THE

PRIMER

TRAINER

APPLICATION MANUAL

Manual Revision 1.0

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APPLICATIONS

APPLICATION 1:   Count Down Timer
This is an example of a countdown timer which displays a count down from 9999 to 0 and sounds an alarm and lights the LEDs. No additional hardware required.

APPLICATION 2:   Waveform Generator
This is a program which uses the D/A output to generate sine, square, triangle and sawtooth waveforms of varying frequency. You will need an oscilloscope to view the waveforms.

APPLICATION 3:   Interfacing a Temperature Sensor to the PRIMER
This application involves interfacing a temperature sensor to the A/D and gives an example of control based on temperature. This requires assembling a circuit.

APPLICATION 4:   Interfacing a Photocell to the PRIMER
This is an example using a simple photo-resistor circuit connected to the A/D input. The program may be modified to perform a count when the photo-resistor is in the presence of light or when it is darkened. This requires building a simple 2 component circuit.

APPLICATION 5:   Using the PRIMER to Regulate the Speed of a DC Motor
This application demonstrates DC motor speed control. This requires building a circuit.

APPLICATION 6:   External Multiplexed Display and Keypad Decoder
This demonstrates and emulates the functions of a keypad decoder and two digit LED display controller. This requires circuit assembly.

APPLICATION 7:   Controlling an LCD Module
In this application, a character LCD display is controlled via the digital output port. This requires building a simple circuit.

APPLICATION 8:   Capacitance Meter
The PRIMER can be used to measure capacitors ranging from 0.01 to 220uF, by adding a simple 3 component circuit.

APPLICATION 9:   Interfacing a Stepper Motor to the PRIMER
This application demonstrates microprocessor control of a stepper motor. This requires circuit assembly.

APPLICATION 10: Interfacing an 8255A PPI to the PRIMER
This introduces the method of interfacing an I/O mapped device to the PRIMER by building a simple circuit using the 8255A PPI.

Application 1: Count Down Timer

This program will count down from the packed BCD number in the HL register pair to 0 at a time increment determined by the hex number in the DE register pair. When the count = 0, the alarm will sound and the LEDs will light. The alarm can be discontinued and the program terminated by pressing any key on the keypad. After typing in the program, load the HL and DE register pairs as follows :

Load the HL register pair with the desired time interval.
Format = packed BCD   range = 9999 to 0001

Load DE register pair with the time scaler.
Format = hex   range = 0001h to FFFFh

The time scaler determines how many hundredths of seconds must pass before the counter is decremented. The time interval between decrements will be ((time scaler) / 100) seconds. For example, if the scaler is 0064h (100 decimal) the timer will decrement once a second. If the scaler is 1770h (6000 decimal) the timer will count decrement once every 60 seconds.

```
                    ;---------------------------------------------------------;
                    ;...........EQUATES.......................................;
                    ;---------------------------------------------------------;

 FFE9 =             VEC7HLF:    EQU     0FFE9H  ;INT 7.5 VECTOR
 0000 =             SCALELO:    EQU     00H     ;307200HZ / 768 =
 004C =             SCALEHI:    EQU     4CH     ;100HZ TICK RATE
 0014 =             TIMERLO:    EQU     14H     ;TIMER PORTS
 0015 =             TIMERHI:    EQU     15H
 00CD =             TIMCMD:     EQU     0CDH    ;TIMER FUNC. COMMAND
 0010 =             CMDREG:     EQU     10H     ;TIMER COMMAND PORT
 001A =             INTMASK:    EQU     1AH     ;INTERRUPT MASK
 FF01 =             TIMPROG:    EQU     0FF01H  ;RTC PROG START ADDR
 000C =             SERVC:      EQU     0CH     ;EMOS SERVICES
 0012 =             SERV12:     EQU     12H
 000B =             SERV0B:     EQU     0BH
 1000 =             MOS:        EQU     1000H   ;MOS CALL LOCATION
 00FF =             LIGHT:      EQU     0FFH    ;ALARM LED ON PATTERN
 0000 =             DARK:       EQU     0       ;ALARM LED OFF PATTERN


                    ;---------------------------------------------------------;
 FF01                        ORG     TIMPROG
                    ;---------------------------------------------------------;


                    ;---------------------------------------------------------;
                    ;...........INITIALIZE....................................;
                    ;---------------------------------------------------------;

 FF01 F3            START:   DI                     ;DISABLE INTERRUPTS
 FF02 22AEFF                 SHLD    TIM1            ;LOAD H/L TO TIMER1
 FF05 EB                     XCHG
 FF06 22A4FF                 SHLD    SCALER          ;D/E CONTAINS SCALER
 FF09 2157FF                 LXI     H,TIMERS        ;ON 7.5 INTERRUPT
 FF0C 22E9FF                 SHLD    VEC7HLF         ;VECTOR TO RTC
 FF0F 3E00                   MVI     A,SCALELO      ;SET LOW COUNT BYTE
 FF11 D314                   OUT     TIMERLO         ;OF TIMER CHIP

 FF13 3E4C                   MVI     A,SCALEHI      ;SET HIGH COUN T BYTE
 FF15 D315                   OUT     TIMERHI         ;OF TIMER CHIP
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FF17 3ECD                MVI     A,TIMCMD      ;SET TIMER CHIP FOR
FF19 D310                OUT     CMDREG        ;100 HZ SQUARE WAVE
FF1B 3E01                MVI     A,01H         ;SET ALARM FLAG TO
FF1D 32B0FF              STA     ALRMFLAG      ;ARM ALARM
FF20 2AA4FF              LHLD    SCALER        ;INITIALIZE TIMER 0
FF23 22ACFF              SHLD    TIM0
FF26 3E1A                MVI     A,INTMASK    ;UNMASK 7.5 AND 5.5
FF28 30                  SIM                   ;INTERRUPTS
FF29 FB                  EI                    ;ENABLE INTERRUPTS

               ;---------------------------------------------------------;
               ;...........MAIN PROGAM..................................;
               ;---------------------------------------------------------;

FF2A 0E12      DOTIME:   MVI     C,SERV12  ;USE SERVICE 12
FF2C 2AAEFF              LHLD    TIM1      ;TO DISPLAY TIMER 1
FF2F EB                  XCHG              ;DE WILL BE DISPLAYED
FF30 CD0010              CALL    MOS       ;CALL MOS
FF33 3AB0FF              LDA     ALRMFLAG  ;IF ALARM IS ON
FF36 FE01                CPI     01H       ;GO WAIT FOR KEY
FF38 CA2AFF              JZ      DOTIME    ;ELSE DISPLAY TIMER
FF3B 0E12                MVI     C,SERV12  ;MAKE SURE WE DISPLAY
FF3D 2AAEFF              LHLD    TIM1      ;ONE LAST TIME TO
FF40 EB                  XCHG              ;DISPLAY TERMINAL
FF41 CD0010              CALL    MOS       ;COUNT
FF44 0E0B                MVI     C,SERV0B  ;STRIKE ANY KEY
FF46 CD0010              CALL    MOS       ;TO STOP ALARM
FF49 20                  RIM                ;SPEAKER OFF
FF4A F640                ORI     40H
FF4C E67F                ANI     7FH
FF4E 30                  SIM
FF4F 0E0C                MVI     C,SERVC   ;LEDS OFF
FF51 1E00                MVI     E,DARK
FF53 CD0010              CALL    MOS
FF56 FF                  RST     7         ;RETURN TO MOS
               ;---------------------------------------------------------;
               ;...........7.5 INTERRUPT HANDLER........................;
               ;--------------------------------------------------------;
FF57 F5        TIMERS:   PUSH    PSW
FF58 E5                  PUSH    H
FF59 2AACFF              LHLD    TIM0          ;GET TIM0
FF5C 7D                  MOV     A,L           ;IF ITS NOT ZERO
FF5D B4                  ORA     H
FF5E C29CFF              JNZ     DECTIM0       ;DECREMENT TIM0
FF61 2AA4FF              LHLD    SCALER        ;ELSE TIM0 = 100
FF64 22ACFF              SHLD    TIM0          ;RELOAD TIM0
FF67 3AAEFF              LDA     TIM1          ;GET TIM1 LOW
FF6A C699                ADI     99H           ;DECREMENT
FF6C 27                  DAA                  ;DECIMAL ADJUST
FF6D 32AEFF              STA     TIM1          ;STORE TIM1 LOW
FF70 3AAFFF              LDA     TIM1+01H      ;GET TIM1 HIGH
FF73 CE99                ACI     99H           ;DECREMENT
FF75 27                  DAA                  ;DECIMAL ADJUST
FF76 32AFFF              STA     TIM1+01H     ;STORE TIM1 HIGH
FF79 2AAEFF              LHLD    TIM1          ;GET TIM1
FF7C 7D                  MOV     A,L           ;IF ITS NOT ZERO
FF7D B4                  ORA     H
FF7E C2A0FF              JNZ     EXITTIME      ;EXIT
FF81 3AB0FF              LDA     ALRMFLAG      ;IF ALARM HAS
FF84 FE00                CPI     00H           ;BEEN ACTIVATED
FF86 CAA0FF              JZ     EXITTIME       ;EXIT
FF89 3E00                MVI     A,00H         ;ELSE, ZERO ALARM
FF8B 32B0FF              STA     ALRMFLAG      ;FLAG & ACTIVATE
FF8E 20                  RIM                   ;SPEAKER ON
FF8F F6C0                ORI     0C0H
```

```
FF91 30                   SIM
FF92 0E0C                 MVI     C,SERVC       ;LEDS ON
FF94 1EFF                 MVI     E,LIGHT
FF96 CD0010               CALL    MOS
FF99 C3A0FF               JMP     EXITTIME      ;EXIT
FF9C 2B        DECTIM0:   DCX     H             ;DECREMENT TIM0
FF9D 22ACFF               SHLD    TIM0
FFA0 E1       EXITTIME:   POP     H             ;RECOVER REGISTERS
FFA1 F1                   POP     PSW
FFA2 FB                   EI
FFA3 C9                   RET                   ;RETURN
               ;--------------------------------------------------------;
               ;...........SUBROUTINES..................................;
               ;--------------------------------------------------------;

               ;--------------------------------------------------------;
               ;...........DATA STORAGE.................................;
               ;--------------------------------------------------------;
FFA4           SCALER:     DS       02H         ;DETERMINES TIME INCR.
FFA6           DISPBUFF:   DS       06H         ;DISPLAY BUFFER
FFAC           TIM0:       DS       02H
FFAE           TIM1:       DS       02H         ;SOFTWARE TIMER 1
FFB0           ALRMFLAG:   DS       01H         ;ALARM FLAG.0 = NO ALRM
               ;--------------------------------------------------------;
FFB1                      END
```

The machine language for the program is listed below.

ADDRESS	DATA	DESCRIPTION		ADDRESS	DATA	DESCRIPTION	
FF01	F3	DI		FF1D	32	STA	FFB0
FF02	22	SHLD	FFAE	FF1E	B0		
FF03	AE			FF1F	FF		
FF04	FF			FF20	2A	LHLD	FFA4
FF05	EB	XCHG		FF21	A4		
FF06	22	SHLD	FFA4	FF22	FF		
FF07	A4			FF23	22	SHLD	FFAC
FF08	FF			FF24	AC		
FF09	21	LXI	H,FF57	FF25	FF		
FF0A	57			FF26	3E	MVI	A,1A
FF0B	FF			FF27	1A		
FF0C	22	SHLD	FFE9	FF28	30	SIM	
FF0D	E9			FF29	FB	EI	
FF0E	FF			FF2A	0E	MVI	C,12
FF0F	3E	MVI	A,00	FF2B	12		
FF10	00			FF2C	2A	LHLD	FFAE
FF11	D3	OUT	14	FF2D	AE		
FF12	14			FF2E	FF		
FF13	3E	MVI	A,4C	FF2F	EB	XCHG	
FF14	4C			FF30	CD	CALL	1000
FF15	D3	OUT	15	FF31	00		
FF16	15			FF32	10		
FF17	3E	MVI	A,CD	FF33	3A	LDA	FFB0
FF18	CD			FF34	B0		
FF19	D3	OUT	10	FF35	FF		
FF1A	10			FF36	FE	CPI	01
FF1B	3E	MVI	A,01	FF37	01		
FF1C	01						

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ADDRESS	DATA	DESCRIPTION	
FF38	CA	JZ	FF2A
FF39	2A		
FF3A	FF		
FF3B	0E	MVI	C,12
FF3C	12		
FF3D	2A	LHLD	FFAE
FF3E	AE		
FF3F	FF		
FF40	EB	XCHG	
FF41	CD	CALL	1000
FF42	00		
FF43	10		
FF44	0E	MVI	C,0B
FF45	0B		
FF46	CD	CALL	1000
FF47	00		
FF48	10		
FF49	20	RIM	
FF4A	F6	ORI	40
FF4B	40		
FF4C	E6	ANI	7F
FF4D	7F		
FF4E	30	SIM	
FF4F	0E	MVI	C,0C
FF50	0C		
FF51	1E	MVI	E,00
FF52	00		
FF53	CD	CALL	1000
FF54	00		
FF55	10		
FF56	FF	RST	7
FF57	F5	PUSH	PSW
FF58	E5	PUSH	H
FF59	2A	LHLD	FFAC
FF5A	AC		
FF5B	FF		
FF5C	7D	MOV	A,L
FF5D	B4	ORA	H
FF5E	C2	JNZ	FF9C
FF5F	9C		
FF60	FF		
FF61	2A	LHLD	FFA4
FF62	A4		
FF63	FF		
FF64	22	SHLD	FFAC
FF65	AC		
FF66	FF		
FF67	3A	LDA	FFAE
FF68	AE		
FF69	FF		
FF6A	C6	ADI	99
FF6B	99		
FF6C	27	DAA	
FF6D	32	STA	FFAE
FF6E	AE		
FF6F	FF		
FF70	3A	LDA	FFAF
FF71	AF		
FF72	FF		
FF73	CE	ACI	99
FF74	99		
FF75	27	DAA	

ADDRESS	DATA	DESCRIPTION	
FF76	32	STA	FFAF
FF77	AF		
FF78	FF		
FF79	2A	LHLD	FFAE
FF7A	AE		
FF7B	FF		
FF7C	7D	MOV	A,L
FF7D	B4	ORA	H
FF7E	C2	JNZ	FFA0
FF7F	A0		
FF80	FF		
FF81	3A	LDA	FFB0
FF82	B0		
FF83	FF		
FF84	FE	CPI	00
FF85	00		
FF86	CA	JZ	FFA0
FF87	A0		
FF88	FF		
FF89	3E	MVI	A,00
FF8A	00		
FF8B	32	STA	FFB0
FF8C	B0		
FF8D	FF		
FF8E	20	RIM	
FF8F	F6	ORI	C0
FF90	C0		
FF91	30	SIM	
FF92	0E	MVI	C,0C
FF93	0C		
FF94	1E	MVI	E,FF
FF95	FF		
FF96	CD	CALL	1000
FF97	00		
FF98	10		
FF99	C3	JMP	FFA0
FF9A	A0		
FF9B	FF		
FF9C	2B	DCX	H
FF9D	22	SHLD	FFAC
FF9E	AC		
FF9F	FF		
FFA0	E1	POP	H
FFA1	F1	POP	PSW
FFA2	FB	EI	
FFA3	C9	RET	

Application 2: Waveform Generator

This application allows the user to output 4 different waveforms (sine, square, triangle and sawtooth) from the digital to analog convertor. The desired waveform can be selected by moving DIP switches 6 and 7 to one of 4 possible combinations. The frequency of the waveforms can be changed by moving DIP switches 0 through 5.

```
timerhi: equ      15h      ; the timer mode and MSB of count length
timerlo: equ      14h      ; the LSB of count length
dip:     equ      12h      ; DIP switch port
dacout:  equ      13h      ; Digital to analog output port
cmdreg:  equ      10h      ; 8155 control register.

         org      0ff01h
getime:  in       dip               ;get value of DIP switches
         add      a                 ;shift left padding zeros
         add      a                 ;shift left padding zeros
         out      timerlo           ;set the low count
         mvi      a,11000000b
         out      timerhi           ;single pulse w/auto reload
         mvi      a,0cdh
         out      cmdreg            ;enable timer

         in       dip               ;read DIP again
         ani      11000000b         ;Mask all DIP bits except 6 and 7
         cpi      0
         jz       sinewv            ;if upper bits are 0, output sine wave
         cpi      01000000b
         jz       sqrwav            ;if upper 2 bits are 01, output square wave
         cpi      10000000b
         jz       triang            ;if upper 2 bits are 10, output triangle wave

         ; If none of the above, upper 2 bits are 11, so output a .......
         ; sawtooth wave

sawwav:  mvi      c,0               ; invert the pattern
         mvi      d,3fh             ; starting value to output
         jmp      trian2

         ; triangle wave
triang:  mvi      c,1
         mvi      d,0               ; upward slope 0 to 3e
trian1:  mov      a,d
         call     dactim            ; output the pattern to DAC and wait
         inr      d
         mvi      a,3fh             ; if D = 3F then slope down
         cmp      d
         jnz      trian1

trian2:  mov      a,d               ; downward slope 3f to 1
         call     dactim            ; output the pattern to DAC and wait
         dcr      d
         jnz      trian2
         jmp      getime            ; check DIP switch

         ; square wave
sqrwav:  mvi      c,1               ; non-inverted output
sqrwv2:  mvi      d,32              ; output 32 times for each half of period
sqrwv3:  xra      a
         call     dactim            ; output the pattern to DAC and wait
         dcr      d
         jnz      sqrwv3            ; jump if not output 32 times already
         dcr      c                 ; change to inverted output mode
         jz       sqrwv2            ; if c=0 then sqrwv2
```

```
        jmp     getime          ; c=FF so check DIP switch

        ; sine wave
sinewv: lxi     h,sintbl        ; point to sine table
quadst: mvi     c,1             ; C=1 = 1st 2 quadrants, C=0 2nd two
quadrants
quad1:  inx     h               ; skip the 0
qud1lp: inx     h
        mov     a,m             ; A is value from table
        ora     a               ; set Z flag if A = 0
        jz      quad2           ; if A = 0 then read the table backwards
        call    dactim          ; output the pattern to DAC and wait
        jmp     qud1lp

quad2:  dcx     h               ; skip the 0
qud2lp: dcx     h
        mov     a,m             ; A is value from table
        ora     a               ; set Z flag if A = 0
        jz      quad3           ; if A=0 then invert the output pattern
        call    dactim          ; output the pattern to DAC and wait
        jmp     qud2lp

quad3:  dcr     c               ; change invert flag
        jz      quad1           ; if C=0 start over but invert data
        jmp     getime          ; if C=FF then check DIP switch

        ; DACTIM:  This subroutine examines the C register and if C=0
        ; it will invert the data in the A register otherwise if C=1 it
        ; will not.  The A register is then output to the D to A convertor.
        ; After this, the RST 7.5 interrupt flag will be polled until a pulse
        ; is sent from the 8155 timer. This causes the program to pause after
        ; each output from the D to A convertor according the the length
        ; of the timer count.
dactim: inr     c               ; see what C is .... (0 or 1)
        dcr     c               ; ...without changing it
        jnz     dactim1         ; jump if C = 1 and don't invert data
        mov     b,a             ; invert the data
        mvi     a,3fh           ; by subtracting it from this value
        sub     b

dactim1: out    dacout          ; output the data
polltmr: rim                    ; loop until rst 7.5 flag is high
        ani     01000000b       ; mask all but rst 7.5 flag
        jz      polltmr         ; check it again if not set
        mvi     a,10h
        sim                     ; clear the interrupt flag
        ret

        ; This is 1 quadrant of the sine wave pattern with zeros marking
        ; the start and the end.
sintbl: defb    0, 1Fh,21h,23h,25h, 27h,29h,2Bh,2Dh, 2Eh,30h,32h,34h, 35h
        defb    36h,38h,39h,3Ah, 3Bh,3Ch,3Dh,3Dh, 3Eh,3Eh,3Fh,3Fh, 3Fh, 0

        end
```

