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ELEC 327 MSP430G2553 IR Motor Control

**System Concept and Design:**

The concept of our project is simple in theory but a bit more complicated in practice. We would be exploring the use of motors and infrared signal detection with an MSP430; concepts that we have not really covered extensively. We had planned on having these 3 stages of development for the project:

1. Vehicle motors driven by MSP430 after reading signals from an IR remote
2. Remote activating a self-roaming mode with vehicle utilizing ultrasonic range finder to avoid obstacles and reroute
3. Creating our own IR remote with a potentiometer as wheel; LEDS and speakers to pimp out the vehicle

Our minimal viable product would be development stage #1, as the requirements for this project were to incorporate motion control. Stage 2 of development would have been a cool feature to have that adds extra value. Stage 3 would just be for uniqueness and pride.

**System Architecture:**

**IR Detection:**

Materials:

1. 21 Button NEC IR remote: <http://www.adafruit.com/products/389>
2. IR Sensor TSOP38238: <http://www.digikey.com/product-detail/en/TSOP38238/751-1227-ND/1681362>

The majority of infrared (IR) controllers transmit a digital code using a 38 kHz IR signal. There are some that transmit at 40 kHz, but the 21 button remote we were using transmitted at 38 kHz using an NEC code output with a 940nm IR LED.

We used an IR receiver that came in a 3-pin package. By simply connecting VCC (+2.5V to +5.5V) to pin 3 and GND to pin 2, we were able to get a signal out on pin 1. The IR Receiver, we were using was the TSOP38238 ([Datasheet](http://www.adafruit.com/datasheets/tsop382.pdf)) but any IR receiver will work as long as it is able to detect IR signals at the 940nm wavelength.

When any button is pressed the data sequence begins as follows:

1. A low pulse ~9.2ms wide starts the sequence.
2. The first data pulse follows ~4.4ms later.
3. Data pulses are low pulses ~0.74ms wide.

The spacing before the next data pulse determines whether the bit is zero or one.

* For a "zero," the spacing to the next pulse is ~1.2ms
* For a "one," the spacing to the next pulse is ~2.4ms

The total number of bits transmitted is either 32 or 64 bits; but in our case it is 32 bits.  
There are four ways of interpreting the bits received:

1. We can consider short time spacing between clocks (1.2ms) to be "zero" and long intervals (2.4ms) to be "one".
2. Or we can invert the logic of each bit with 1.2ms to be a “one” and 2.4ms to be “zero”
3. We can choose if the first bit received is the least significant bit (LSB) of the data stream.
4. Or we can choose the first bits to be the most significant bit (MSB) of the data stream.

The difficult part was to come up with a mechanism in order to capture and decode the received data stream. I decided to use the MSP430G2553’s timer modules to be able to precisely record and decode the IR signals. The timer module has some great functionality that we will exploit:

* Input capture - This feature allows us to take a time stamp of when an external event occurs. The trigger can be a rising edge, a falling edge or both rising and falling edges of an input signal.
* Output compare - We can set a timer register to a specific count and an interrupt is generated when the timer register reaches this preset count.

Because I am using an IR remote, the input capture mode would be what I want as I want to be able to capture the rising and falling edges of the IR signal. The input capture will be able to determine the time between successive falling edges and from that I will be able to decode the “zeros” and “ones” in the data stream. But because I want to be able to know when the end of one data stream ends and when another one begins, I will also have to use the output compare. The output compare will create a timeout when there are no falling edges appearing within ~120ms, so I know that a signal has completed and I can stop reading and do not accidently combine 2 IR signals together.

The MSP430G2553 has two timer modules, TIMER0 and TIMER1. I am going to use 2 interrupt vectors assigned to TIMER0 for reading and decoding IR signals. TIMER0\_A0\_VECTOR is used when the Capture/Compare interrupt flag CCIFG in register TA0CCTL0 is set. TIMER0\_A1\_VECTOR is used for all other interrupts, including CCIFG in TA0CCTL1, CCIFG in TA0CCTL2 and TAIFG in TA0CTL.

In this case, TA0IV is used as an efficient interrupt priority encoder in order to process multiple interrupts. If TA0IV = 0x02, capture or compare associated with register TA0CCR1 occurred and interrupt flag CCIFG in TA0CCTL1 is set. If TA0IV = 0x04, capture or compare associated with register TA0CCR2 occurred and interrupt flag CCIFG in TA0CCTL2 is set. If TA0IV = 0x0A, timer register TA0R overflow occurred and interrupt flag TAIFG in TA0CTL is set. When servicing TIMER0\_A1 interrupts, the TA0IV register must be read in order to clear the interrupt request flags.  
  
TIMER0 Input Capture0 is assigned to port P1.1 (pin-3). We connect the output of the IR Sensor Module to this pin. We initialize the hardware to use P1.1 as Input Capture whenever a falling edge is detected. We use TIMER0\_A1\_VECTOR to process a timeout condition to tell us that the data transmission has ended. Since we are using P1.1 as the input pin, we have already assigned TA0CCR0 to be the input capture register, so we cannot use that the default timeout counter. Hence we have to use the timer in the CONTINUOUS COUNT mode and will stop the timer when the timeout is reached.

The basic MCU internal clock is 1MHz. The timer is configured with a divide-by-8 prescaler, such that each timer count represents 8μs.  
LED1 at P1.0 (pin-2) is used as an indicator when data is being received. LED1 goes off when the timeout has occurred.  
The TIMEOUT has been set for about 120ms to avoid repeated action when the key is held down continuously.