#include "GPIO.hpp"
#include "IABoard.hpp"
#include "Configuration.hpp"

// LED Pins
#define PIN_LED_READY 23
#define PIN_LED_BUSY 24
#define PIN_LED_FAULT 25

// PWM Pin
#define PWM_PIN 13

// 24V Power Switch Pins
#define PIN_POWERSW1 4
#define PIN_POWERSW2 26

// Pins for Impedance switching
#define PIN_IMPEDANCE1 5
#define PIN_IMPEDANCE2 6

// Pins for extra switches (e.g. WebServer, WriteProtect)
#define PIN_EXTRASW1 27
#define PIN_EXTRASW2 22

// Analog Channels
#define ADDVOL_CHANNEL 2
#define SUBVOL_CHANNEL 3
#define CELL_DC 1
#define SEN_OUT 4
#define EXC_IN 1
#define SEN_IN 2

class PCB
{
public:
   PCB(Configuration *config);
   ~PCB();

   void ledFault(bool state);
   void ledBusy(bool state);
   void ledReady(bool state);

   void setImpedance(IMPEDANCE impedance);

   void setEXTRASW1(bool state);
   void setEXTRASW2(bool state);

   void setPOWERSW1(bool state);
   void setPOWERSW2(bool state);

   void setLoadcellVoltage(float voltage);
   void setLoadcellDCVoltage(float voltage);
   void setSENVoltage(float voltage);

   float getEXCVoltage();
   float getSENVoltage();

   void setPWM(float frequency, float dutyCycle);

   void reloadConfig();

private:
   GPIO *_gpio;
   IABoard *_ia;
   Configuration *_config;
};
```

4.17 F:/GITHUB/SiWaSIM-PiSoftware/src/Simulator.cpp File Reference

```
#include "Simulator.hpp"
```

4.18 F:/GITHUB/SiWaSIM-PiSoftware/src/Simulator.hpp File Reference

```
#include "PCB.hpp"
#include "Configuration.hpp"
#include "IABoard.hpp"
#include <chrono>
#include <thread>
```

Classes

- class Simulator

Macros

- #define CONFIG_PATH "/home/siwasim/SiWaSIM-PiSoftware/Konfiguration/config.json"

4.18.1 Macro Definition Documentation

4.18.1.1 CONFIG_PATH

```
#define CONFIG_PATH "/home/siwasim/SiWaSIM-PiSoftware/Konfiguration/config.json"
```

4.19 Simulator.hpp

Go to the documentation of this file.

```
#pragma once
#include "PCB.hpp"
#include "Configuration.hpp"
#include "IABoard.hpp"
#include <chrono>
#include <thread>

using namespace std::chrono_literals;

#define CONFIG_PATH "/home/siwasim/SiWaSIM-PiSoftware/Konfiguration/config.json"

class Simulator
{
public:
   Simulator();
   ~Simulator();

   void setWeightPER(float percentage); // Set the weight from 0 - 100% of nominal Load
   void setWeightKG(float kg);          // Set the weight in kg
```

```

    void setVelocity(float meterspersecond);
    void setVelocityPER(float percentage);
    void setVelocityFRQ(float frequency);

    void bootupAnimation();
    void loadConfig();

private:
    Configuration *_config;
    PCB *_pcb;
    IABoard *_ia;
};
```

4.20 F:/GITHUB/SiWaSIM-PiSoftware/src/UART.cpp File Reference

```
#include "UART.hpp"
```

4.21 F:/GITHUB/SiWaSIM-PiSoftware/src/UART.hpp File Reference

```
#include <stdint.h>
#include <fcntl.h>
#include <iostream>
#include <sstream>
#include <termios.h>
#include <unistd.h>
#include <vector>
```

Classes

- class UART

4.22 UART.hpp

Go to the documentation of this file.

```
#pragma once
#include <stdint.h>
#include <fcntl.h>
#include <iostream>
#include <sstream>
#include <termios.h>
#include <unistd.h>
#include <vector>

class UART
{
public:
    UART();
    ~UART();
    bool begin();
    bool transmitMSG(uint8_t *msg, uint16_t length);
    std::vector<uint8_t> receiveMSG();

private:
    int uart0 = -1;
    // std::string _dev;
    const uint8_t _messageSizeRX = 0;      // Number of bytes to wait for
    const uint8_t _messageTimeoutRX = 50; // Read Timeout in 0.1s steps
};
```

4.23 F:/GITHUB/SiWaSIM-PiSoftware/src/utility.cpp File Reference

```
#include "utility.hpp"
```

Functions

- float constrainMinMax (float value, float min, float max)
- float constrainMin (float value, float min)
- float constrainMax (float value, float max)

4.23.1 Function Documentation

4.23.1.1 constrainMax()

```
float constrainMax (
            float value,
            float max )
```

Constrain a value to an upper limit if the value is above that limit

Parameters

value	The value to be clipped
max	The upper limit

Returns

Returns the clipped / constrained value

4.23.1.2 constrainMin()

```
float constrainMin (
            float value,
            float min )
```

Constrain a value to a lower limit if the value is below that limit

Parameters

value	The value to be clipped
min	The lower limit

Returns

Returns the clipped / constrained value

4.23.1.3 constrainMinMax()

```
float constrainMinMax (
            float value,
            float min,
            float max )
```

Constrain a value between an upper and a lower limit to clip the value

Parameters

value	The value to be clipped
min	The lower limit
max	The upper limit

Returns

Returns the clipped / constrained value

4.24 F:/GITHUB/SiWaSIM-PiSoftware/src/utility.hpp File Reference

Functions

- float constrainMinMax (float value, float min, float max)
- float constrainMin (float value, float min)
- float constrainMax (float value, float max)

4.24.1 Function Documentation

4.24.1.1 constrainMax()

```
float constrainMax (
            float value,
            float max )
```

Constrain a value to an upper limit if the value is above that limit

Parameters

value	The value to be clipped
max	The upper limit

Returns

Returns the clipped / constrained value

4.24.1.2 constrainMin()

```
float constrainMin (
             float value,
             float min )
```

Constrain a value to a lower limit if the value is below that limit

Parameters

value	The value to be clipped
min	The lower limit

Returns

Returns the clipped / constrained value

4.24.1.3 constrainMinMax()

```
float constrainMinMax (
             float value,
             float min,
             float max )
```

Constrain a value between an upper and a lower limit to clip the value

Parameters

value	The value to be clipped
min	The lower limit
max	The upper limit

Returns

Returns the clipped / constrained value

4.25 utility.hpp

Go to the documentation of this file.

```
#pragma once

float constrainMinMax(float value, float min, float max);
float constrainMin(float value, float min);
float constrainMax(float value, float max);
```

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