ADDRESS	DATA	DESCRIPTION
FF01	DB	IN 12
FF02	12	
FF03	87	ADD A
FF04	87	ADD A
FF05	D3	OUT 14
FF06	14	
FF07	3E	MVI A,C0
FF08	C0	
FF09	D3	OUT 15
FF0A	15	
FF0B	3E	MVI A,CD
FF0C	CD	
FF0D	D3	OUT 10
FF0E	10	
FF0F	DB	IN 12
FF10	12	
FF11	E6	ANI C0
FF12	C0	
FF13	FE	CPI 00
FF14	00	
FF15	CA	JZ FF56
FF16	56	
FF17	FF	
FF18	FE	CPI 40
FF19	40	
FF1A	CA	JZ FF43
FF1B	43	
FF1C	FF	
FF1D	FE	CPI 80
FF1E	80	
FF1F	CA	JZ FF29
FF20	29	
FF21	FF	
FF22	0E	MVI C,00
FF23	00	
FF24	16	MVI D,3F
FF25	3F	
FF26	C3	JMP FF38
FF27	38	
FF28	FF	
FF29	0E	MVI C,01
FF2A	01	
FF2B	16	MVI D,00
FF2C	00	
FF2D	7A	MOV A,D
FF2E	CD	CALL FF7C
FF2F	7C	
FF30	FF	
FF31	14	INR D
FF32	3E	MVI A,3F
FF33	3F	
FF34	BA	CMP D
FF35	C2	JNZ FF2D
FF36	2D	
FF37	FF	
FF38	7A	MOV A,D
FF39	CD	CALL FF7C
FF3A	7C	
FF3B	FF	

ADDRESS	DATA	DESCRIPTION
FF3C	15	DCR D
FF3D	C2	JNZ FF38
FF3E	38	
FF3F	FF	
FF40	C3	JMP FF01
FF41	01	
FF42	FF	
FF43	0E	MVI C,01
FF44	01	
FF45	16	MVI D,20
FF46	20	
FF47	AF	XRA A
FF48	CD	CALL FF7C
FF49	7C	
FF4A	FF	
FF4B	15	DCR D
FF4C	C2	JNZ FF47
FF4D	47	
FF4E	FF	
FF4F	0D	DCR C
FF50	CA	JZ FF45
FF51	45	
FF52	FF	
FF53	C3	JMP FF01
FF54	01	
FF55	FF	
FF56	21	LXI H,FF91
FF57	91	
FF58	FF	
FF59	0E	MVI C,01
FF5A	01	
FF5B	23	INX H
FF5C	23	INX H
FF5D	7E	MOV A,M
FF5E	B7	ORA A
FF5F	CA	JZ FF68
FF60	68	
FF61	FF	
FF62	CD	CALL FF7C
FF63	7C	
FF64	FF	
FF65	C3	JMP FF5C
FF66	5C	
FF67	FF	
FF68	2B	DCX H
FF69	2B	DCX H
FF6A	7E	MOV A,M
FF6B	B7	ORA A
FF6C	CA	JZ FF75
FF6D	75	
FF6E	FF	
FF6F	CD	CALL FF7C
FF70	7C	
FF71	FF	
FF72	C3	JMP FF69
FF73	69	
FF74	FF	
FF75	0D	DCR C
FF76	CA	JZ FF5B

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ADDRESS	DATA	DESCRIPTION
FF77	5B	
FF78	FF	
FF79	C3	JMP FF01
FF7A	01	
FF7B	FF	
FF7C	0C	INR C
FF7D	0D	DCR C
FF7E	C2	JNZ FF85
FF7F	85	
FF80	FF	
FF81	47	MOV B,A
FF82	3E	MVI A,3F
FF83	3F	
FF84	90	SUB B
FF85	D3	OUT 13
FF86	13	
FF87	20	RIM
FF88	E6	ANI 40
FF89	40	
FF8A	CA	JZ FF87
FF8B	87	
FF8C	FF	
FF8D	3E	MVI A,10
FF8E	10	
FF8F	30	SIM
FF90	C9	RET
FF91	00	From here down is sine wave data
FF92	1F	
FF93	21	
FF94	23	
FF95	25	
FF96	27	
FF97	29	
FF98	2B	
FF99	2D	
FF9A	2E	
FF9B	30	
FF9C	32	
FF9D	34	
FF9E	35	
FF9F	36	
FFA0	38	
FFA1	39	
FFA2	3A	
FFA3	3B	
FFA4	3C	
FFA5	3D	
FFA6	3D	
FFA7	3E	
FFA8	3E	
FFA9	3F	
FFAA	3F	
FFAB	3F	
FFAC	00	

Application 3: Interfacing a Temperature Sensor to the PRIMER

Purpose:

To expose the student to rudimentary analog interface techniques.

Goals:

1. Build and test a simple temperature sensing circuit.
2. Load a program that will make use of the temperature sensor's output.
3. Calibrate the sensor and software to provide a temperature reading in approximate engineering units.
4. Control a simple process with temperature.

Materials required:

1) PRIMER trainer
1) Fahrenheit thermometer
1) hair dryer
(A digital voltmeter may also prove helpful if available)

Component Description	**DIGI-KEY part number**	
LM358 Dual Op-Amp.	LM358N	1
LM35 Prec Celsius Temp Sensor.	LM35DZ-ND	1
100 Ohm 1% metal film resistor.	100.0XBK-ND	1
1K Ohm 1% metal film resistor.	1.00KXBK-ND	2
100K Ohm 5% carbon film resistor.	100KQBK-ND	4
100 K Ohm Potentiometer	3292W-104-ND	1
8 pin soldertail dip socket	A9308	1
1X2 inch piece of perfboard		

The electronic components listed above may be ordered from DIGI-KEY® , by phone by dialing 1-800-344-4539. They may also be found at electronic supply stores and other mail order houses.

Circuit Description:

The temperature sensing circuit used, in our application, is centered around the National Semiconductor LM35 series temperature sensors. The LM35N, with a range of (0 - 100 degrees Celsius), will be used in our application and produce an output voltage that is linearly proportional to the Celsius temperature. The LM35 senses temperature by amplifying the voltage differential at the base-emitter junctions of two identical transistors, that are operating at different currents, with the same temperature applied to them. As the junction temperature changes, the curve of base-emitter voltage vs. temperature will differ between the two transistors, because they are operating at different currents. This differential would normally be a problem in conventional circuitry, but is taken advantage of here. The differential voltage is amplified by the LM35, and presented to the output. The LM35, unlike other sensors, is calibrated in Celsius and provides 10 millivolts per degree Celsius. The advantage of this calibration is that we need not subtract a large constant voltage from the output to scale down Kelvin calibration. Each degree Kelvin is the same as one degree centigrade, but the scales start at different absolute temperatures. Zero degrees kelvin is -273 degrees centigrade, therefore, 0 degrees centigrade is +273 degrees kelvin. Additional Information may be obtained from National Semiconductor's website at (http://www.national.com/pf/LM/LM35.html)

Although kelvin and Celsius are equivalent (for this application) Fahrenheit degrees are entirely different. Both the scale shift, and the scale "gain" are different. Standard conversion formulas are used to convert centigrade to Fahrenheit and vice-versa. As nine Fahrenheit degrees pass for 5 Celsius degrees (5/9 plus the 32 Fahrenheit scale shift), each degree Fahrenheit will produce an eighteen (18) millivolt change per degree Fahrenheit. The program description describes how the analog reading is converted to Fahrenheit.

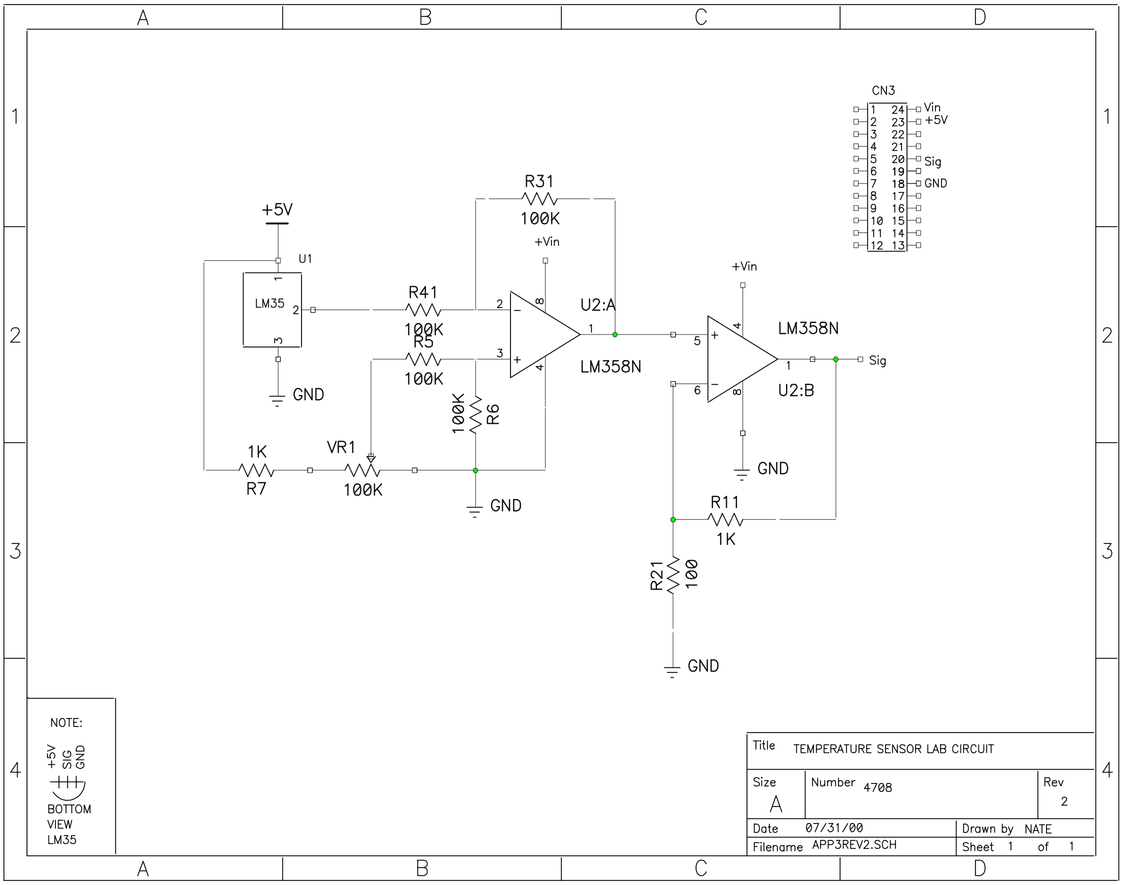
Referring to the schematic, the LM35 temperature sensor chip, U1, is powered by the 5 volt VCC supply of the PRIMER, which comes from the header connector plugged onto the analog port pins. As temperature rises, the LM35 output voltage (pin 2), rises. In our application, the PRIMER requires an inverse proportionality to the temperature rise. To achieve this inverse proportion to temperature rise , one half of U2, (LM358 Dual Op-Amp) is configured as a DC Summing Amplifier. The output of the LM35 is fed into the inverting pin (2), of the LM358. Pin 3 of the (LM358 Dual Op-Amp) has a voltage reference applied via VR1,R5,R6,R7. The output of the LM35 is subtracted from the voltage reference obtaining the inverse proportionality with temperature rise.

The PRIMER's A/D converter has 6 bits of resolution. This works out to 2^6 or 64 unique readings (or counts, as it is often termed in reference to A/D's) from 0 to 5V or 5V/64 = 0.078V per count which is 78mV per count. The circuit was designed to cause a change of slightly more than one count per millivolt change. To achieve this the second half of the LM358 is configured as a non-inverting DC amplifier. The output of the DC Summing Amplifier, via pin 1, is applied to the the non-inverting pin, 5 . The gain is set via the feedback resistor, R1, and R2 and applied to the inverting pin 6. The resistor values for R1 and R2 have been chosen to provide a gain of 11 to the output via pin 7 and therefore will output 110 milivolts per degree Celsius.

Procedure:

The temperature circuit should be built on perfboard, and connected to the PRIMER's analog port connector header. The circuit may be connected by wire-wrapping, soldering or by using a female connector. The circuit will draw power from the PRIMER, and feed its analog output to the PRIMER. Carefully check the wiring of the circuit, and be sure it is properly connected to the PRIMER.

HINT: Allow the circuit to thoroughly cool after soldering and handling. Residual heat that remains in the LM35 package, will deter attempts to adjust the setpoint correctly. If you set VR1, and the reading slowly drifts down, (lower temperature) it is probably due to this effect.



APPLICATION 3-3

Load the following program into memory:

```
         ; This program shows the fahrenheit temperature in the
         ; left four displays
leds     equ      11h      ; output port for digital output LEDs
adcin    equ      9        ; ADCIN service number
leddec   equ      13h      ; LEDDEC service number
mult     equ      7        ; MULT service number
div      equ      8        ; DIV service number
mos      equ      1000h    ; address of MOS services
adjst    equ      123      ; #of fahrenheit degrees * 100 per
                           ; change in value returned from ADCIN
         org      0ff01h
loop:    mvi      c,adcin
         call     mos      ; get the digital value of analog input voltage
         mvi      h,0
         lda      mxanlg   ; maximum analog value (this may be different on
                           ;   other PRIMERs, or with different temp sensors)
         sub      l        ; invert the analog conversion
         mov      l,a      ; HL = analog value
         lxi      d,adjst  ; load D with the adjustment factor
         mvi      c,mult
         call     mos      ; DE = HL * DE
         xchg              ; HL = DE
         lxi      d,100
         mvi      c,div
         call     mos      ; divide HL by 100
         lda      basetmp  ; get the base temperature
         add      l        ; now A is the actual temperature
         mov      e,a      ; E = temperature
         mov      a,e      ; A = temperature
         lhld     lotemp   ; L = low temp limit, H=high temp limit
         cmp      l        ; see if analog value is below L
         jnc      chkhi    ; check the high value if not
         mvi      a,0
         out      leds     ; turn on LEDs
chkhi:   mov      a,e      ; A = temperature
         cmp      h
         jc       noled    ; if A<H then don't turn off LEDs
         mvi      a,0FFh
         out      leds     ; H > = A so turn off LEDs
noled:   mvi      d,0      ; clear D register
         mvi      c,leddec
         call     mos      ; display the temp in DE
         jmp      loop     ; read it again

mxanlg:  ds       1        ; max analog value given by temp sensor
basetmp: ds       1        ; base temperature
lotemp:  ds       1        ; lower limit temperature
hitemp:  ds       1        ; upper limit temperature
         end
```

ADDRESS	DATA	INSTRUCTION
FF01	0E	MVI C,09
FF02	09	
FF03	CD	CALL 1000
FF04	00	
FF05	10	
FF06	26	MVI H,00
FF07	00	
FF08	3A	LDA FF42
FF09	42	
FF0A	FF	
FF0B	95	SUB L
FF0C	6F	MOV L,A
FF0D	11	LXI D,007B
FF0E	7B	
FF0F	00	
FF10	0E	MVI C,07
FF11	07	
FF12	CD	CALL 1000
FF13	00	
FF14	10	
FF15	EB	XCHG
FF16	11	LXI D,0064
FF17	64	
FF18	00	
FF19	0E	MVI C,08
FF1A	08	
FF1B	CD	CALL 1000
FF1C	00	
FF1D	10	
FF1E	3A	LDA FF43
FF1F	43	
FF20	FF	
FF21	85	ADD L
FF22	5F	MOV E,A
FF23	7B	MOV A,E

ADDRESS	DATA	INSTRUCTION
FF24	2A	LHLD FF44
FF25	44	
FF26	FF	
FF27	BD	CMP L
FF28	D2	JNC FF2F
FF29	2F	
FF2A	FF	
FF2B	3E	MVI A,0
FF2C	00	
FF2D	D3	OUT 11
FF2E	11	
FF2F	7B	MOV A,E
FF30	BC	CMP H
FF31	DA	JC FF38
FF32	38	
FF33	FF	
FF34	3E	MVI A,FF
FF35	FF	
FF36	D3	OUT 11
FF37	11	
FF38	16	MVI D,00
FF39	00	
FF3A	0E	MVI C,13
FF3B	13	
FF3C	CD	CALL 1000
FF3D	00	
FF3E	10	
FF3F	C3	JMP FF01
FF40	01	
FF41	FF	
FF42	3F	(max analog val)
FF43	00	(base temp data)
FF44	5A	(lo temp limit)
FF45	64	(hi temp limit)

After loading in the program, you must calibrate the temperature sensor circuit and the program. Start the program running at FF01 and observe the left four numeric output LEDs. A decimal number should be displayed there. With a small screwdriver, turn the potentiometer (VR1) clockwise. If after 20 turns the output hasn't changed, turn VR1 counterclockwise for 20 turns (VR1 has mechanical stops that don't care if you turn them too many times). Adjust VR1 until the value on the display is as low as it can go. As soon as the value on the display stops decreasing, stop turning VR1. Subtract the value that is on the displays from 64 (decimal), stop the program then convert that value to hexadecimal and store it at FF42. Since the value returned by the A/D convertor decreases as the temperature increases, it is subtracted from the maximum value the A/D convertor can produce (normally 63 decimal) thereby inverting the value. The temperature sensor, though, does not produce the 5 volts required to give the maximum value, and for this reason the value at FF42 must be changed.

Now check the temperature of the sensor using a thermometer and convert this value to hex and store it at FF43. This is the base temperature. If you start the program at FF01 again, the base temperature (or within 1 or 2 degrees of it) will be shown on the displays. Heat up the sensor with the hair dryer and you will see that when the displayed temperature reaches 100 degrees the digital output LEDs turn off. Let the sensor cool down to below 90 degrees and they will turn on again. It is possible for the digital output connector (connected to the digital output LEDs) to control external devices such as fans or heaters, if you know how to build relay drivers that will turn such devices on and off (do not attempt this if you are not proficient in electronics). If a fan is connected to the output connector, the program can turn on the fan when the temperature reaches 100 degrees and turn it off when the temperature drops below 90 degrees. Likewise, if a heater is connected, the program can turn on the heater when the temperature drops below 90 and turn it off when the temperature reaches 100 degrees.

You may be wondering by now why the program is written in such a way as to turn the LEDs on at one temperature and turn them off at another. This is done to keep the output device from rapidly oscillating on and off. Rapid oscillation is fine when dealing with LEDs but it can be destructive to relays. This technique of using different turn on and turn off temperatures is commonly used in environment control systems. To see what would happen if there was one turn on and turn off temperature, store 5A at address FF45 and run the program. Heat up the sensor to 89 degrees and while watching the digital output LEDs, slowly heat the sensor to 90 degrees. You should see that as the temperature approaches 90 degrees the LEDs will start to oscillate rapidly for a moment (the LEDs may appear to dim) until the temperature is stable at 90 degrees.

Program Description:

The program reads the analog to digital convertor and then inverts the value that was returned from it so that as the temperature increases, the value will increase. This value is then scaled to provide an accurate Fahrenheit temperature. It was found through experimentation, that a change of 69 degrees from the base temperature causes the A/D convertor value to change by 56 decimal. This means that for each change in A/D convertor value there is a 69/56 or 1.23 degree change in the temperature. Since MOS only does integer math, a trick had to be used to perform floating point math. The inverted A/D convertor value was multiplied by 123 and then the product was divided by 100 which effectively scaled the value by 1.23 and removed the tenths and hundredths digits. After the A/D convertor value is converted to fahrenheit, the base temperature is added to it to give the actual value. After this, it is compared to the low and high temperature values. If the temperature is below the low temperature value, zero is sent to the port for the digital output LEDs (which causes them to turn on), and if the temperature is at the high temperature limit, FF hex is sent the to the port (which turns the LEDs off). Finally the temperature is displayed on the left 4 displays and the program starts all over again.

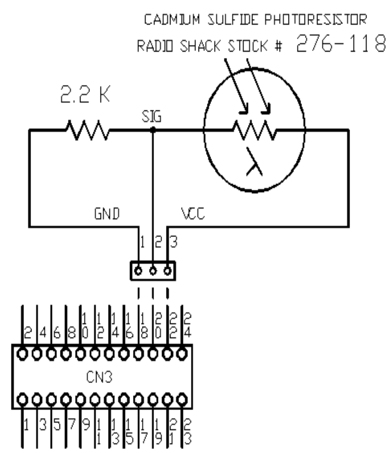
Application 4: Interfacing a Photocell

This application shows how to interface a photocell to the PRIMER Trainer and gives an example program which demonstrates its capabilities.

Start out by getting the needed parts. These parts can be obtained from Radio Shack if desired. The circuit is so simple (see diagram) that you may build it without a perfboard.

PART-NUMBER	PART-VALUE	PART-DESCRIPTION
276-118	Photocell	Cadmium sulfide
	2.2 KΩ	¼ or ⅛ W resistor

8The circuit is so simple (see diagram below) that you may build it without a perfboard. You may connect it to CN 3 by wire-wrapping, soldering, or using a female connector (be sure to disconnect power from the PRIMER first). After building the circuit and connecting it to CN3, reconnect the power and see if the board powers up correctly. If it does not, disconnect power again and check the circuit. Once the board is powered up correctly, you will want to enter the self test mode by pressing "FUNC." then "1". After the RAM diagnostics are complete, the analog to digital conversion value will be displayed on the right two displays while a proportional tone is emitted from the speaker. In normal room lighting, the number displayed should be around 20 hex, and with the photocell darkened, the number should be close to 00.



