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1  #include "interrupt.h"
2  //按键
3  //UART
4  //捕获
5  //eeprom读写
6
7  #define PA15_FREQ 1000000
8  #define PB4_FREQ 1000000
9
10 struct keys key[4] = {0};
11
12 char rx_array[50];
13 char rx_data;
14 char rx_pointer;
15
16 uint PA15_freq, PA15_duty, PA15_rise, PA15_fall;
17 uint PB4_freq, PB4_duty, PB4_rise, PB4_fall;
18 uint PB4_flag = 0;
19
20 void HAL_TIM_IC_CaptureCallback(TIM_HandleTypeDef *htim)
21 {
22     if(htim->Instance == TIM3)
23     {
24         if(htim->Channel == HAL_TIM_ACTIVE_CHANNEL_1)
25         {
26             PA15_rise = __HAL_TIM_GetCounter(htim);
27             __HAL_TIM_SetCounter(htim, 0);
28             PA15_freq = PA15_FREQ/PA15_rise;
29             PA15_duty = PA15_fall*100/PA15_rise;
30         }
31         if(htim->Channel == HAL_TIM_ACTIVE_CHANNEL_2)
32         {
33             PA15_fall = __HAL_TIM_GetCounter(htim);
34         }
35     }
36     if(htim->Instance == TIM8)
37     {
38         if(PB4_flag == 0)
39         {
40             PB4_rise = __HAL_TIM_GetCounter(htim);
41             __HAL_TIM_SetCounter(htim, 0);
42             PB4_freq = PB4_FREQ/PB4_rise;
43             PB4_duty = PB4_fall*100/PB4_rise;
44             __HAL_TIM_SET_CAPTUREPOLARITY(htim, TIM_CHANNEL_1, TIM_INPUTCHANNELPOLARITY_FALLING);
45         }
46         else
47         {
48             PB4_fall = __HAL_TIM_GetCounter(htim);
49             __HAL_TIM_SET_CAPTUREPOLARITY(htim, TIM_CHANNEL_1, TIM_INPUTCHANNELPOLARITY_RISING);
50         }
51         PB4_flag = !PB4_flag;
52     }
53 }
54
55 void HAL_UART_RxCpltCallback(UART_HandleTypeDef *huart)
56 {
57     if(huart->Instance == USART1)
58     {
59         rx_array[rx_pointer++] = rx_data;
60         HAL_UART_Receive_IT(huart, (uint8_t *)&rx_data, 1);
61     }
62 }
63
64 void HAL_TIM_PeriodElapsedCallback(TIM_HandleTypeDef *htim)
65 {
66     if(htim->Instance == TIM6)
67     {
68         key[0].value = HAL_GPIO_ReadPin(GPIOB, GPIO_PIN_0);
69         key[1].value = HAL_GPIO_ReadPin(GPIOB, GPIO_PIN_1);
70         key[2].value = HAL_GPIO_ReadPin(GPIOB, GPIO_PIN_2);
71         key[3].value = HAL_GPIO_ReadPin(GPIOA, GPIO_PIN_0);

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72     for(int i=0;i<4;i++)
73     {
74         switch(key[i].state)
75         {
76             case 0:
77                 if(key[i].value == 0) key[i].state = 1;
78                 break;
79             case 1:
80                 if(key[i].value == 0)
81                 {
82                     key[i].state = 2;
83                     key[i].click_time = 0;
84                 }
85                 else key[i].state = 0;
86                 break;
87             case 2:
88                 if(key[i].value == 0)
89                     key[i].click_time++;
90                 else if(key[i].click_time >70)
91                 {
92                     key[i].long_flag = 1;
93                     key[i].state = 0;
94                 }
95                 else
96                 {
97                     switch(key[i].double_state)
98                     {
99                         case 0:
100                             key[i].double_state = 1;
101                             break;
102                         case 1:
103                             key[i].double_flag = 1;
104                             key[i].double_state = 0;
105                             break;
106                     }
107                     key[i].double_time = 0;
108                     key[i].state = 0;
109                 }
110             }
111             break;
112         }
113         case 2:
114             if(key[i].value == 0)
115                 key[i].click_time++;
116             else
117             {
118                 key[i].short_flag = 1;
119                 key[i].state = 0;
120             }
121             break;
122     }
123
124     if(key[i].double_state == 1)
125     {
126         key[i].double_time++;
127         if(key[i].double_time>30)
128         {
129             key[i].short_flag = 1;
130             key[i].double_state = 0;
131         }
132     }
133 }
134 }
135 }
136 }
137 }
138 }

```