If the circuit appears to be working correctly, press reset and proceed to the next page.

The machine language for the program is listed below.

ADDRESS	DATA	DESCRIPTION	
8F01	AF	XRA	A
8F02	32	STA	8FB2
8F03	B2		
8F04	8F		
8F05	26	MVI	H,00
8F06	00		

8F07	11	LXI	D,8FA1
8F08	A1		
8F09	8F		
8F0A	CD	CALL	8F8B
8F0B	8B		
8F0C	8F		
8F0D	3A	LDA	8FB2
8F0E	B2		
8F0F	8F		
8F10	16	MVI	D,07
8F11	07		
8F12	47	MOV	B,A
8F13	E6	ANI	0F
8F14	0F		
8F15	C6	ADI	30
8F16	30		
8F17	5F	MOV	E,A
8F18	0E	MVI	C,11
8F19	11		
8F1A	CD	CALL	1000
8F1B	00		
8F1C	10		

ADDRESS	**DATA**	**DESCRIPTION**	
8F1D	78	MOV	A,B
8F1E	0F	RRC	
8F1F	0F	RRC	
8F20	0F	RRC	
8F21	0F	RRC	
8F22	E6	ANI	0F
8F23	0F		
8F24	C6	ADI	30
8F25	30		
8F26	15	DCR	D
8F27	5F	MOV	E,A
8F28	0E	MVI	C,11
8F29	11		
8F2A	CD	CALL	1000
8F2B	00		
8F2C	10		
8F2D	0E	MVI	C,09
8F2E	09		
8F2F	1E	MVI	E,00
8F30	00		
8F31	CD	CALL	1000
8F32	00		
8F33	10		
8F34	7D	MOV	A,L
8F35	07	RLC	
8F36	07	RLC	

continued on next page...

ADDRESS	**DATA**	**DESCRIPTION**	
8F37	07	RLC	
8F38	E6	ANI	07
8F39	07		
8F3A	3C	INR	A
8F3B	4F	MOV	C,A
8F3C	3E	MVI	A,FF
8F3D	FF		
8F3E	B7	ORA	A
8F3F	1F	RAR	
8F40	0D	DCR	C

```
8F41     C2     JNZ    8F3E
8F42     3E
8F43     8F
8F44     D3     OUT    40
8F45     40
8F46     01     LXI    B,8FB1
8F47     B1
8F48     8F
8F49     DB     IN     41
8F4A     41
8F4B     E6     ANI    01
8F4C     01
8F4D     C2     JNZ    8F5B
8F4E     5B
8F4F     8F
8F50     7D     MOV    A,L
8F51     02     STAX   B
8F52     11     LXI    D,8FA8
8F53     A8
8F54     8F
8F55     CD     CALL   8F8B
8F56     8B
8F57     8F
8F58     C3     JMP    8F2D
8F59     2D
8F5A     8F
8F5B     0A     LDAX   B
8F5C     C6     ADI    F6
8F5D     F6
8F5E     BD     CMP    L
8F5F     DA     JC     8F64
8F60     64
8F61     8F
8F62     26     MVI    H,01
8F63     01
8F64     0A     LDAX   B
8F65     BD     CMP    L
8F66     D2     JNC    8F78
8F67     78
8F68     8F
8F69     24     INR    H
8F6A     25     DCR    H
8F6B     CA     JZ     8F78
8F6C     78
8F6D     8F
8F6E     21     LXI    H,8FB2
8F6F     B2
8F70     8F
8F71     7E     MOV    A,M
8F72     3C     INR    A
8F73     B7     ORA    A
8F74     27     DAA
8F75     77     MOV    M,A
8F76     26     MVI    H,00
8F77     00
8F78     11     LXI    D,0000
8F79     00
8F7A     00
ADDRESS  DATA   DESCRIPTION
8F7B     24     INR    H
8F7C     25     DCR    H
8F7D     C2     JNZ    8F83
8F7E     83
8F7F     8F
8F80     11     LXI    D,0320
```

```
8F81    20
8F82    03
8F83    0E    MVI    C,10
8F84    10
8F85    CD    CALL   1000
8F86    00
8F87    10
8F88    C3    JMP    8F07
8F89    07
8F8A    8F
8F8B    E5    PUSH   H
8F8C    C5    PUSH   B
8F8D    EB    XCHG
8F8E    46    MOV    B,M
8F8F    23    INX    H
8F90    16    MVI    D,00
8F91    00
8F92    5E    MOV    E,M
8F93    0E    MVI    C,11
8F94    11
8F95    CD    CALL   1000
8F96    00
8F97    10
8F98    14    INR    D
8F99    23    INX    H
8F9A    05    DCR    B
8F9B    C2    JNZ    8F92
8F9C    92
8F9C    8F
8F9E    C1    POP    B
8F9F    E1    POP    H
8FA0    C9    RET
8FA1    06    DATA FOR "CELL->"
8FA2    43
8FA3    45
8FA4    4C
8FA5    4C
8FA6    2D
8FA7    3E
8FA8    08    DATA FOR "--LOAD--"
8FA9    2D
8FAA    2D
8FAB    4C
8FAC    4F
8FAD    41
8FAE    44
8FAF    2D
8FB0    2D
8FB1    64    SETPOINT
8FB2    00    COUNT
```

Application 5: Using the PRIMER to Regulate the Speed of a DC Motor

Purpose:

To introduce the student to one method of regulating the speed of a small DC
motor.

Goals:

1. Study formulas, data, and waveforms relating to a DC motor.

2. Build an interface circuit that will allow the PRIMER to regulate the speed of a particular DC motor.

3. Build a motor holding fixture that will allow one motor to be mechanically coupled to another.

4. Load, run, and test a program that will allow the PRIMER via the interface circuit to:

    A. Regulate the speed of a particular DC motor.
    B. Accept desired speed input via the on-board DIP switches.
    C. Display motor speed and pulse width via the on-board 7-segment displays and LEDs respectively.

Equipment, Components, and Materials:

Equipment (required):

Qty.	Description	Source	Part Number
1	PRIMER	EMAC	E600-00
1	Solderless Breadboard	Radio Shack	276-175
1	PRIMER Interface Cable	EMAC	E600-15

Components and Materials:

Interface Circuit:

1	Transistor, 2N2222	Digi-Key	PN2222A-ND
1	Transistor, 2N2907	Digi-Key	PN2907A-ND
1	Resistor, 8.2K , ¼W, 5%, Carbon Film	Digi-Key	8.2KQ
1	Resistor, 1.8K , ¼W, 5%, Carbon Film	Digi-Key	1.8KQ
1	Resistor, 1K , ¼W, 5%, Carbon Film	Digi-Key	1.0KQ
1	Resistor, 390 , ¼W, 5%, Carbon Film	Digi-Key	390Q
1	Diode, 1N4005	Digi-Key	1N4005GI
1	Capacitor, 2200µF, 16V	Digi-Key	P1216

Motor Load Resistors:

1	Resistor, 1.0 , ½W, 5%, Carbon Film	Digi-Key	1.0H
1	Resistor, 3.3 , ½W, 5%, Carbon Film	Digi-Key	3.3H
1	Resistor, 8.2 , ½W, 5%, Carbon Film	Digi-Key	8.2H
1	Resistor, 33 , ½W, 5%, Carbon Film	Digi-Key	33H

Motor Holding Fixture: (optional)

Qty.	Description	Source	Part Number
1	Aluminum or Plexiglas Flat, 3.9" x 2.9" x 1/16-1/8"	-	-
2	Aluminum or Plexiglas Flat, 1.8" x 0.5" x 1/16-1/8"	-	-
8	Aluminum Spacers, Round Threaded, 4-40 x 0.75"	Digi-Key	J240
2	Perfboard, Glass epoxy, Pad per hole, 0.4" x 2.2"	-	-
2	Terminal Block, 2 position	Digi-Key	ED1631-ND
1	Tennis Racquet Grip Wrap (Motor Mounting Pads) (or equivalant)	SOFTGRIP	STG-X
12	Pan Head Screws, 4-40 x 1/4"	Digi-Key	H142
4	Pan Head Screws, 4-40 x 1/2"	Digi-Key	H146
16	Lock Washers, #4	Digi-Key	H236
2	Motor with Gear(1.5 to 4.5VDC, 65mA @ 4.5VDC, 3 pole, permanent anisotropic magnet, 1.5 oz.in. stall torque)	Radio Shack	273-237

General:

20"ea.	Wire, Stranded, 22 Ga., Red and Black	Radio Shack	278-1218
20"	Wire, Wire Wrap, 30 Ga.	Radio Shack	278-503

Introduction:

In this lab, we would like to program the PRIMER to regulate the speed of a DC motor. The PRIMER will adjust motor speed by varying the armature voltage applied to the motor. This will be accomplished by varying the amount of time a fixed voltage is applied to the armature within a fixed time frame. This technique is called pulse width modulation (PWM). The time when voltage is applied to the motor will be referred to as "motor on time" or pulse width (PW). The time remaining in the fixed time frame would be "motor off time." The PRIMER will read the speed of the motor by using the on-board analog to digital (A/D) converter to measure the voltage (back EMF) generated by the motor during motor off time. This voltage is directly proportional to motor speed. By comparing motor speed to the desired speed, input via the on-board DIP switches, the PRIMER can correctly adjust motor on time to keep motor speed constant. Before we get to the interface circuit and PRIMER program needed to regulate motor speed, it might be helpful to look at some basic information relative to DC motors in general and to the motor we will be regulating in particular.

Motor Formulas:

$$T = 7.04K\ I_a$$

$$V_g = K\ N$$

$$I_a = V - \frac{V_g}{R_a}$$

$$V - I_a R_a$$

Where:

- K = A constant for a particular motor.
- = Field flux.
- Ia = Armature Current.
- Ra = Armature Resistance.
- V = Armature Voltage.
- Vg = Back or Counter EMF.
- N = Motor Speed.

$$N = \frac{\text{--------}}{K} \qquad T = \text{Motor Torque.}$$

These formulas show that there is a linear relationship between applied armature voltage V and motor speed N for a given load. Since back EMF, Vg,is directly related to motor speed there is also a linear relationship between V and Vg. The formulas also show that:

1. Vg will always be less than V.
2. Ia, and therefore torque are greatest at low motor speed and both decrease as motor speed is increased.
3. When an increased load is applied to a motor it must supply more torque.
   This in turn means that Ia must increase. If Ia increases motor speed
   will decrease. The only way to return the motor to its original speed
   is to increase the armature voltage V.

The motor we will use in this lab is a permanent magnet type. Permanent magnets provide the field flux . Magnetic fields setup by current flowing in the armature windings cause the armature to rotate inside the magnetic fields set up by the permanent magnets. To maintain armature rotation, the direction of the armature magnetic fields must constantly change relative to the fixed direction of the magnetic fields of the permanent magnets. This function is provided by brushes riding on a commutator attached to the motor shaft that constantly changes the direction of current flow in the armature windings as the shaft rotates. In this mode of operation, we supply electrical energy to the motor in the form of armature current and the motor supplies mechanical energy in the form of shaft rotation. If we supply mechanical energy to the motor by rotating the shaft, the motor will supply electrical energy in the form of armature current. This armature current results from the armature windings cutting across the magnetic lines of force set up by the magnetic fields of the permanent magnets. This current as seen by an electrical load across the motor terminals would be alternating (AC) if not for the rectifying action of the commutator converting it to DC. In this mode of operation, the motor is acting as a generator and the resulting DC voltage measured across the motor terminals is called counter or back EMF. The amplitude of this voltage will depend on the electrical load attached to the motor terminals but for a given load, changes in this back EMF will be directly proportional to changes in the speed of the rotating armature.

Motor Waveforms:

If we use a pulse generator to apply pulse width modulation to the circuit of Figure 1 and observe the resulting A/D signal on an oscilloscope, we would see the waveforms of Figure 2. The three regions of interest in the waveforms are marked as A, B, and C. The period of the PWM signal is A + B + C. The motor on time is A and the motor off time is B + C. Region B in waveform B is a negative voltage generated by the collapsing magnetic field in the armature windings when armature current is cut off at the beginning of motor off time. If this voltage were not clamped by diode D1 to that coul about -0.7V, it would be a very large negative voltage d potentially damage the PRIMER A/D circuitry. Region C in Waveform B is the back EMF generated by the armature rotating in the magnetic field of the permanent magnets during motor off time. If the pulse width of the PWM signal is now increased we would see the waveforms of Figure 3. The motor speed will noticeably increase and the amplitude of the back EMF of Region C will be greater. Two things are of interest in observing the motor waveforms that will have a bearing on our motor controller program.

1. The back EMF voltage is not "straight line smooth" as we would like it to be, but rather is a varying signal riding on a DC level. The amplitude of the varying signal seems to increase with increasing motor speed (increased pulse width). We could filter this with our circuitry but it would be difficult since we would not want to filter the motor on time voltage. This would introduce an unwanted error in the back EMF. A better solution would be to digitally filter (average) the back EMF by totalling 16 back EMF samples and then dividing the total by 16.

2. The point in the PWM period where we will begin to sample the back EMF must be carefully chosen to avoid sampling the motor on time voltage or the negative voltage transition. A sample window must be set up that will start late enough to assure back EMF will be present during maximum PW, but not so late that the program can't finish executing the required amount of code before the start of the next PWM period.

Motor Speed vs. Pulse Width and the Motor as an Integrator:

If we applied increasing pulse widths to the circuit of Figure 1, allowed the motor to accelerate up to speed and recorded the back EMF for each pulse width for various motor loads and plotted the results we would get a graph similar to the one in Figure 4. You might be surprised to see that the relationship between applied pulse width and back EMF is not linear for many of the curves. The curves appear to go from logarithmic for an unloaded motor toward linear as motor load is increased. This seems to contradict the results we would predict if we use the motor formulas we looked at earlier. The reason for this is that we are asking the motor to integrate the PWM signal into an armature voltage. We would expect that:

This is a linear relationship but this relationship only holds up if the acceleration (charge) and deceleration (discharge) times in the motor (integrator) are close to equal. The acceleration time (charge time) will be much shorter than deceleration time at no motor load because we are driving the armature up to speed and then allowing the armature to decelerate at its own pace. Deceleration is strictly load dependent. If there is no load on the motor the deceleration time is long, (relative to acceleration time), the integrator discharge time is long, and the curve is logarithmic. As the motor load increases (decreasing RL), the acceleration (charge) and deceleration (discharge) times become more nearly equal, the motor begins to act more like a true integrator, the armature voltage to PW relationship becomes linear, and the graph becomes linear. To state the previous discussion another way, if the linear changes in PW were producing linear changes in armature voltage, the motor would be responding linearly. Look at the graph in Figure 5. Notice the motor speed response vs. pulse width increase is linear, independent of motor load. These plots were produced by integrating the PWM signal externally and applying the resulting voltage via a power op-amp to the motor. Now the motor is behaving as the formulas predict because it is not required to integrate the PWM signal. Since our program will allow the PRIMER to measure motor speed with the A/D converter and then adjust the pulse width to the value necessary to obtain the desired speed, you might imagine that nonlinearity in the motor speed curves is unimportant.

Nonlinearity can make it more difficult for our program to control motor speed. Consider the curve for an unloaded motor (motors uncoupled) in Figure 4. Notice that a pulse width change of only 1 count, say from 6 to 7, can cause a speed change of more than 10. This means it will be difficult if not impossible for our program to make fine adjustments in motor speed since it can only make incremental (not fractional) changes to pulse width. Now look at the curve in Figure 4 for a motor load of 8.1 ohms. Now incremental changes in pulse width result in incremental changes in motor speed and as a result much finer adjustment of motor speed will be possible. So even though our program will do a fair job controlling motor speed when the motor is operating on one of the non linear curves, it will do a much better job controlling speed when the motor is operating on a more linear curve.

Motor Interface Circuit Description and Assembly:

Capacitor C1 in Figure 6 provides energy during times of high armature current to prevent fluctuations of the 5V supply. Resistor R1 sets the base current of transistor Q1 when PWM is high. Transistor Q1 provides base current for transistor Q2 when PWM is high. Q2 base current is set by resistors R2 and R3. Resistor R2 prevents Q2 conduction as a result of Q1 leakage or low level transients. Q2 provides armature current for motor M1 when PWM is high. Diode D1 clamps the negative voltage spike generated by the collapsing magnetic field of the armature at Q2 turn off. Resistor R4 limits the current into the A/D converter during the negative voltage spike. Two advantages of using pulse width modulation applied directly to the motor to control motor voltage are:

1. Relatively simple interface circuitry.
2. There is much less power dissipation because the controlling devices are switches (on or off).

The circuit in Figure 6 consists of easily available, inexpensive components. The circuit can be constructed on a solderless breadboard and wired to the PRIMER and motor using the PRIMER Interface Cable. The PWM and A/D connections can be wire-wrapped from the PRIMER CN3 connector to wire-wrap posts or stiff wires pushed into the breadboard. The motor leads should be short lengths (10 in.max.) of 22 ga. wire soldered to the motor tabs (no polarity) and then tinned on the other end so they will push into the breadboard holes.

Motor Holding Fixture:

A convenient way of loading one motor is to have it drive another motor which can in turn feed generated current through various load resistors to increase the load on the driving motor. If the motor you are using has a gear attached to the shaft, two motors can be coupled as illustrated in the motor fixture drawing. If your motor does not have a gear on the shaft, you can try coupling two motors with a short length of plastic tubing that will slip onto and hold tightly to the motor shafts. With this scheme the motors will be mounted in-line instead of offset in the motor fixture. Other motor loading schemes can be used such as using the motor to drive a propeller or placing a friction load against the motor shaft (holding your finger against the shaft at different degrees of pressure will do). You can choose your own method for mounting, coupling, and loading the motors but remember to construct fixtures from non-ferrous material because of the permanent magnets in the motors.

Program Description:

Refer to flowcharts 1 and 2 for a discussion of the motor controller program. The program divides the PWM period into 64 time slices or t_slices. Each t_slice is 160µs long. The t_slices are numbered from 0-63. A variable called t_slice is incremented in an interrupt handler on every 7.5 interrupt. Continuous pulses 160µs apart from the timer chip initiate each 7.5 interrupt. This interrupt handler also manages the PWM output. If pulse width is less than time slice, PWM output (output port bit 0) is high, otherwise it's low. The scheduling of events is illustrated below:

```
New
Event       Minimum                      Maximum Sample
Period
              PW                            PW     Mark
Starts
        |      |                             |       |          |
|

--------------------------------------------------------------
        0      3                            50      52         63
0
                                  Time Slice
```

The time between time slice 0 and sample mark is used to display speed and pulse width. These are displayed on the 7-segment LED display and LEDs 7-1 respectively. Notice there are upper and lower limits for pulse width. The time between maximum PW and sample mark is reserved to allow the negative voltage spike to pass when PW is maximum. The time between sample mark and end of period is used to sample the back EMF, average 16 samples, and calculate a new pulse width based on the current speed and the desired speed (set with the PRIMER DIP switches). The program consists of two programs, a background program and a foreground program. The background program executes every time the microprocessor receives an interrupt pulse on the 7.5 interrupt pin. The timer chip is set by the initialization part of our program to provide a pulse to the 7.5 interrupt pin every 160µs. The background program has two functions.

1. To increment the time slice each time it executes. The only exception to this is when time slice reaches a maximum count of 63 at which time it is set back to zero.
2. To set the PWM signal (output port bit 0) high or low. If time slice is less than pulse width the output is high, otherwise it is low.

The foreground program monitors time slice and waits till it's 0. Then it displays motor speed on the leftmost four 7-segment LED digits and it displays pulse width in a bar graph fashion on LEDs 7-1 as follows:

Pulse Width LEDs On

0-7	(0% - 11%)	1
8-15	(12% - 23%)	1, 2
16-23	(24% - 36%)	1, 2, 3
24-31	(37% - 48%)	1, 2, 3, 4
32-39	(49% - 61%)	1, 2, 3, 4, 5
40-47	(62% - 73%)	1, 2, 3, 4, 5, 6
48-50	(74% - 78%)	1, 2, 3, 4, 5, 6, 7

The foreground program then waits for time slice to equal sample mark.

Sample mark is set to accommodate the longest possible pulse width plus time for the negative voltage transition (after motor current cutoff) to expire. At sample mark the back EMF is sampled and added to a total of 16 such samples. If 16 samples have not yet been totaled the program repeats by going back and waiting for time slice to equal 0. When 16 samples have been totaled, the total is divided by 16 to produce an average speed (it is this average speed that will later be displayed on the 7-segment display after time slice 0). The average speed is then subtracted from the speed set on the PRIMER DIP switches to produce an error term. If the error is < -1, the pulse width is decremented. If the error is > 1, the pulse width is incremented. If the error is -1, 0, or 1, the pulse width is unchanged. The pulse width is then range checked. If the pulse width is less than minimum (3), it is set to minimum. If the pulse width is greater than maximum (50), it is set to maximum. Otherwise the pulse width is unchanged.

The entire process then repeats by going back and again waiting for time slice 0. To test the motor speed program wire the circuit of Figure 6 and connect the PRIMER and drive motor M1 to the circuit as previously described. Couple the second motor M2 if available to the drive motor M1. Motor M2 if used should be unloaded (no RL across its terminals). Set the PRIMER DIP switches for a speed of 20. Load the motor control program into the PRIMER and run the program. The motor will accelerate to speed and the PW and average speed will be displayed as previously described. Load the drive motor by placing an 8.2 , ½W resistor across the terminals of motor M2 or by hand friction. The motor speed will decrease at first, as indicated by the 7-segment LED display. Then the PW will increase, as indicated by the 7 LEDs, to bring the motor speed back to 20. Now remove the 8.2 load resistor from motor M2 or the friction source. The speed of the drive motor will increase suddenly and the PW will begin to decrease to bring the motor speed back to 20.

Use the curves of Figure 4 and load resistors for various speeds set in on the DIP switches to exercise the motor speed control program. Notice from the curves of Figure 4 that there are limits on the maximum speed attainable for various motor loads. If you try to request a motor speed greater than the motor can provide for a given load, the program will simply increase the pulse width to maximum to get the maximum speed possible. Note that the following program text can be cut out and assembled.

```
;--------------------------------------------------------------
; This program regulates the speed of a DC motor by....
; [1] Averaging 16 samples of back EMF during motor off time.
; [2] Generating an error term (DIP switch - average EMF).
; [3] Using the error term to adjust the pulse width.
; [4] Using the resulting pulse width to pulse width modulate
;     (PWM) the motor.
```

```
;
; WARNING:  Use a 9V supply with a current limit of 1000 mA or
;          more with this lab.  The standard 500mA supply will
;          be damaged if it is used with this lab.
;
MOS:           EQU    1000H          ;MOS SERVICES ADDRESS.
PWM_PORT:      EQU    11H            ;DIGITAL OUTPUT PORT.
DIP_SW:        EQU    12H            ;DIP SWITCH PORT.
SERV09:        EQU    09H            ;MOS SERVICE.ADCIN => L.
SERV13:        EQU    13H            ;MOS SERVICE.DE => 7-SEG DISPLAY.
PW_MIN:        EQU    03H            ;MINIMUM PW. T=160uS X PW_MIN
PW_MAX:        EQU    32H            ;MAXIMUM PW. T=160uS X PW_MAX
MAX_SLICE:     EQU    3FH            ;MAXIMUM NUMBER OF TIME SLICES.
                                     ;SETS PWM PERIOD.
                                     ;T=160uS X MAX_SLICE.
SMARK:         EQU    34H            ;TIME SLICE WHERE BACK EMF
                                     ;SAMPLE WILL BE TAKEN.
VEC7HLF:       EQU    0FFE9H         ;7.5 INTERRUPT VECTOR.
SCALELO:       EQU    35H            ;MODE/SCALER FOR TIMER,
SCALEHI:       EQU    11000000B      ;CONTINUOUS PULSES EVERY 160uS.
TIMERLO:       EQU    14H            ;TIMER PORT.
TIMERHI:       EQU    15H            ;TIMER PORT.
TIMCMD:        EQU    0CDH           ;TIMER CONTROL COMMAND.
CMDREG:        EQU    10H            ;TIMER CONTROL PORT.
INTMASK:       EQU    1AH            ;INTERRUPT MASK.

               ORG    0FF01H

               DI
               LXI    H,SLICER       ;POINT 7.5 INTERRUPT
               SHLD   VEC7HLF        ;VECTOR TO SLICER.
               MVI    A,SCALELO      ;SET UP TIMER FOR
               OUT    TIMERLO        ;CONTINUOUS PULSES
               MVI    A,SCALEHI      ;AT DESIRED INTERRUPT
               OUT    TIMERHI        ;RATE.
               MVI    A,TIMCMD
               OUT    CMDREG
               MVI    A,INTMASK
               SIM
               EI

PWM_MOTOR:
               LXI    H,0000H        ;REG H = TOTAL
               MVI    B,10H          ;REG B = SAMPLE COUNT.

CHKZERO:
               LDA    T_SLICE        ;TIME SLICE = 0 ?
               CPI    00H
               JNZ    CHKZERO        ;NO.GO CHECK SMARK.
               MVI    D,00H          ;DISPLAY SPEED.
               MOV    E,C            ;C = SPEED.
               PUSH   B
               MVI    C,SERV13
               CALL   MOS
```

```
             POP    B
             LDA    PULSE_WIDTH
             MOV    D,A              ;DISPLAY PW.
             MVI    E,0FFH           ;E = MASK.
             ORA    E                ;CLEAR CARRY.
ROT_MASK:
             RAL                     ;ROTATE 0 TO MASK.
             MOV    E,A              ;SAVE MASK.
             MOV    A,D              ;GET PW.
             SUI    08H              ;PW = PW - 8.
             MOV    D,A              ;SAVE RESULT TO D.
             MOV    A,E              ;GET MASK.
             JNC    ROT_MASK         ;PW STILL POS. ?
             DI                      ;DISABLE INTERRUPT.
             LDA    IMAGE            ;GET IMAGE.
             RAR                     ;SAVE BIT 0.
             MOV    A,E              ;GET MASK.
             RAL                     ;7 BITS MASK + BIT 0.
             STA    IMAGE            ;TO IMAGE.
             EI                      ;ENABLE INTERRUPT.
CHK_SMARK:
             LDA    T_SLICE
             CPI    SMARK            ;TIME SLICE = SMARK ?
             JNZ    CHK_SMARK        ;NO.WAIT TILL IT IS.
             XCHG                    ;DE = TOTAL.
             PUSH   B                ;SAMPLE BACK EMF.
             MVI    C,SERV09
             CALL   MOS
             POP    B
             MVI    H,00H            ;HL = SAMPLE.
             DAD    D                ;HL = TOTAL + SAMPLE.
             DCR    B                ;DEC. SAMPLE COUNT.
             JNZ    CHKZERO          ;IF NOT 0, CHK 0 T_SLICE.

DIV_MORE:    DAD    H                ;HL*16/256=HL/16, SO...
             DAD    H                ;...4 DAD H's MAKES HL*16...
             DAD    H                ;..AFTER THIS H=HL/256 (THINK ABOUT IT)
             DAD    H                ;SPEED=TOTAL / MAX SAMP (16).
             MOV    C,H              ;STORE SPEED.
             IN     DIP_SW           ;GET DESIRED SPEED.
             ANI    00111111B        ;DES.SPEED 6 BITS MAX.
             SUB    H                ;SWITCH-SPEED=ERROR.
             LXI    H,PULSE_WIDTH
             JM     DECPW_CHK        ;ERROR = -. DEC PW ?
             CPI    2                ;ERROR < 2 ?
             JC     PW_RANGE         ;YES. NO PW CHANGE.
             INR    M                ;NO. INC PW.
             JMP    PW_RANGE         ;RANGE CHECK PW.
DECPW_CHK:
             CPI    0FFH             ;ERROR = -1.
             JZ     PW_RANGE         ;YES. RANGE CHECK PW.
             DCR    M                ;NO. DEC PW.
PW_RANGE:
             MVI    A,PW_MIN         ;PW < MIN ?
```

```
             CMP    M
             JC     MAX_CHK         ;NO. CHECK MAX.
             MOV    M,A             ;YES. PW = MIN.
MAX_CHK:
             MVI    A,PW_MAX        ;PW > MAX ?
             CMP    M
             JNC    PWM_MOTOR       ;NO. PW OK.
             MOV    M,A             ;YES. PW = MAX.
             JMP    PWM_MOTOR       ;START AGAIN.

;----------------------------------------------------------------
;.......................SLICER...................................
;SLICER IS AN INTERRUPT HANDLER FOR THE 7.5 INTERRUPT.
;SLICER CONTROLS A TIME MARKER (T_SLICE) BY ADJUSTING IT FROM
;0 TO MAX_SLICE IN EQUAL TIME INCREMENTS ON EACH 7.5 INTERRRUPT.
;SLICER ALSO CONTROLS THE WIDTH OF THE PULSE USED TO DRIVE THE
;MOTOR BY COMPARING THE VALUE OF PULSE_WIDTH TO THAT OF T_SLICE
;TO DETERMINE IF THE PULSE SHOULD BE HIGH OR LOW.
;PULSE HIGH => T_SLICE < PULSE_WIDTH.
;PULSE LOW  => T_SLICE >=PULSE_WIDTH.
;----------------------------------------------------------------

SLICER:
             PUSH   PSW             ;SAVE REGISTERS.
             PUSH   H
             LXI    H,T_SLICE       ;H POINTS TO T_SLICE.
             INR    M               ;INCREMENT T_SLICE
             MVI    A,MAX_SLICE
             CMP    M               ;T_SLICE = MAX_SLICE ?
             JNZ    PWM             ;NO. T_SLICE OK.
             MVI    M,00H           ;YES. T_SLICE = 0.
PWM:
             MOV    A,M             ;A = T_SLICE.
             LXI    H,PULSE_WIDTH   ;M = PULSE WIDTH.
             CMP    M               ;T_SLICE < PULSE WIDTH ?
             LXI    H,IMAGE         ;M = IMAGE.
             MOV    A,M             ;GET IMAGE.
             RAR                    ;CY => BIT 7.
             RLC                    ;BIT 7 => BIT 0.
             MOV    M,A             ;STORE IMAGE.
             OUT    PWM_PORT        ;OUTPUT IMAGE.
             POP    H               ;RECOVER REGISTERS.
             POP    PSW
             EI
             RET                    ;RETURN

T_SLICE:     DB     00H
PULSE_WIDTH: DB     PW_MIN
IMAGE:       DS     01H
             END
;-----------------------------------------------------------
```

OBJECT/MACHINE CODE

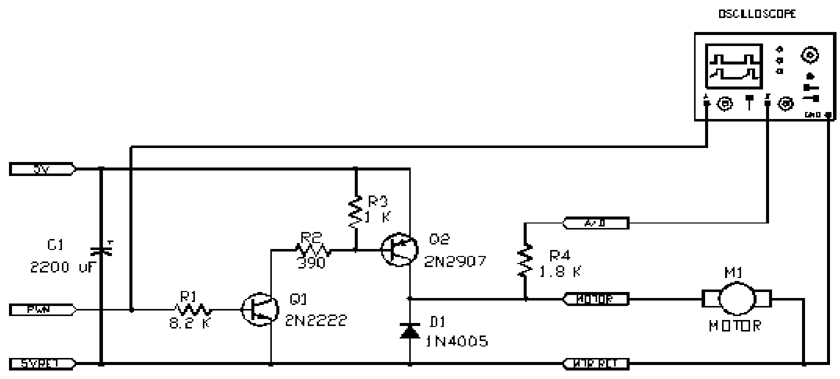
```
ADDRESS  DATA   INSTRUCTION
FF01     F3     DI
FF02     21     LXI   H, FF92
FF03     92
FF04     FF
FF05     22     SHLD  FFE9
```

```
FF06    E9
FF07    FF
FF08    3E    MVI   A, 35
FF09    35
FF0A    D3    OUT   14
FF0B    14
FF0C    3E    MVI   A, C0
FF0D    C0
FF0E    D3    OUT   15
FF0F    15
FF10    3E    MVI   A, CD
FF11    CD
FF12    D3    OUT   10
FF13    10
FF14    3E    MVI   A, 1A
FF15    1A
FF16    30    SIM
FF17    FB    EI
FF18    21    LXI   H, 0000
FF19    00
FF1A    00
FF1B    06    MVI   B, 10
FF1C    10
FF1D    3A    LDA   FFB2
FF1E    B2
FF1F    FF
FF20    FE    CPI   00
FF21    00
FF22    C2    JNZ   FF1D
FF23    1D
FF24    FF
FF25    16    MVI   D, 00
FF26    00
FF27    59    MOV   E,C
FF28    C5    PUSH  B
FF29    0E    MVI   C, 13
FF2A    13
FF2B    CD    CALL  1000
FF2C    00
FF2D    10
FF2E    C1    POP   B
FF2F    3A    LDA   FFB3
FF30    B3
FF31    FF
FF32    57    MOV   D,A
FF33    1E    MVI   E, FF
FF34    FF
FF35    B3    ORA   E
FF36    17    RAL
FF37    5F    MOV   E,A
FF38    7A    MOV   A,D
FF39    D6    SUI   08
FF3A    08
FF3B    57    MOV   D,A
FF3C    7B    MOV   A,E
FF3D    D2    JNC   FF36
FF3E    36
FF3F    FF
FF40    F3    DI
FF41    3A    LDA   FFB4
```

```
FF42      B4
FF43      FF
FF44      1F      RAR
FF45      7B      MOV   A,E
FF46      17      RAL
FF47      32      STA   FFB4
FF48      B4
FF49      FF
FF4A      FB      EI
FF4B      3A      LDA   FFB2
FF4C      B2
FF4D      FF
FF4E      FE      CPI   34
FF4F      34
FF50      C2      JNZ   FF4B
FF51      4B
FF52      FF
FF53      EB      XCHG
FF54      C5      PUSH  B
FF55      0E      MVI   C, 09
FF56      09
FF57      CD      CALL  1000
FF58      00
FF59      10
FF5A      C1      POP   B
FF5B      26      MVI   H, 00
FF5C      00
FF5D      19      DAD   D
FF5E      05      DCR   B
FF5F      C2      JNZ   FF1D
FF60      1D
FF61      FF
FF62      29      DAD   H
FF63      29      DAD   H
FF64      29      DAD   H
FF65      29      DAD   H
FF66      4C      MOV   C,H
FF67      DB      IN    12
FF68      12
FF69      E6      ANI   3F
FF6A      3F
FF6B      94      SUB   H
FF6C      21      LXI    H,FFB3
FF6D      B3
FF6E      FF
FF6F      FA      JM     FF7B
FF70      7B
FF71      FF
FF72      FE      CPI    02
FF73      02
FF74      DA      JC     FF81
FF75      81
FF76      FF
FF77      34      INR    M
FF78      C3      JMP    FF81
FF79      81
FF7A      FF
FF7B      FE      CPI    FF
FF7C      FF
FF7D      CA      JZ     FF81
```

```
FF7E    81
FF7F    FF
FF80    35      DCR     M
FF81    3E      MVI     A,03
FF82    03
FF83    BE      CMP     M
FF84    DA      JC      FF88
FF85    88
FF86    FF
FF87    77      MOV     M,A
FF88    3E      MVI     A,32
FF89    32
FF8A    BE      CMP     M
FF8B    D2      JNC     FF18
FF8C    18
FF8D    FF
FF8E    77      MOV     M,A
FF8F    C3      JMP     FF18
FF90    18
FF91    FF
FF92    F5      PUSH    PSW
FF93    E5      PUSH    H
FF94    21      LXI     H,FFB2
FF95    B2
FF96    FF
FF97    34      INR     M
FF98    3E      MVI     A,3F
FF99    3F
FF9A    BE      CMP     M
FF9B    C2      JNZ     FFA0
FF9C    A0
FF9D    FF
FF9E    36      MVI     M,00
FF9F    00
FFA0    7E      MOV     A,M
FFA1    21      LXI     H,FFB3
FFA2    B3
FFA3    FF
FFA4    BE      CMP     M
FFA5    21      LXI     H,FFB4
FFA6    B4
FFA7    FF
FFA8    7E      MOV     A,M
FFA9    1F      RAR
FFAA    07      RLC
FFAB    77      MOV     M,A
FFAC    D3      OUT     11
FFAD    11
FFAE    E1      POP     H
FFAF    F1      POP     PSW
FFB0    FB      EI
FFB1    C9      RET
FFB2    00      (time slice)
FFB3    03      (pulse width)
FFB4    xx      (output port, undefined leave blank)
```

Schematic 1



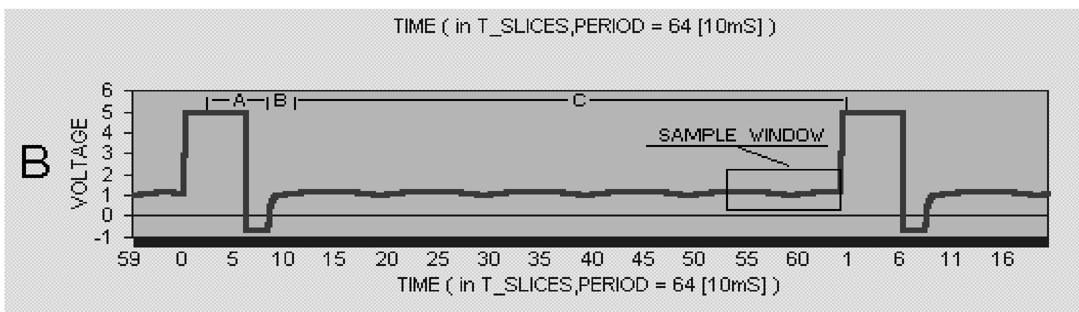
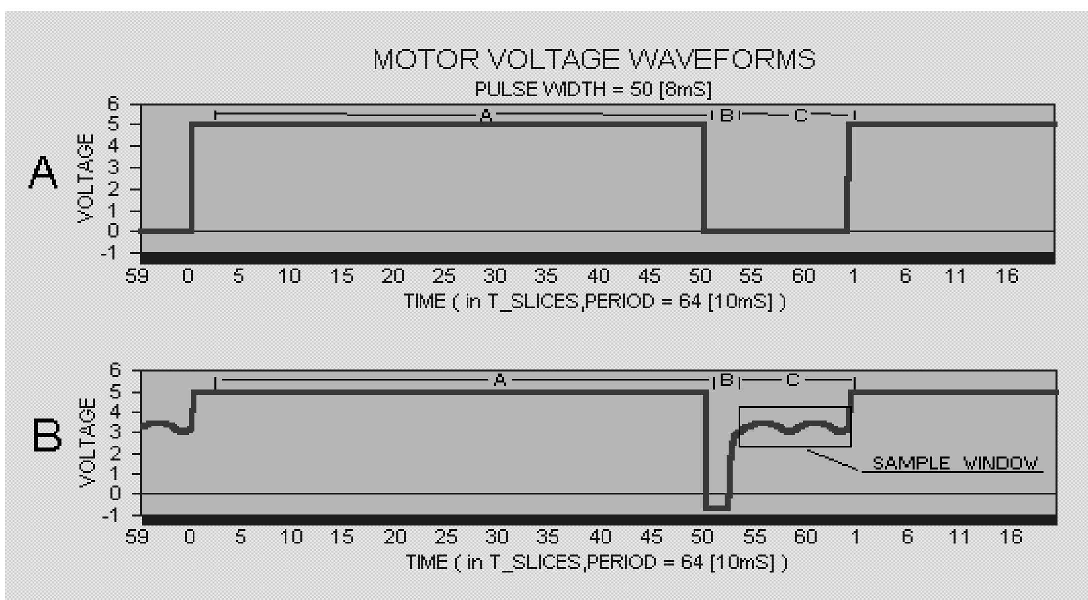
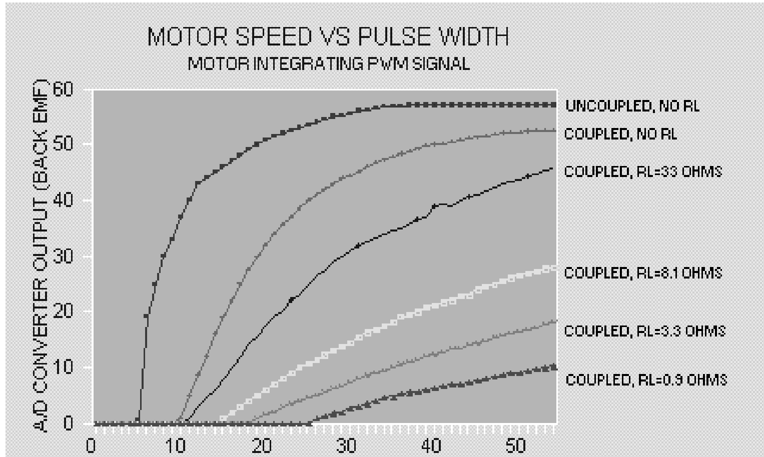


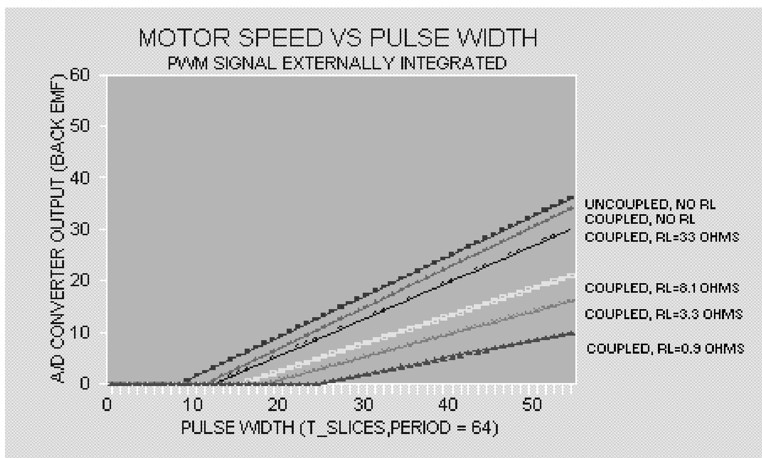
Figure 2



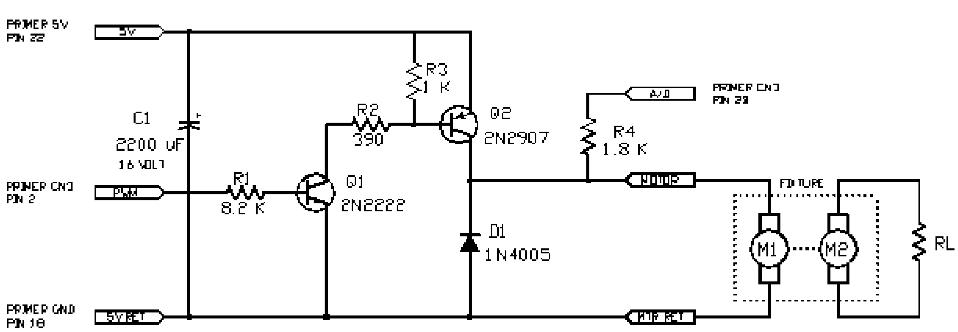
→

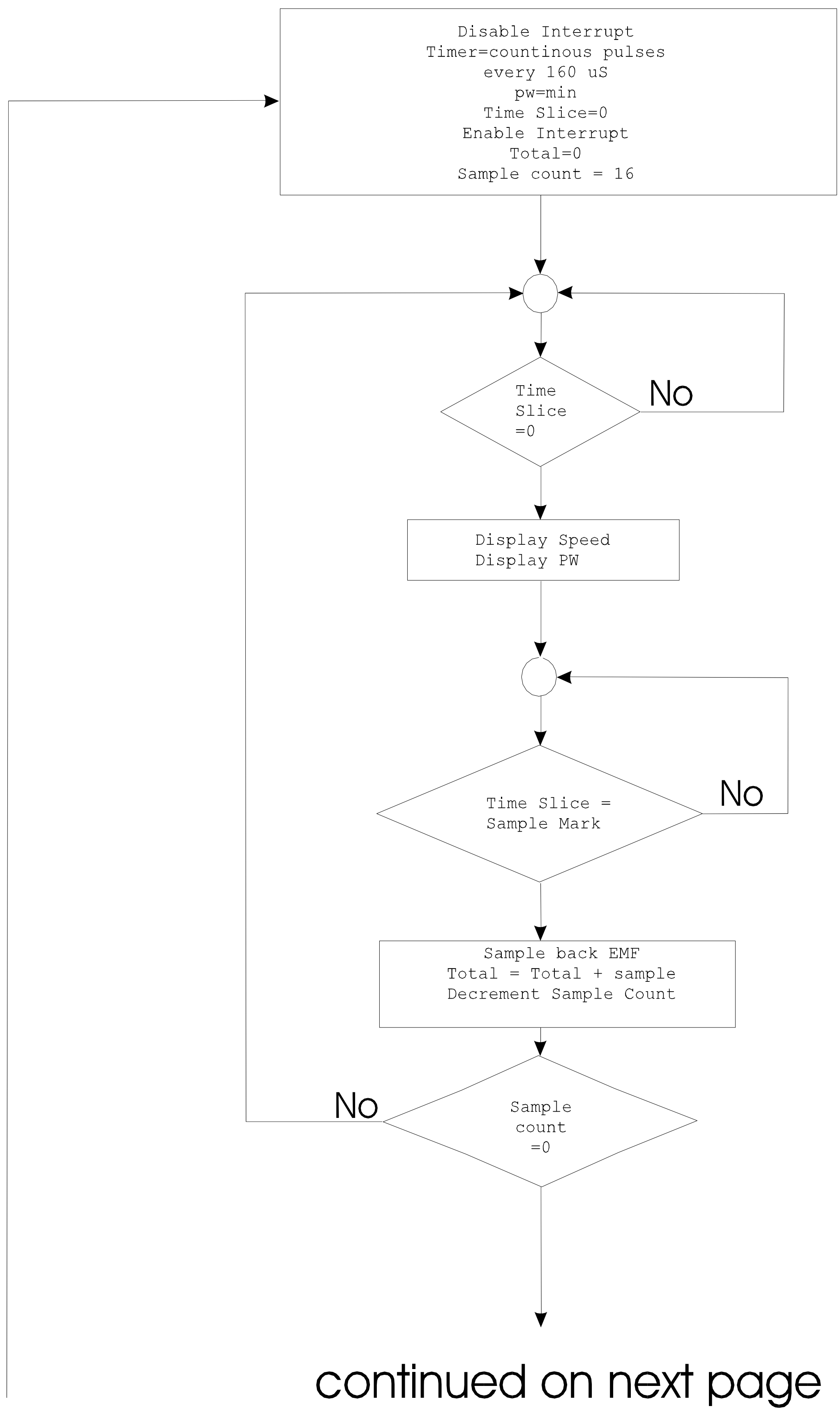
Figure 3


MOTOR SPEED VS PULSE WIDTH
MOTOR INTEGRATING PWM SIGNAL
A/D CONVERTER OUTPUT (BACK EMF)
0
10
20
30
40
50
60
UNCOUPLED, NO RL
COUPLED, NO RL
COUPLED, RL=33 OHMS
COUPLED, RL=8.1 OHMS
COUPLED, RL=3.3 OHMS
COUPLED, RL=0.9 OHMS


MOTOR SPEED VS PULSE WIDTH
PWM SIGNAL EXTERNALLY INTEGRATED
A/D CONVERTER OUTPUT (BACK EMF)
0
10
20
30
40
50
60
UNCOUPLED, NO RL
COUPLED, NO RL
COUPLED, RL=33 OHMS
COUPLED, RL=8.1 OHMS
COUPLED, RL=3.3 OHMS
COUPLED, RL=0.9 OHMS
PULSE WIDTH (T_SLICES,PERIOD = 64)

Schematic 2


PRIMER 5V
PIN 22
5V
C1
2200 uF
16 VOLT
PRIMER GND
PIN 18
5V RET
R1
8.2 K
Q1
2N2222
R2
390
R3
1 K
Q2
2N2907
D1
1N4005
R4
1.8 K
A/D
PRIMER CN3
PIN 29
MOTOR
MTR RET
FIXTURE
M1
M2
RL



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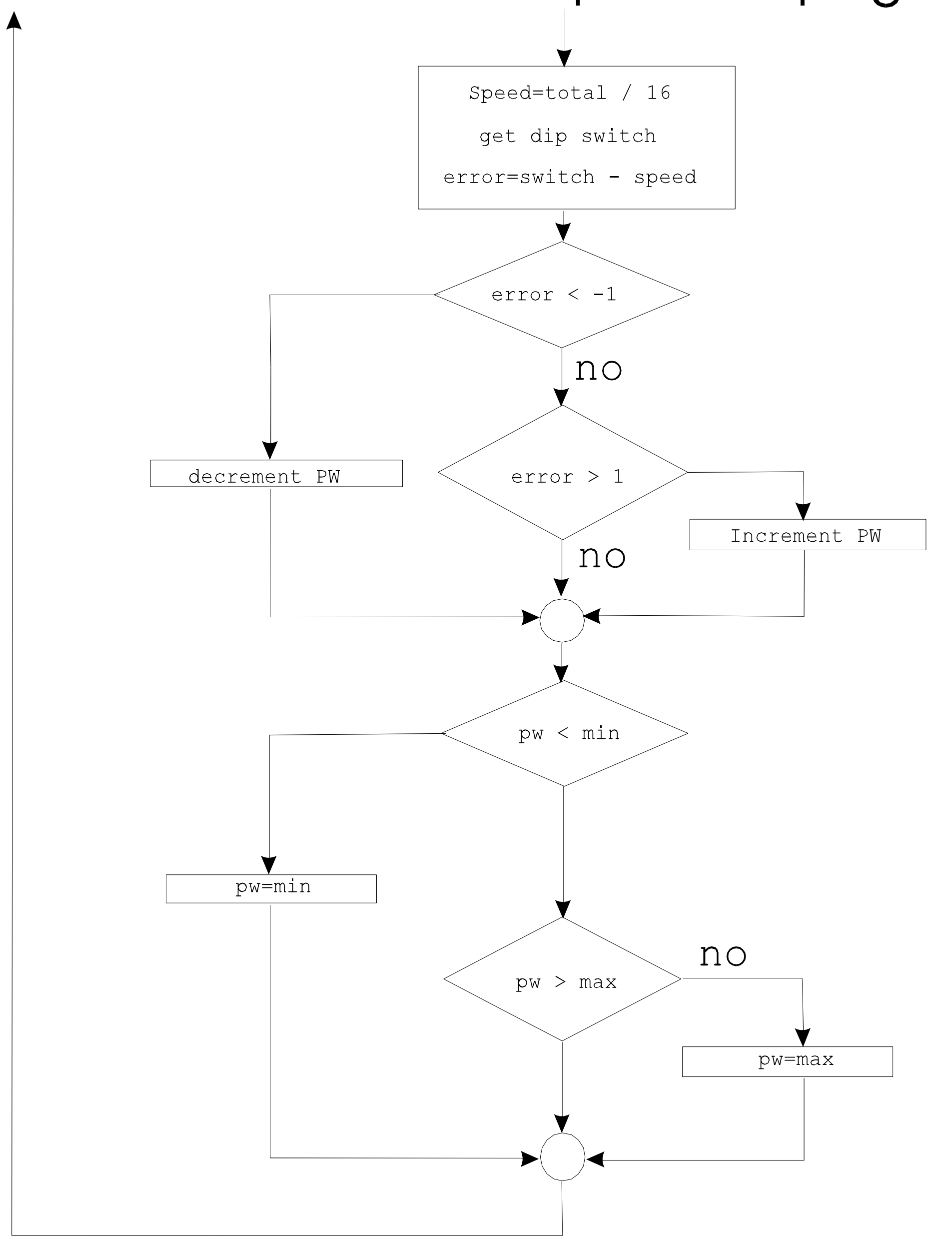
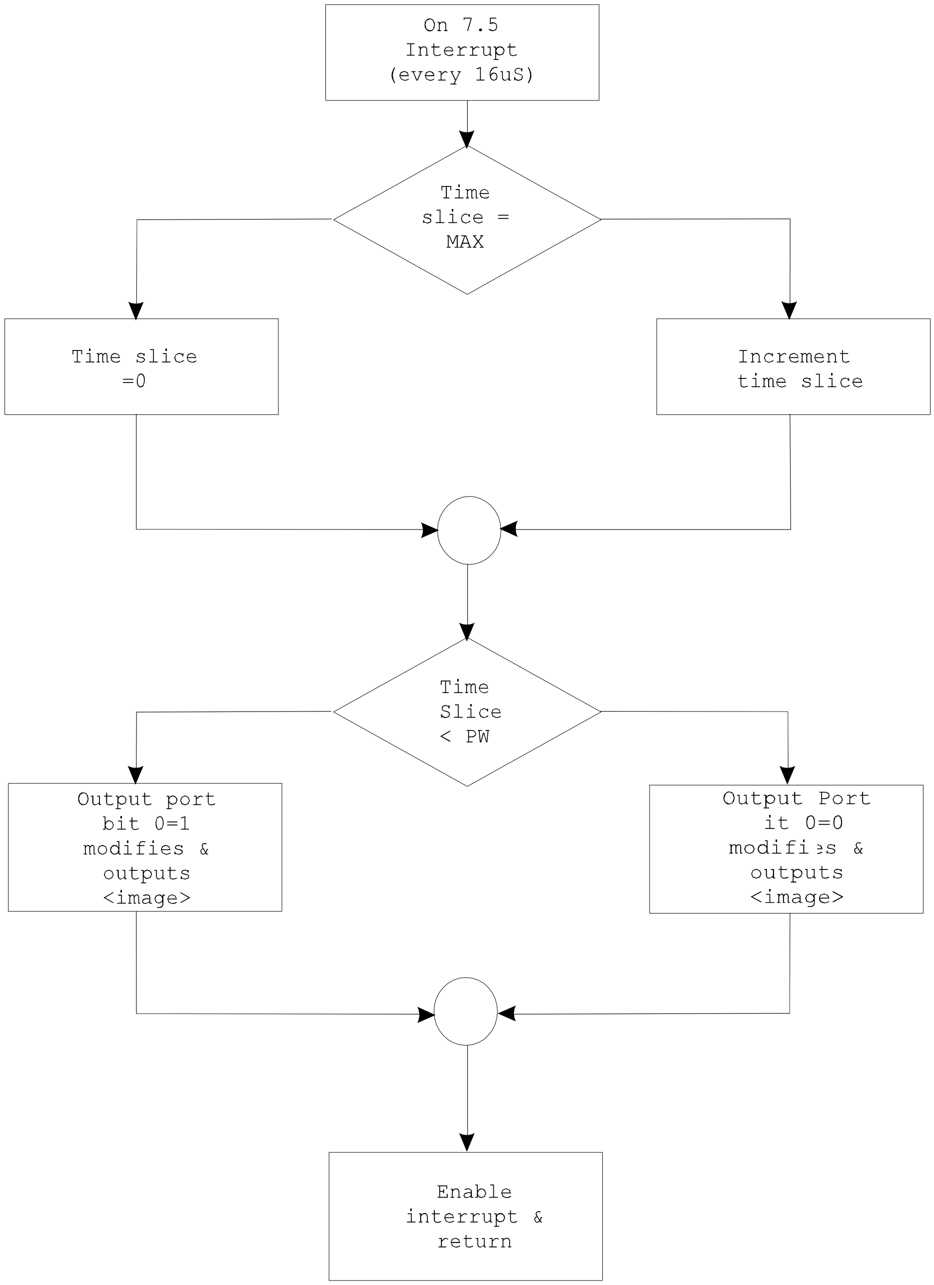
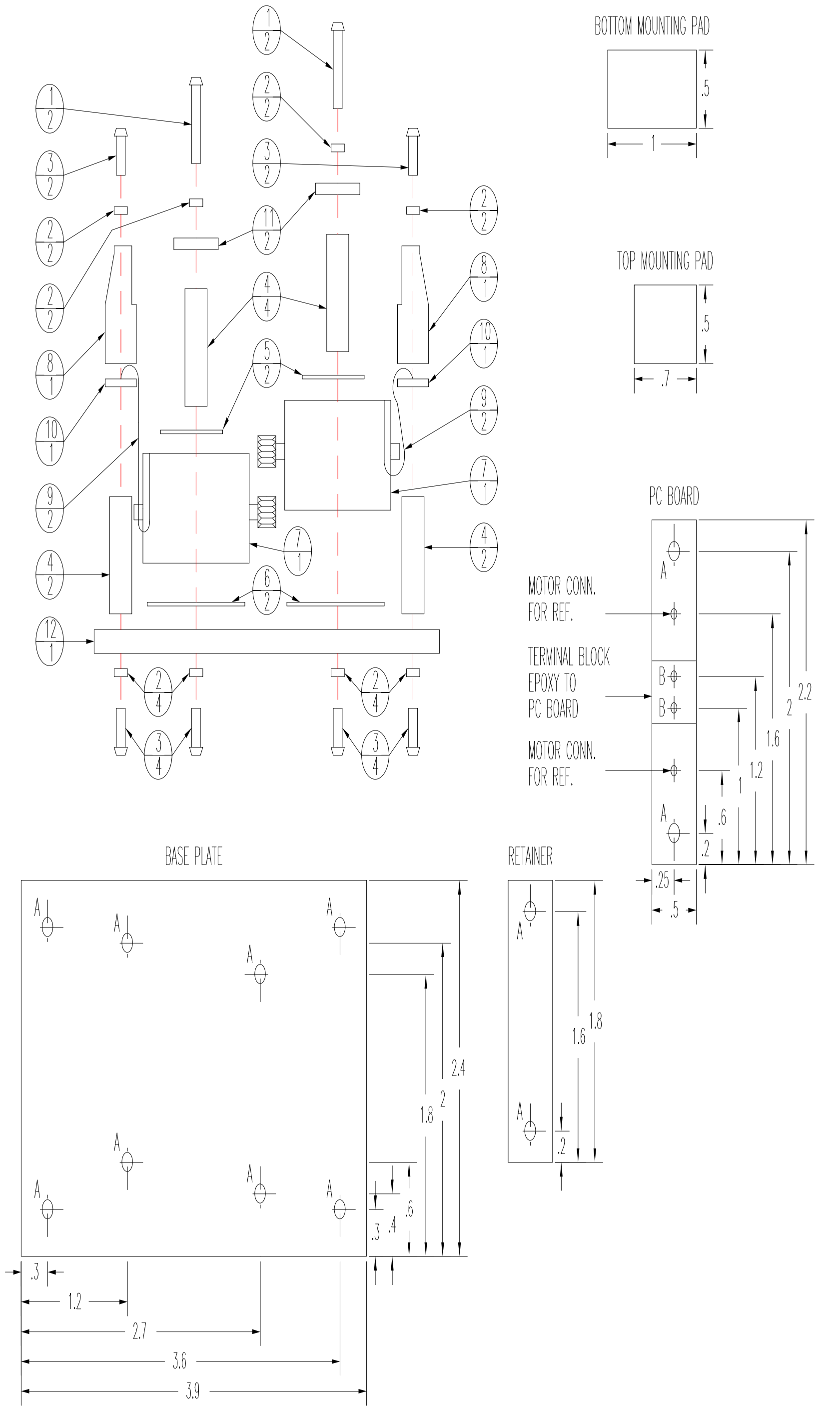




On 7.5
Interrupt
(every 16uS)
Time
slice =
MAX
Time slice
=0
Increment
time slice
Time
Slice
< PW
Output port
bit 0=1
modifies &
outputs
<image>
Output Port
it 0=0
modifi s &
outputs
<image>
Enable
interrupt &
return



ITEM	QTY	DESCRIPTION
1	4	SCREW, PAN HEAD 4-40 X 1/2"
2	16	LOCK WASHER #4
3	12	SCREW, PAN HEAD 4-40 X 1/4"
4	8	SPACER ROUND T 4-40 X 1/4" X
5	2	MOTOR MOUNTING PAD, TOP
6	2	MOTOR MOUNTING PAD, BOTTOM
7	2	MOTOR, DC, PM, 1.5V-4.5V, WIGEA
8	2	TERMINAL BLOCK, 2 POSITION
9	4	WIRE, MOTOR-PC 22 GA. STRANDED
10	2	PC BOARD, .4" X GLASS EPOXY
11	2	RETAINER, AL FLA 0.5" X 1.8" X 1/
12	1	BASE PLATE, AL F 2.9" X 3.9" X 1/

HOLE	QTY	DESCRIPTION
A	12	1/8" THRU
B	2	0.035" (#65) THR

TITLE
MOTOR MOUNTING

BY
DEREK JOHNSTON

REV. A

DWG. NO. FIG.

Application 6: External Multiplexed Display and Keypad Decoder

Purpose: To demonstrate and emulate the functions of a keypad and two digit LED display controller.

Goals:

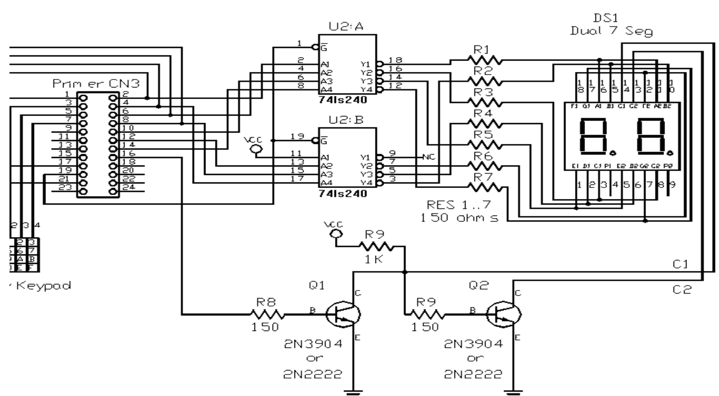
1. Build and test a keypad and numeric LED display interface.
2. Load a program that will demonstrate the numeric LED display interface.
3. Modify the program and load additional code which will demonstrate the keypad decoder.

Component Description	Digi-Key part number
2) 2N3904 or 2N2222	2N3904-ND or 2N2222-ND
1) 74ls240	DM74LS240N-ND
1) 4x4 matix keypad	GH5004-ND
1) 2 digit LED display	P355-ND
9) 150 ohm 5% 1/4 watt resister	
1) 1 Kohm 5% 1/4 watt resister	

This application will be demonstrated in two phases: with the display only, and then with the keypad and display.

Display Controller Circuit Description

To drive an external 7 segment display using the trainer, the 8 output lines (numbered 0 to 7) would be the obvious choice. This would provide control for each of the 7 elements leaving one output line free. What if we want to drive two digits?. We need 7 more outputs which we don't have. The answer to this problem is to use a multiplexed scheme of driving the digits.



We can drive the anodes of each of the elements of the pair of 7 segment displays with the same outputs (one output per matching pair of segments) and use the 8th (bit 7) to select which display will turn on by driving the cathode of the desired digit to ground. This will allow us to display data on the left digit and turn the right one off, and vice-versa. If this is done rapidly enough it will appear as if both digits are showing simultaneously, due to "persistence of vision" in the human eye.

To lessen the load on the output port, the outputs drive a 74LS240 tri-state inverting buffer and the outputs of this go to the anodes of both digits of the display. The buffer's two enable lines are tied to the Primer's digital to analog (D/A) output and they tri-state the outputs when the D/A is output is 5V. This turns off the display which will be necessary when including the keypad in the circuit. When the D/A output is 0V the buffer is enabled and the outputs go to the opposite logic level as their respective inputs.

If the buffer is enabled, bit 7 selects which display to turn on. If bit 7 is high, the voltage applied to the base of Q1 will bring the cathode for the left display to ground, causing it to turn on. When this happens, the base of Q2 is pulled to ground causing it to turn off, which turns off the display on the right. When bit 7 is low, this turns off Q1 which allows the base voltage of Q2 to rise and turn on the display on the right.

```
;
; External Multiplexed Display and Keypad Decoder program.
;
OPORT       EQU   11H          ;OUTPUT PORT
IPORT       EQU   12H          ;INPUT PORT
MOS         EQU   1000H        ;MOS CALL ADDRESS
DACSRV      EQU   0EH          ;D/A SERVICE

          ORG     0FF01H

LOOP:     IN      IPORT        ;READ DIP SWITCHES
          MOV     B,A
          CALL    HEXOUT       ;DISPLAY B
          JMP     LOOP
;
; Display the hex value of B on the LEDs.  This routine must be
; called repeatedly in order for the data to be shown continuously,
; since it works on the principle of persistance of vision.  The right
; digit is turned on and off first, then the left digit is turned on and off.
;
HEXOUT:   MOV     A,B          ;GET VALUE
          ANI     0FH          ;MASK OFF UPPER NIBBLE
          CALL    BIN7SG       ;CHANGE TO 7 SEG VALUE
          OUT     OPORT        ;SEND TO PORT
          CALL    FLSHDG       ;TURN ON DISPLAY MOMENTARILY

          MOV     A,B          ;GET ORIGINAL VALUE
          ANI     0F0H         ;NOW MASK OFF LOWER NIBBLE
          RRC
          RRC
          RRC
          RRC
          CALL    BIN7SG       ;CHANGE TO 7 SEG VALUE
          ORI     80H          ;SET BIT 7 SO LEFT DIGIT IS DISPLAYED
          OUT     OPORT        ;SEND TO PORT
          CALL    FLSHDG       ;TURN ON DISPLAY MOMENTARILY
          RET
;
; Change the binary number in A to its 7 seg. output pattern.
;
BIN7SG:   PUSH    H
          PUSH    D
          LXI     D,TAB7SG     ;POINT TO START OF TABLE
          MVI     H,0
          MOV     L,A          ;HL = OFFSET INTO TABLE
          DAD     D            ;ADD TABLE ADDR TO OFFSET
          MOV     A,M          ;GET OUTPUT PATTERN
          POP     D
          POP     H
          RET
;
; TRANSLATE TABLE FOR LED OUTPUT
;
TAB7SG:   DB      40H,79H,24H,30H
          DB      19H,12H,02H,78H
          DB      00H,18H,08H,03H
          DB      46H,21H,06H,0EH
;
; This flashes on and off the digit selected by bit 7 sent to OPORT.
```

```
;
FLSHDG:   PUSH    D
          PUSH    PSW
          CALL    LEDON        ;ENABLE LEDS
          LXI     D,0FFH
DELAY1:   DCX     D
          MOV     A,D
          ORA     E
          JNZ     DELAY1
          CALL    LEDOFF       ;DISABLE LEDS
          POP     PSW
          POP     D
          RET
;
; LEDON, LEDOFF, TURN ON/OFF THE LEDS THROUGH THE D/A OUTPUT
;  5V OUT TRI-STATES THE OUTPUTS OF THE 74LS240
;  0V OUT ENABLES THE OUTPUTS OF THE 74LS240
;
LEDON:    MVI     E,0          ;SEND OUT 0V
          JMP     LEDCTL
LEDOFF:   MVI     E,0FFH       ;SEND OUT 5V
LEDCTL:   MVI     C,DACSRV     ;D/A SERVICE
          CALL    MOS
          RET
```

Display Controller Software Description

The program will be described from the lowest level subroutine to the main routine.

LEDON, LEDOFF
The subroutine LEDON turns on the selected display by sending 0V from the D/A into the 74LS240 enables and LEDOFF turns them off by sending 5V.

FLSHDG
This CALLs LEDON, goes into a delay loop and then CALLs LEDOFF. This causes the display selected by bit 7 to display for the period of time of the delay.

BIN7SG
This converts the number in the accumulator (A), which is in the range of 0 to F hex, to its corresponding binary pattern which will be used by another routine to illuminate the desired display segments. Since each element of a digit is controlled by bits 0 to 6 the bit pattern sent to the output port will form specific patterns. The table TAB7SG used by this routine has these bit patterns for digits 0 to F.

HEXOUT
This displays the hex value of the B register on the displays. This routine must be called repeatedly in order for the data to appear to be shown continuously, since it works on the principle of persistence of vision. The upper 4 bits of B are masked off leaving only the lower 4 bits which are converted to the appropriate binary pattern using BIN7SG and and this pattern is sent to the output port. Since the patterns received from BIN7SG always have bit 7 cleared, this will turn on the digit on the right when FLSHDG is called. To display the left digit, the lower 4 bits are masked off of B and the upper 4 are moved to the lower 4 bit positions. This value is converted using BIN7SG, bit 7 of the result is set to 1, and it is sent to the output port. This time when FLSHDG is called, the left digit will be displayed since bit 7 is set.

The main loop of this first example gets its input from the DIP switches, copies the value to B, CALLs HEXOUT and loops back to read the DIP switches again.

Using the Program

Build the circuit and then check your work. Now load the following program into memory and run it. With all the DIP switches in the ON position the port will input 00 and this should be shown on the displays. The binary value input to the DIP switches will be shown in hex on the displays (refer to the section at the beginning of this manual which discusses binary to hex conversion). Set the DIP switches so one digit is different than the other.

It appears that both digits are showing at the same time. To show what is really happening, we can increase the delay in FLSHDG so we can see what is really happening. Change the byte at FF4B from 00 to FF and run the program again. The displays can now be seen alternating left to right with each change in bit 7. Note that the PRIMER's digital output LEDs reflect the data sent to the output port (output bits of 0 turn on these LEDs). Watch the binary pattern on bits 6 to 0 as the digits change.

Move the DIP switches to the off position so that "FF" is displayed (this guarantees that none of the inputs are being pulled low), stop the program and change the byte at FF4B back to 00 again.

ADDRESS	DATA	DESCRIPTION	
FF01	D3	IN	12
FF02	12		
FF03	47	MOV	B,A
FF04	CD	CALL	FF0A
FF05	0A		
FF06	FF		
FF07	C3	JMP	FF01
FF08	01		
FF09	FF		
FF0A	78	MOV	A,B
FF0B	E6	ANI	0F
FF0C	0F		
FF0D	CD	CALL	FF27
FF0E	27		
FF0F	FF		
FF10	D3	OUT	11
FF11	11		
FF12	CD	CALL	FF44
FF13	44		
FF14	FF		
FF15	78	MOV	A,B
FF16	E6	ANI	F0
FF17	F0		
FF18	0F	RRC	
FF19	0F	RRC	
FF1A	0F	RRC	
FF1B	0F	RRC	
FF1C	CD	CALL	FF27
FF1D	27		
FF1E	FF		
FF1F	F6	ORI	80
FF20	80		
FF21	D3	OUT	11
FF22	11		
FF23	CD	CALL	FF44
FF24	44		
FF25	FF		
FF26	C9	RET	
FF27	E5	PUSH	H
FF28	D5	PUSH	D
FF29	11	LXI	D,FF34
FF2A	34		
FF2B	FF		
FF2C	26	MVI	H,00
FF2D	00		
FF2E	6F	MOV	L,A
FF2F	19	DAD	D
FF30	7E	MOV	A,M
FF31	D1	POP	D
FF32	E1	POP	H
FF33	C9	RET	

ADDRESS	DATA	DESCRIPTION
FF34	40	(PATTERN FOR "0")
FF35	79	(PATTERN FOR "1")
FF36	24	(PATTERN FOR "2")
FF37	30	(PATTERN FOR "3")
FF38	19	(PATTERN FOR "4")
FF39	12	(PATTERN FOR "5")
FF3A	02	(PATTERN FOR "6")
FF3B	78	(PATTERN FOR "7")
FF3C	00	(PATTERN FOR "8")
FF3D	18	(PATTERN FOR "9")
FF3E	08	(PATTERN FOR "A")
FF3F	03	(PATTERN FOR "B")
FF40	46	(PATTERN FOR "C")
FF41	21	(PATTERN FOR "D")
FF42	06	(PATTERN FOR "E")
FF43	0E	(PATTERN FOR "F")
FF44	D5	PUSH D
FF45	F5	PUSH PSW
FF46	CD	CALL FF58
FF47	58	
FF48	FF	
FF49	11	LXI D,00FF
FF4A	FF	
FF4B	00	
FF4C	1B	DCX D
FF4D	7A	MOV A,D
FF4E	B3	ORA E
FF4F	C2	JNZ FF4C
FF50	4C	
FF51	FF	
FF52	CD	CALL FF5D
FF53	5D	
FF54	FF	
FF55	F1	POP PSW
FF56	D1	POP D
FF57	C9	RET
FF58	1E	MVI E,00
FF59	00	
FF5A	C3	JMP FF5F
FF5B	5F	
FF5C	FF	
FF5D	1E	MVI E,FF
FF5E	FF	
FF5F	0E	MVI C,0E
FF60	0E	
FF61	CD	CALL 1000
FF62	00	
FF63	10	
FF64	C9	RET

Scanning the Keypad

To read a 4 by 4 matrix keypad we need 4 inputs and 4 outputs. The 4 inputs will check for a key pressed in one of the 4 columns in the current row selected by the 4 outputs. Since all of the outputs are currently being used, where do we get 4 more? We will use the same ones used for the displays but we will only use them while the displays are off (this is why we needed the circuitry to turn off both displays).

The subroutine KEYSCN (shown below), which will be added to the previous program, will be CALLed while the digits are off so that the changes in the output port will not be visible. When a key is pressed, the routine will modify the B register by shifting it left 4 bits and putting the binary value of the key into the lower 4 bits.

When KEYSCN is CALLed, output bits 0 to 3 are set to 0 to select all 4 rows at once. When the input port is read and all of the lower 4 bits are 1, this indicates no key is pressed and the routine is exited without changing B. If any of the lower 4 bits are 0 this indicates a key has been pressed. The routine then selects 1 row at a time (by setting 1 of the output bits to 0 and the others to 1) until the input port reads a 0 on any of the lower 4 bits. When this happens, the row is found, and the column is found by finding which input port bit was 0. When the row and column is found it is translated to a value from 0 to F hex. The B register is shifted 4 bits to the left and this new value is put in the lower 4 bits and the routine exits.

There is another feature in KEYSCN which keeps a key that is being held closed from modifying the B register more than 1 time. When a key is pressed, the H register is loaded with a value which defines the minimum number of times KEYSCN must be CALLed while no key is pressed before it will recognize another key press. For example, when a key is pressed, B is modified by the new key value and H is loaded with 20 hex before exiting KEYSCN. On the next entry to KEYSCN the keypad will be examined to see if a key has been pressed and if one is pressed, H is not decremented and the routine is exited without changing B. If no keys are being pressed, H is decremented and the routine is exited without changing B. If no keys are pressed for 32 (20 hex) CALLs of KEYSCN then H will be 0 and any key pressed after this time will affect the B register, and again, H will be loaded with 20 hex.

```
;
; This routine checks for a key pressed and if there is one, register B
; is shifted left one nibble and the key value is put in the low nibble.
; The subsequent CALLs after a CALL that affected B, will not affect B
; again until no key has been pressed for 20 CALLs and then a key is
; pressed again.  This prevents a single key press from being
; interpreted as more than one.
;
; On entry and exit: H=debounce counter
;
DBOUNCE  EQU     20           ;NUMBER OF CALLs FOLLOWING A KEY PRESS
KEYSCN:  XRA     A            ;A=0
         OUT     OPORT        ;SELECT ALL 4 ROWS
         IN      IPORT        ;READ ALL 4 ROWS OF KEYPAD
         ANI     0FH          ;MASK OFF UPPER 4 BITS
         CPI     0FH          ;IF 0FH THEN NO KEYS PRESSED
         JNZ     KEYSC1       ;SKIP IF KEY READY

         ; NO KEY PRESSED, SO DEC. THE DEBOUNCE (IF>0) AND EXIT
         INR     H
         DCR     H            ;IS DEBOUNCE 0?
         RZ                   ;RETURN IF YES
         DCR     H            ;DEC ONCE MORE
         RET

KEYSC1:  INR     H
         DCR     H
         RNZ                  ;IF DEBOUNCE <> 0 EXIT

         ; SCAN FOR SPECIFIC ROW
         PUSH    D
         MVI     E,01111111B ;ROW SCAN VALUE (WILL BE ROTATED)
         MVI     D,-4         ;ROW ADDER (+4=0)

KEYSC2:  MOV     A,E          ;GET ROW SCAN VALUE
         RLC                  ;ROTATE IT
         OUT     OPORT        ;SEND ROW SCAN TO OUTPUT PORT
         MOV     E,A          ;SAVE BACK NEW ROW SCAN

         MOV     A,D          ;GET ROW ADDER
         ADI     4            ;INC ROW ADDER BY 4
         MOV     D,A          ;SAVE IT
```

```
        IN      IPORT       ;SEE IF THIS ROW HAS CHAR READY
        ANI     0FH         ;MASK OFF UPPER
        CPI     0FH
        JZ      KEYSC2      ;LOOP TILL <> 0FH

        ; FIND WHAT COL. IT'S IN
        MVI     L,0FFH      ;SET SO INR WILL MAKE 0
KEYPD1: INR     L
        RRC
        JC      KEYPD1      ;LOOP TILL NO CY
        ; NOW ADD COL. TO ROW ADDER
        MOV     A,D         ;GET ROW ADDER
        ADD     L
        MOV     L,A         ;L IS THE KEY PRESSED (0 TO F HEX)
        ; SHIFT B LEFT 1 NIBBLE AND PUT L IN LOWER NIBBLE
        MOV     A,B         ;SHIFT B
        ADD     A
        ADD     A
        ADD     A
        ADD     A           ;THIS SHIFTS LEFT PADDING 0's
        ADD     L           ;PUT L IN LOWER NIBBLE
        MOV     B,A         ;NEW B REG

        MVI     H,DBOUNCE   ;DEBOUNCE VAL. (NO KEYS ACCEPTED TILL 0)
        POP     D
        RET
```

Using the Program

The previous program will be modified slightly (assuming it is still in memory) by putting CALL KEYSCN in the program in place of IN IPORT, MOV B,A and a new subroutine will be added at the end. (Pay close attention to the addresses when entering the following program, since there is a skip in sequence of the addresses after the first three.) When you run the program you should see the key you press on the right display and the digit that was there before, moved to the left display. As you have just seen demonstrated in this application, multiplexing allows you to greatly extend the capabilities of an output port.

ADDRESS	**DATA**	**DESCRIPTION**
FF01	CD	CALL FF65
FF02	65	
FF03	FF	
:	:	
:	:	
FF65	AF	XRA A
FF66	D3	OUT 11
FF67	11	
FF68	DB	IN 12
FF69	12	
FF6A	E6	ANI 0F
FF6B	0F	
FF6C	FE	CPI 0F
FF6D	0F	
FF6E	C2	JNZ FF76
FF6F	76	
FF70	FF	
FF71	24	INR H
FF72	25	DCR H
FF73	C8	RZ
FF74	25	DCR H
FF75	C9	RET
FF76	24	INR H
FF77	25	DCR H
FF78	C0	RNZ
FF79	D5	PUSH D
FF7A	1E	MVI E,7F
FF7B	7F	
FF7C	16	MVI D,FC
FF7D	FC	
FF7E	7B	MOV A,E
FF7F	07	RLC
FF80	D3	OUT 11
FF81	11	
FF82	5F	MOV E,A
FF83	7A	MOV A,D

ADDRESS	**DATA**	**DESCRIPTION**
FF84	C6	ADI 04
FF85	04	
FF86	57	MOV D,A
FF87	DB	IN 12
FF88	12	
FF89	E6	ANI 0F
FF8A	0F	
FF8B	FE	CPI 0F
FF8C	0F	
FF8D	CA	JZ FF7E
FF8E	7E	
FF8F	FF	
FF90	2E	MVI L,FF
FF91	FF	
FF92	2C	INR L
FF93	0F	RRC
FF94	DA	JC FF92
FF95	92	

```
FF96        FF
FF97        7A    MOV    A,D
FF98        85    ADD    L
FF99        6F    MOV    L,A
FF9A        78    MOV    A,B
FF9B        87    ADD    A
FF9C        87    ADD    A
FF9D        87    ADD    A
FF9E        87    ADD    A
FF9F        85    ADD    L
FFA0        47    MOV    B,A
FFA1        26    MVI    H,14
FFA2        14
FFA3        D1    POP    D
FFA4        C9    RET
```

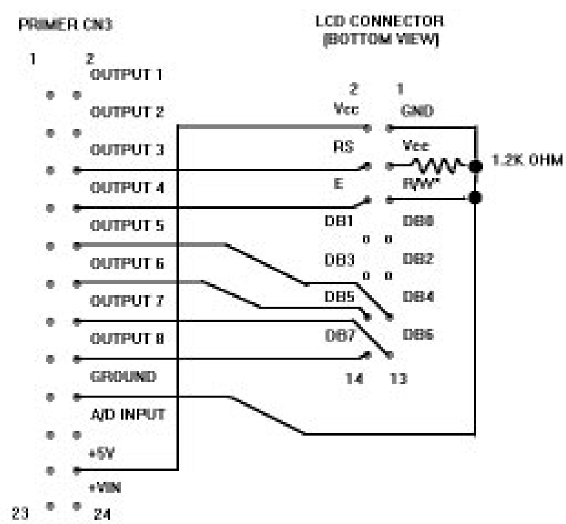
Application 7: Controlling an LCD Module

Purpose: To demonstrate writing characters and cursor positioning on an LCD Module display.

Discussion:

There are many LCD Module display manufacturers and most use the same 14 pin dual row header interface and the same controller chip, the HD44780. These modules display characters only, not graphics (with the exception that you can simulate graphics by dynamically defining your own characters). You may find these displays in surplus catalogs, or parts catalogs such as DIGI-KEY. Some example parts are:

DIGI-KEY Part.	Description	(Call 1-800-DIGI-KEY)
OP116-ND	OPTREX 16x1 standard LCD dot matrix module	
VT216-ND	Varitronix Ltd 16x2 standard LCD dot matrix module	



The HD44780 controller has two registers: one for data and one for commands. The data register allows you to write characters to the display, define your own characters and read display memory. The command register allows writing of several commands relating to display control and initialization and also reading the controller's status and address counter. In the interest of simplicity we will write to the controller registers in this application.

The controller can transfer data in 8 or 4 bit mode, so we will use it in 4 bit mode since we have only 8 output ports and we need at least 4 to transfer data (DB4 to DB7) and 2 for the control lines (RS and E).

```
;
; LCD DRIVER CODE
;
OPORT    EQU      11H          ;OUTPUT PORT
IPORT    EQU      12H          ;INPUT PORT
KEYIN    EQU      0BH          ;SERVICE FOR READING KEYPAD
MOS      EQU      1000H        ;MOS CALL ADDRESS

;
; OPORT BITS ARE DEFINED AS FOLLOWS:
;  7   6   5   4   3   2   1   0
; DB7 DB6 DB5 DB4  E   RS (not used)
```

```
;

         ORG      0FF01H
         MVI      A,11110011B ; RS, E, = 0.
         OUT      OPORT

         ; RESET CODE
         CALL     DELAY
         CALL     DELAY
         MVI      A,30H
         CALL     DLNOUT
         CALL     DLNOUT
         CALL     DLNOUT

         ; INIT CODE
         MVI      A,00100000B ;SET 4 BIT MODE
         CALL     DLNOUT

         MVI      A,00101000B ;SET 4 BIT, 2 LINE, 5 BY 7 DOTS
         CALL     OUTCMD
         MVI      A,00001000B ;DISPLAY OFF
         CALL     OUTCMD
         MVI      A,00000001B ;DISPLAY ON
         CALL     OUTCMD
         MVI      A,00001110B ;TURN ON DISPLAY, CURSOR, AND BLINK.
         CALL     OUTCMD
         MVI      A,00000110B ;ENTRY MODE SET. INC. W/CURSOR MOVEMENT
         CALL     OUTCMD

         LXI      H,TSTSTR
         CALL     SHWSTR

LOOP:    NOP
         NOP
         NOP
         NOP
         NOP                  ;THESE ARE PLACE HOLDERS

         MVI      C,KEYIN
         CALL     MOS         ;GET A KEY
         MVI      A,'0'
         ADD      L           ;CONVERT 0 TO 9 IN L TO ASCII
         CALL     OUTDTA      ;DISPLAY THE CHAR
         JMP      LOOP

TSTSTR:  DB 'The Primer.',0

;
; Show the string pointed to by HL.  When 0 is encountered the program exits
; returning HL pointing to the byte after the 0.
;
SHWSTR:  MOV      A,M         ;READ STRING
         INX      H           ;CHANGE POINTER
         ORA      A           ;SEE IF A=0
         RZ                   ;EXIT IF END OF STRING
         CALL     OUTDTA      ;DISPLAY CHARACTER
         JMP      SHWSTR

;
; Send A to the LCD with RS=1, high nibble first and low second.
;
OUTDTA:  MVI      E,0100B     ;SET RS
         JMP      OBYT1
;
; Send A to the LCD with RS=0, high nibble first and low second.
;
OUTCMD:  MVI      E,0         ;RS=0
OBYT1:   MOV      B,A         ;SAVE IN B
         ANI      0F0H        ;MASK OFF LOW NIBBLE
```

```
        ORA     E           ;MAYBE MODIFY RS
        CALL    DLNOUT      ;SEND IT
        MOV     A,B
        ADD     A
        ADD     A
        ADD     A
        ADD     A           ;LOWER IS MOVED TO UPPER, PADDING 0'S
        ORA     E           ;MAYBE MODIFY RS
        CALL    DLNOUT
        RET

;
; This delays and falls through to OUTNIB
;
DLNOUT: CALL    DELAY

;
; Send data in A to the LCD.  Assumes bits 0 to 3 have been properly set.
;
OUTNIB: PUSH    PSW
        ANI     11110111B   ;CLEAR E
        OUT     OPORT       ;SEND NIBBLE
        ORI     1000B       ;SET E BIT
        OUT     OPORT
        ANI     11110111B   ;CLEAR E BIT
        OUT     OPORT
        POP     PSW
        RET

;
; 5ms time delay for 8085 is 24 t states
;
DELAY:  PUSH    PSW         ;approx 5ms for 3.072 MHZ clock
        PUSH    H
        LXI     H,641
DLAY2:  DCX     H           ;6 T STATES
        MOV     A,H         ;4 T STATES
        ORA     L           ;4 T STATES
        JNZ     DLAY2       ;10 T STATES
        POP     H
        POP     PSW
        RET
```

Program Description:

According to the schematic, the output port controls the LCD and the port bits are connected as follows:

output port bits:	7	6	5	4	3	2	1	0
LCD header pins:	DB7	DB6	DB5	DB4	E	RS	(not used)	

The routine OUTNIB assumes the upper nibble of A has the value you want to output and bit 2 (RS) is set to 0 for a command or 1 for data. This value is output first with bit 3 (E) low, then high, then low again. The E input when brought high momentarily causes the data input to RS and DB4 through DB7 to be accepted by the LCD controller. DLNOUT works the same except a 5mS delay (provided by DELAY) occurs before executing OUTNIB.

DELAY is called because the method we used to interface to the LCD Module prevents us from reading the LCD module. This in turn prevents us from reading the busy flag which tells us the LCD controller is busy executing a command and cannot receive another yet. DELAY gets us around this problem because it takes longer to execute than any of the LCD controller's instructions insuring that the LCD will not be busy by the time it is finished. In the initialization section some longer delays are needed, so DELAY is called repeatedly.

OUTCMD and OUTDTA use the same core routine but they select RS of 0 and 1 respectively. This core routine takes the byte in A and breaks it into two nibbles and sends them to DLNOUT (high nibble first).

The main routine does the hardware reset for the HD44780, followed by the display mode setup. Then SHWSTR sends the ASCII string pointed to by HL to the display via OUTDTA, and then the MOS subroutine KEYIN is called to get a key from the keypad and the key is translated to ASCII and sent to the display (via OUTDTA) and then it loops back to get another key.

Connect Primer connector CN3 to the LCD according to the schematic and then enter the following program. When you run the program "The Primer._" should be shown on the display and when you press one of keys "0" to "9" they will be shown on the display, with each new character displayed to the right of the previous.

Eventually if you press the keys enough times you will eventually run out of display area. The characters are now being stored in an area that is not being displayed. If you have a 2 line display and you send enough characters, they will start showing up on the second line and after more are sent they will eventually show up on the first line.

ADDRESS	**DATA**	**DESCRIPTION**	
FF01	3E	MVI	A,F3
FF02	F3		
FF03	D3	OUT	11
FF04	11		
FF05	CD	CALL	FF8D
FF06	8D		
FF07	FF		
FF08	CD	CALL	FF8D
FF09	8D		
FF0A	FF		
FF0B	3E	MVI	A,30
FF0C	30		
FF0D	CD	CALL	FF7B
FF0E	7B		
FF0F	FF		
FF10	CD	CALL	FF7B
FF11	7B		
FF12	FF		
FF13	CD	CALL	FF7B
FF14	7B		
FF15	FF		
FF16	3E	MVI	A,20
FF17	20		
FF18	CD	CALL	FF7B
FF19	7B		
FF1A	FF		
FF1B	3E	MVI	A,28
FF1C	28		
FF1D	CD	CALL	FF68
FF1E	68		
FF1F	FF		
FF20	3E	MVI	A,08
FF21	08		
FF22	CD	CALL	FF68
FF23	68		
FF24	FF		
FF25	3E	MVI	A,01
FF26	01		
FF27	CD	CALL	FF68
FF28	68		
FF29	FF		
FF2A	3E	MVI	A,0E
FF2B	0E		
FF2C	CD	CALL	FF68
FF2D	68		
FF2E	FF		
FF2F	3E	MVI	A,06
FF30	06		
FF31	CD	CALL	FF68
FF32	68		
FF33	FF		
FF34	21	LXI	H,FF4D
FF35	4D		
FF36	FF		
FF37	CD	CALL	FF59
FF38	59		
FF39	FF		
FF3A	00	NOP	
FF3B	00	NOP	
FF3C	00	NOP	
FF3D	00	NOP	
FF3E	00	NOP	
FF3F	0E	MVI	C,0B
FF40	0B		

ADDRESS	**DATA**	**DESCRIPTION**	
FF41	CD	CALL	1000
FF42	00		
FF43	10		
FF44	3E	MVI	A,30
FF45	30		
FF46	85	ADD	L
FF47	CD	CALL	FF63
FF48	63		
FF49	FF		
FF4A	C3	JMP	FF3A
FF4B	3A		
FF4C	FF		
FF4D	54	"T"	
FF4E	68	"h"	
FF4F	65	"e"	
FF50	20	" "	
FF51	50	"P"	
FF52	72	"r"	
FF53	69	"i"	
FF54	6D	"m"	
FF55	65	"e"	

FF56	72	"r"	
FF57	2E	"."	
FF58	00	(end marker)	
FF59	7E	MOV	A,M
FF5A	23	INX	H
FF5B	B7	ORA	A
FF5C	C8	RZ	
FF5D	CD	CALL	FF63
FF5E	63		
FF5F	FF		
FF60	C3	JMP	FF59
FF61	59		
FF62	FF		
FF63	1E	MVI	E,04
FF64	04		
FF65	C3	JMP	FF6A
FF66	6A		
FF67	FF		
FF68	1E	MVI	E,00
FF69	00		
FF6A	47	MOV	B,A
FF6B	E6	ANI	F0
FF6C	F0		
FF6D	B3	ORA	E
FF6E	CD	CALL	FF7B
FF6F	7B		
FF70	FF		
FF71	78	MOV	A,B
FF72	87	ADD	A
FF73	87	ADD	A
FF74	87	ADD	A
FF75	87	ADD	A
FF76	B3	ORA	E
FF77	CD	CALL	FF7B
FF78	7B		
FF79	FF		
FF7A	C9	RET	
FF7B	CD	CALL	FF8D
FF7C	8D		
FF7D	FF		
FF7E	F5	PUSH	PSW
FF7F	E6	ANI	F7
FF80	F7		
ADDRESS	**DATA**	**DESCRIPTION**	
FF81	D3	OUT	11
FF82	11		
FF83	F6	ORI	08
FF84	08		
FF85	D3	OUT	11
FF86	11		
FF87	E6	ANI	F7
FF88	F7		
FF89	D3	OUT	11
FF8A	11		
FF8B	F1	POP	PSW
FF8C	C9	RET	
FF8D	F5	PUSH	PSW
FF8E	E5	PUSH	H
FF8F	21	LXI	H,0281
FF90	81		
FF91	02		
FF92	2B	DCX	H
FF93	7C	MOV	A,H
FF94	B5	ORA	L
FF95	C2	JNZ	FF92
FF96	92		
FF97	FF		
FF98	E1	POP	H
FF99	F1	POP	PSW
FF9A	C9	RET	

In the next example we will modify the program to use the Set DD RAM Address command which will in effect allow us to control the cursor position. Modify the following addresses and run the program. You will see that each key typed will show up on the screen in the same place even though it is still automatically incrementing the cursor position. This is because the address is set for that cursor position after the cursor has been incremented.

You may want to experiment with different cursor positions. If you have a 2 line display, you can move the cursor to line 2 by sending 10000000b + 40h (C0h) to OUTCMD, where 10000000b is the command for Set DD RAM Address and 40h is the offset for line 2.

ADDRESS	**DATA**	**DESCRIPTION**	
FF3A	3E	MVI	A,8B
FF3B	8B		
FF3C	CD	CALL	FF68
FF3D	68		
FF3E	FF		

Application 8: Capacitance Meter

Purpose: This application shows how to use the PRIMER as a capacitance meter.

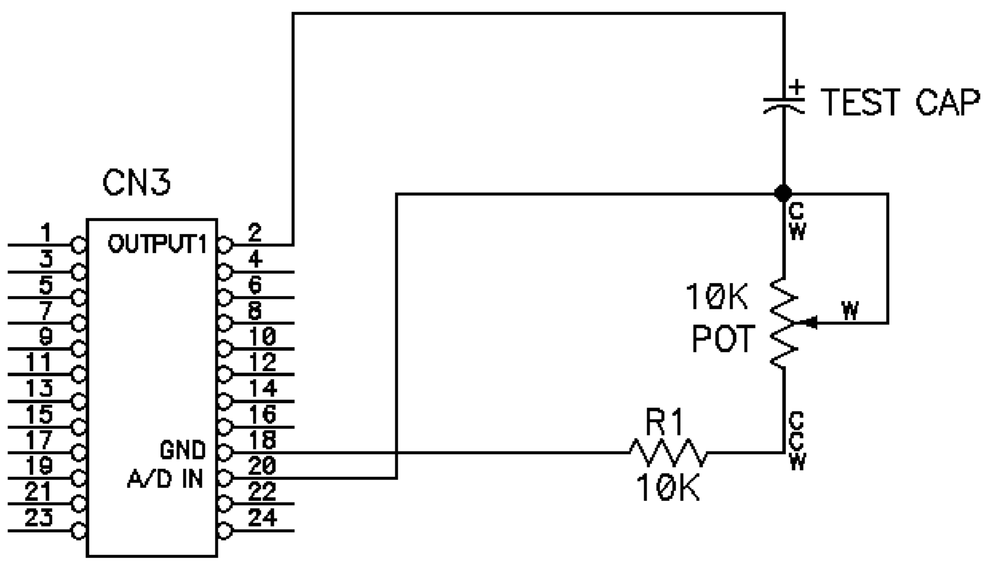
Discussion:

This application is an example of how the PRIMER can be used as a useful piece of electronic test equipment. The Capacitance Meter application can be used to accurately measure capacitors ranging from .01 to 220 uF.

The parts required are minimal. Items needed are:

1) 10K ohm mutiturn potentiometer
2) 10K ohm 1/4 watt resistor
3) one capacitor of a known value in the range of 1 to 100 uF (calibration cap)
4) several capacitors, for testing, in the range of .01uF to 300 uF
5) breadboard

The circuit is very simple. Follow the schematic below to assemble the circuit.



CIRCUIT DESCRIPTION

The PRIMER uses the on-board D/A converter, the comparator, OUTPUT1, and the timer within the 8155 to measure capacitance. The capacitor is connected in series with R1. The open end of the capacitor is then tied to OUTPUT1 and the open end of R1 is tied to ground. The D/A output of the PRIMER is tied to the non-inverting side if the op-amp comparator while the capacitor-R1 connection is tied to the inverting side. When the program first starts, the D/A is set slightly above ground potential and OUTPUT1 is set LOW. The capacitor now discharges through R1. The program waits for the comparator to go HIGH which indicates the capacitor voltage has fallen below the D/A voltage which guarantees a fully discharged cap. The program then starts the timer and sets OUTPUT1 HI which starts the capacitor charging. The timer is driven by a 307.2 Khz input Clock. The timer works by loading a “count” value into a register within the timer. The timer then decrements this value every time the input clock completes a cycle. When the value reaches 0, the timer generates an output pulse then reloads the register with the “count” value and the process starts all over again. By increasing the value in the “count” register the pulse rate can be slowed down and vise-versa. The Capacitor Meter program uses the timer as the time-base by counting how many pulses are generated by the timer while the capacitor is charging. The larger the cap, the longer the charge time, therefore the more pulses will be generated. The voltage across the resistor is near VCC when OUTPUT1 first goes HIGH, then ramps down as the capacitor charges. When the voltage falls below the D/A voltage the comparator output goes HIGH, stopping the timer. The current pulse count is then converted to decimal and displayed on the LED display.

CALIBRATION

The Capacitor Meter program works by measuring the time required to charge the capacitor through a resistor. The time-base is generated by the timer within the 8155. The Capacitor Meter program has 2 user selectable timer scales to choose from. The LO scale can measure capacitor values up to 9.999 uF while the HI scale can measure values up to 999.9 uF. Two scales were chosen to provide good resolution to small caps but also have the ability to measure large caps. The scale is determined by the “count” value loaded into the 8155 timer. A value of 10 is loaded in the “count” register for low scale and a value of 1000 for the high scale. Once the capacitor is charged the pulse count is displayed on the LED display in decimal. A decimal point is then placed on the LED display in the “10's” place for high scale and in the “1000's” place for low scale. So the actual value written to the display for a 1uF capacitor measured in low scale would be “1000". Once the decimal point is added it looks like “1.000". Because the Capacitor Meter uses a fixed time base to calculate capacitance, the resistor value must be determined to calibrate the Capacitor Meter.

The equation for capacitor charge time of an RC circuit is:

$$T = 5*R*C$$

Where:

T = Time in Seconds

R = Resistance in Ohms
C = Capacitance in Farads

Solving for R gives:

R = T/5C

The equation above is used to determine the approximate resistance value for the Capacitor Meter program.

Thus we can calculate the actual resistance value:

(1 / 307.2 Khz) * 10000 / 5 * 1uF = 6400 Ohms

This is the value for the total resistance. Keep in mind that the PRIMER has an in-circuit resistor with a value of 100 K ohms in parallel with the calibration resistor. The actual resistance value will be slightly above the theoretical value because the program does not charge the capacitor 100%. Other factors such as ESR (Equivalent Series Resistance) cause errors to grow quit large as capacitor values increase into the hundreds of uF's range. The value calculated is a good starting point but some final tweaking will be required.

USING THE PROGRAM

Following is the assembly language listing of the Capacitor Meter program:

```
;      CAPACITOR METER

P IN            EQU     12H     ;ADDRESS OF PORT A
P OUT           EQU     11H     ;ADDRESS OF PORT B
P 8155          EQU     10H     ;ADDRESS OF 8155 CONTROL REGISTER
P CNTLO         EQU     14H     ;ADDRESS OF LO BYTE OF COUNTER
P CNTHI         EQU     15H     ;ADDRESS OF HI BYTE OF COUNTER
TMRSTRT         EQU     0CDH    ;START TIMER COMMAND
TMRSTOP         EQU     8DH     ;STOP TIMER COMMAND
ADCVAL          EQU     01H     ;VALUE OF 1 TO D/A
TMRMODE         EQU     0C0H    ;SINGLE PULSE AND RELOAD
DSPORT          EQU     40H     ;ADDRESS OF LED DISPLAY DATA
DSPCMD          EQU     41H     ;ADDRESS OF LED DISPLAY COMMAND REGISTER
MOS             EQU     1000H   ;MOS SERVICE


      ORG     0FF01H            ;ORIGIN OF MEM IN 8155

START:
      MVI     E,ADCVAL          ;SET D/A TO LOW V
      MVI     C,0EH             ;SERVICE 0E (DACOUT)
      CALL    MOS               ; MOS SERVICE

      MVI     A,TMRSTOP         ;STOP TIMER
      OUT     P 8155

      LXI     D,0000H           ;CLR D,E (PUT 0'S IN LED DISPLAY)
      MVI     C,13H             ;CALL LEDDEC ROUTINE IN MOS
```

```
        CALL    MOS             ;

        MVI     A,80H           ;"WRITE COMMAND" FOR DIGIT 0
        OUT     DSPCMD

        MVI     A,00010111B     ;WRITE "F" TO DIGIT 0
        OUT     DSPORT

        MVI     A,81H           ;"WRITE COMMAND" FOR DIGIT 1
        OUT     DSPCMD

        MVI     A,11000001B     ;WRITE "u" TO DIGIT 1
        OUT     DSPORT

WAIT:
        IN    12H               ;GET SW0 SETTING
        ANI     01              ;MASK OFF OTHER SWCHS

        MVI     C,5             ;DECIMAL DIG 5
        MOV     B,A
        CALL    DECPNT          ;PLACES THE DECIMAL POINT
        XRI     00000001B       ;COMPLIMENT SW SETTING
        MOV     B,A
        MVI     C,3
        CALL    DECPNT
        MOV     B,A             ;SAVE SWITCH VAL

        MVI     C,16H           ;CALL SWITCH STAT
        CALL    MOS

        MOV     A,H
        RAR                     ;IF KEY WAS PRESSED,
        JNC     WAIT            ; THEN GO !

        MOV     A,B             ;IF DIPSWITCH1 IS ON
        RAR
        JNC     HI              ;THEN GOTO HI

LO:     MVI     A,0E8H          ;LOAD TIMER W/ 1000 D
        OUT     P CNTLO
        MVI     A,0C3H
        OUT     P CNTHI
        JMP     GO

HI:     MVI     A,0AH           ;LOAD TIMER W/ 10 D
        OUT     P CNTLO
        MVI     A,0C0H
        OUT     P CNTHI

GO:     XRA     A               ;CLEAR ACC
        OUT     11H             ;SET PORT A LO

POLE1:          RIM             ;POLE TO MAKE SURE CAP IS DISCHARGED
        RAL                     ;CHECK IF SID HAS GONE HIGH
        JNC     POLE1           ;IF NOT POLE

        MVI     A,0FFH          ;SET OUTPUT1 HIGH
        OUT     11H
```

```
      MVI     A,TMRSTRT        ;START TIMER
      OUT     P 8155

LUP:  MVI     A,1FH            ;CLEAR 7.5 INT
      SIM                      ;SET INTERUPT MASK
POLE2:
      RIM                      ;LOAD ACC WITH INT FLG STATUS
      RAL                      ;CHECK IF SID HAS GONE HIGH
      JC      EXIT             ;IF SO THEN EXIT
      RAL                      ;CHECH IF 7.5 INT WENT SET
      JNC     POLE2            ;IF NOT THEN POLE
      INX     D                ;INCREMENT D AND E
      JMP     LUP              ;GOTO LUP

EXIT: MVI     C,13H            ;CALL LEDDEC ROUTINE IN MOS
      CALL    MOS

      MOV     A,B
      MVI     C,3
      CALL    DECPNT           ;PLACES THE DECIMAL POINT
      XRI     00000001B        ;COMPLIMENT SW SETTING
      MOV     B,A
      MVI     C,5
      CALL    DECPNT

STP:  MVI     C,16H            ;CALL KEYPAD STAT
      CALL    MOS

      MOV     A,H
      RAR                      ;IF A BUTTON WAS NOT PRESSED,
      JNC     STP              ;THEN POLE
      JMP     START            ;ELSE TEST ANOTHER CAP
;******************************************************
; DECPNT:   IN: LOAD C W/ DIGIT #, LOAD B WITH A 1 OR 0
;                              B=1 DEC PNT ON, B=0 DEC PNT OFF
;           OUT: NOTHING
;-------------------------------------------------------
DECPNT:
      PUSH  PSW

      MOV   A,B
      RAL                      ;MOVE BIT 0 TO BIT 3 LOCATION
      RAL
      RAL
      ANI   00001000B
      MOV   B,A

      MVI   A,60H
      ADD   C                  ;COMMAND TO READ DIGIT
      OUT   DSPCMD

      IN    DSPORT             ;GET SEGMENT VALUES
      STA   TEMP               ;SAVE A REG

      MVI   A,80H              ;COMMAND TO WRITE DIGIT
      ADD   C
      OUT   DSPCMD
```

```
       LDA    TEMP                ;RECALL A VALUE
       ANI    11110111B           ;TURN OFF DECIMAL POINT
       ORA    B                   ;TURN ON IF SUPOSED TO IS ON
       OUT    DSPORT              ;WRITE A TO DIGIT

       POP    PSW
       RET
TEMP   DS     1

       END
```

Load the following program into memory:

ADDRESS	DATA	INSTRUCTION	
FF01	1E	MVI	E,01
FF02	01		
FF03	0E	MVI	C,0E
FF04	0E		
FF05	CD	CALL	1000
FF06	00		
FF07	10		
FF08	3E	MVI	A,8D
FF09	8D		
FF0A	D3	OUT	10
FF0B	10		
FF0C	11	LXI	D,0000
FF0D	00		
FF0E	00		
FF0F	0E	MVI	C,13
FF10	13		
FF11	CD	CALL	1000
FF12	00		
FF13	10		

ADDRESS	DATA	INSTRUCTION	
FF14	3E	MVI	A,80
FF15	80		
FF16	D3	OUT	41
FF17	41		
FF18	3E	MVI	A,17
FF19	17		
FF1A	D3	OUT	40
FF1B	40		
FF1C	3E	MVI	A,81
FF1D	81		
FF1E	D3	OUT	41
FF1F	41		
FF20	3E	MVI	A,C1
FF21	C1		
FF22	D3	OUT	40
FF23	40		
FF24	DB	IN	12
FF25	12		

ADDRESS	DATA	INSTRUCTION	
FF26	E6	ANI	01
FF27	01		
FF28	0E	MVI	C,05
FF29	05		
FF2A	47	MOV	B,A
FF2B	CD	CALL	FF99
FF2C	99		
FF2D	FF		
FF2E	EE	XRI	01
FF2F	01		
FF30	47	MOV	B,A
FF31	0E	MVI	C,03
FF32	03		
FF33	CD	CALL	FF99
FF34	99		
FF35	FF		
FF36	47	MOV	B,A
FF37	0E	MVI	C,16
FF38	16		
FF39	CD	CALL	1000
FF3A	00		

FF3B	10		
FF3C	7C	MOV	A,H
FF3D	1F	RAR	
FF3E	D2	JNC	FF24
FF3F	24		
FF40	FF		
FF41	78	MOV	A,B
FF42	1F	RAR	
FF43	D2	JNC	FF51
FF44	51		
FF45	FF		
FF46	3E	MVI	A,E8
FF47	E8		
FF48	D3	OUT	14
FF49	14		
FF4A	3E	MVI	A,C3
FF4B	C3		
FF4C	D3	OUT	15
FF4D	15		
FF4E	C3	JMP	FF59
FF4F	59		
FF50	FF		
FF51	3E	MVI	A,0A
FF52	0A		
FF53	D3	OUT	14
FF54	14		
FF55	3E	MVI	A,C0
FF56	C0		
FF57	D3	OUT	15
FF58	15		
FF59	AF	XRA	A
FF5A	D3	OUT	11
FF5B	11		
FF5C	20	RIM	
FF5D	17	RAL	
FF5E	D2	JNC	FF5C
FF5F	5C		
FF60	FF		
FF61	3E	MVI	A,FF
FF62	FF		

ADDRESS	**DATA**	**INSTRUCTION**	
FF63	D3	OUT	11
FF64	11		
FF65	3E	MVI	A,CD
FF66	CD		
FF67	D3	OUT	10
FF68	10		
FF69	3E	MVI	A,1F
FF6A	1F		
FF6B	30	SIM	
FF6C	20	RIM	
FF6D	17	RAL	
FF6E	DA	JC	FF79
FF6F	79		
FF70	FF		
FF71	17	RAL	
FF72	D2	JNC	FF6C
FF73	6C		

FF74	FF		
FF75	13	INX	D
FF76	C3	JMP	FF69
FF77	69		
FF78	FF		
FF79	0E	MVI	C,13
FF7A	13		
FF7B	CD	CALL	1000
FF7C	00		
FF7D	10		
FF7E	78	MOV	A,B
FF7F	0E	MVI	C,03
FF80	03		
FF81	CD	CALL	FF99
FF82	99		
FF83	FF		
FF84	EE	XRI	01
FF85	01		
FF86	47	MOV	B,A
FF87	0E	MVI	C,05
FF88	05		
FF89	CD	CALL	FF99
FF8A	99		
FF8B	FF		
FF8C	0E	MVI	C,16
FF8D	16		
FF8E	CD	CALL	1000
FF8F	00		
FF90	10		
FF91	7C	MOV	A,H
FF92	1F	RAR	
FF93	D2	JNC	FF8C
FF94	8C		
FF95	FF		
FF96	C3	JMP	FF01
FF97	01		
FF98	FF		
FF99	F5	PUSH	PSW
FF9A	78	MOV	A,B
FF9B	17	RAL	
FF9C	17	RAL	
FF9D	17	RAL	
FF9E	E6	ANI	08
FF9F	08		

ADDRESS	**DATA**	**INSTRUCTION**	
FFA0	47	MOV	B,A
FFA1	3E	MVI	A,60
FFA2	60		
FFA3	81	ADD	C
FFA4	D3	OUT	41
FFA5	41		
FFA6	DB	IN	40
FFA7	40		
FFA8	32	STA	FFBA
FFA9	BA		
FFAA	FF		
FFAB	3E	MVI	A,80
FFAC	80		

```
FFAD          81      ADD     C
FFAE          D3      OUT     41
FFAF          41
FFB0          3A      LDA     FFBA
FFB1          BA
FFB2          FF
FFB3          E6      ANI     F7
FFB4          F7
FFB5          B0      ORA     B
FFB6          D3      OUT     40
FFB7          40
FFB8          F1      POP     PSW
FFB9          C9      RET
```

After loading the program, set the pot for midscale and install the calibration cap. Press FUNC. then RUN (to enter run mode). The display should read "0000 uF" with a decimal point in the "10's" place or in the "1000's" place. Change DIPSWITCH 0 to change the decimal point position. With the decimal point in the “10's” place, the Capacitor Meter program can measure capacitor values up to 999.9 uF. With the decimal point in the “1000's” place, values up to 9.999 uF can be measured. Once the scale is chosen, press any key on the keypad to test the cap. A value will be returned to the display which represents capacitance. Press another key to start the program over again. Adjust the pot and continue to test the calibration capacitor until an accurate reading is realized. Test several caps and record the results. Accuracies greater than 99% are possible.

NOTE- The most accurate results will be obtained when the PRIMER is powered up and the temperature allowed to stabilize over a period of 15 to 30 minutes.

Application 9: Interfacing a Stepper Motor to the PRIMER

Purpose: To show how a computer can be used to perform motion control using a stepper motor.

Goals:

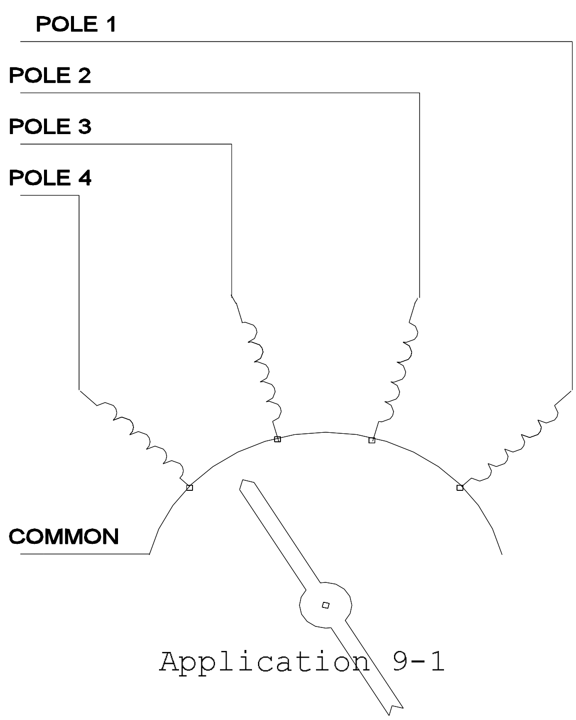
1. Build a stepper motor driver circuit.
2. Load a program that will demonstrate stepper motor control.

Materials:

1) PRIMER trainer
1) breadboard
1) SM4200 4 Phase stepper motor (Jameco part #105890. Call 1-800-831-4242)
1) 7404 Hex Inverter
4) 2N3904 NPN Transistors
4) 1N4001 Diodes
4) 1K Ohm, 1/4 Watt Resistor
1) 220 Ohm, 1/4 Watt Resistor

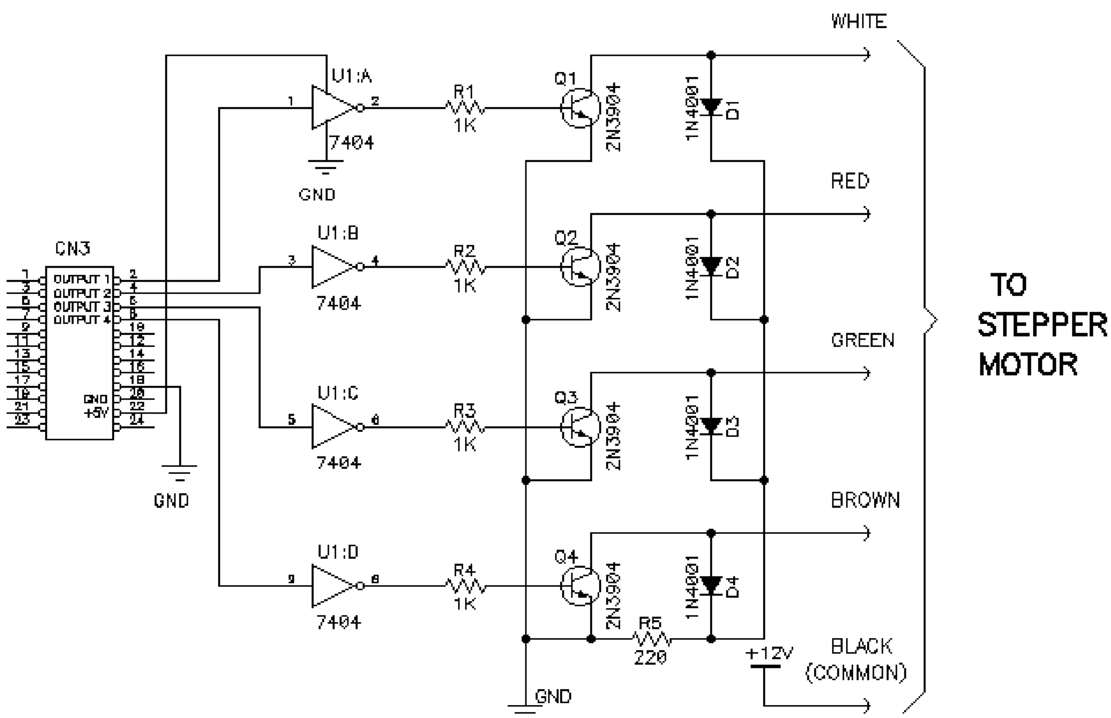
Discussion:

This lab shows how the PRIMER can be used to drive a stepper motor. The diagram below shows the electrical equivalent of a 4 phase stepper motor connected to the output port of the PRIMER. When the program first starts, OUTPUT2 and OUTPUT3 are energized. The stepper is now held in position because of the magnetic force pulling the rotor between the energized poles. A step can be made by turning on OUTPUT4 while turning off OUTPUT2. This moves the rotor one increment. To move one more increment, OUTPUT1 is turned on while OUTPUT3 is turned off. To go back to the original position, the sequence would be as follows: Turn on OUTPUT3 while turning off OUTPUT1, turn on OUTPUT2 while turning off OUTPUT4.



Circuit Description and Construction:

The stepper motor cannot connect directly to the output port of the PRIMER because it uses 5 volt logic levels while the stepper motor operates on 12 volts. The current demand of the stepper motor is also a problem, since computer logic supplies very low current compared to the stepper motor's needs. The solution to these problems is an interface circuit. The circuit shown in the schematic provides the necessary interface from 5 volt logic to a 12 volt source required by the stepper. Transistors Q1-Q4 provide the current and voltage amplification while diodes D1-D4 and resistor R5 provide a feedback path for the back EMF generated when the poles are de-energized. The inverters are used to convert the negative logic on the PRIMER to positive logic and to prevent the stepper from being energized when the



PRIMER is reset. The interface is connected to the low nibble (4 bits) of the PRIMER output port. The driver circuit should be built on a breadboard following the schematic. Once built, a small piece of solid wire should be tightly wrapped around the shaft of the stepper motor to serve as a pointing device.

Note - The stepper motor and driver circuit are powered from a power supply separate from the PRIMER itself. This is necessary because of the large current draw and noise produce by the stepper motor.

Using the Program:

Load the following program into memory:

ADDRESS	DATA	INSTRUCTION	
FF01	1E	MVI	E,37
FF02	37		
FF03	16	MVI	D,01
FF04	01		
FF05	0E	MVI	C,11
FF06	11		
FF07	CD	CALL	1000
FF08	00		
FF09	10		
FF0A	1E	MVI	E,FB
FF0B	FB		
FF0C	15	DCR	D
FF0D	CD	CALL	1000
FF0E	00		
FF0F	10		
FF10	3E	MVI	A,33
FF11	33		
FF12	32	STA	FFAC
FF13	AC		
FF14	FF		
FF15	AF	XRA	A
FF16	32	STA	FFAD
FF17	AD		
FF18	FF		
FF19	6F	MOV	L,A
FF1A	47	MOV	B,A
FF1B	C3	JMP	FF43
FF1C	43		
FF1D	FF		
FF1E	78	MOV	A,B
FF1F	32	STA	FFAD
FF20	AD		
FF21	FF		
FF22	CD	CALL	FF4B
FF23	4B		
FF24	FF		
FF25	3A	LDA	FFAD
FF26	AD		
FF27	FF		
FF28	47	MOV	B,A
FF29	16	MVI	D,00
FF2A	00		
FF2B	58	MOV	E,B
FF2C	0E	MVI	C,13
FF2D	13		
FF2E	CD	CALL	1000
FF2F	00		
FF30	10		
FF31	7D	MOV	A,L
FF32	90	SUB	B
FF33	CA	JZ	FF1E
FF34	1E		
FF35	FF		

ADDRESS	DATA	INSTRUCTION	
FF36	DA	JC	FF3F
FF37	3F		
FF38	FF		
FF39	04	INR	B
FF3A	AF	XRA	A
FF3B	5F	MOV	E,A
FF3C	C3	JMP	FF43
FF3D	43		
FF3E	FF		
FF3F	05	DCR	B
FF40	AF	XRA	A
FF41	3C	INR	A
FF42	5F	MOV	E,A
FF43	16	MVI	D,64
FF44	64		
FF45	CD	CALL	FF72
FF46	72		
FF47	FF		
FF48	C3	JMP	FF29
FF49	26		
FF4A	FF		
FF4B	06	MVI	B,02
FF4C	02		
FF4D	0E	MVI	C,0B
FF4E	0B		
FF4F	CD	CALL	1000
FF50	00		
FF51	10		
FF52	7D	MOV	A,L
FF53	FE	CPI	0A
FF54	0A		
FF55	D2	JNC	FF4D
FF56	4D		
FF57	FF		
FF58	05	DCR	B
FF59	CA	JZ	FF62
FF5A	62		
FF5B	FF		
FF5C	32	STA	FFAA
FF5D	AA		
FF5E	FF		
FF5F	C3	JMP	FF4D
FF60	4D		
FF61	FF		
FF62	32	STA	FFAB
FF63	AB		
FF64	FF		
FF65	3A	LDA	FFAA

FF66	AA		
FF67	FF		
FF68	47	MOV	B,A
FF69	CD	CALL	FFA1
FF6A	A1		
FF6B	FF		

ADDRESS	**DATA**	**INSTRUCTION**	
FF6C	3A	LDA	FFAB
FF6D	AB		
FF6E	FF		
FF6F	80	ADD	B
FF70	6F	MOV	L,A
FF71	C9	RET	
FF72	F5	PUSH	PSW
FF73	C5	PUSH	B
FF74	7B	MOV	A,E
FF75	1F	RAR	
FF76	3A	LDA	FFAC
FF77	AC		
FF78	FF		
FF79	DA	JC	FF80
FF7A	80		
FF7B	FF		
FF7C	0F	RRC	
FF7D	C3	JMP	FF81
FF7E	81		
FF7F	FF		
FF80	07	RLC	
FF81	32	STA	FFAC
FF82	AC		
FF83	FF		
FF84	DB	IN	11
FF85	11		
FF86	E6	ANI	F0
FF87	F0		
FF88	47	MOV	B,A
FF89	3A	LDA	FFAC
FF8A	AC		
FF8B	FF		

ADDRESS	**DATA**	**INSTRUCTION**	
FF8C	E6	ANI	0F
FF8D	0F		
FF8E	B0	ORA	B
FF8F	D3	OUT	11
FF90	11		
FF91	D5	PUSH	D
FF92	06	MVI	B,FF
FF93	FF		
FF94	05	DCR	B
FF95	C2	JNZ	FF94
FF96	94		
FF97	FF		
FF98	00	NOP	
FF99	15	DCR	D
FF9A	C2	JNZ	FF92
FF9B	92		
FF9C	FF		
FF9D	D1	POP	D
FF9E	C1	POP	B
FF9F	F1	POP	PSW
FFA0	C9	RET	
FFA1	F5	PUSH	PSW
FFA2	78	MOV	A,B
FFA3	07	RLC	
FFA4	07	RLC	
FFA5	80	ADD	B
FFA6	07	RLC	
FFA7	47	MOV	B,A
FFA8	F1	POP	PSW
FFA9	C9	RET	

Once the program is started the LED display should read "0000 P0.". The "P0." Stands for "position" and "0000" indicates the relative position of the stepper referenced from its original position when the program was started (thus 0000 means it is in the same position as it was on start up). Press a two digit decimal number on the keypad and the stepper motor should move to that position with the display incrementing as the stepper moves. Once the stepper stops, enter 00 and the stepper should rotate the opposite direction with the display decrementing and finally stopping at 00. The stepper motor should now be in the exact position it was in when the program was first started.

Program Description:

The subroutines are described as follows:

DBLDECIN - Waits for two decimal keys to be pressed then returns the decimal equivalent in the L register. The routine contains error trapping that will not allow a key greater than 9 or a control key to be accepted.

MULTX10 - Used by DBLDECIN to multiply the first key press by a factor of ten. This routine may come in handy in other programs.

STEPR - Moves the stepper motor one step forward or backward. The speed can be controlled by changing the label SPEED, and the direction is controlled by the value in the E register.

```
;      STEPPER MOTOR PROG

P IN         EQU   12H          ;ADRES OF PORT A
P OUT        EQU   11H          ;ADRES OF PORT B
MOS          EQU   1000H        ;MOS SERVICE
KEYIN        EQU   0BH          ;VECTOR FOR KEYIN SERVICE
LEDDEC       EQU   13H          ;VECTOR FOR LEDDEC SERVICE
SPEED        EQU   20           ;STEPR MOTOR SPEED
LEDOUT       EQU   11H



      ORG   0FF01H              ;ORIGIN OF MEM IN 8155



START:
      MVI   E,00110111B         ;THE VALUE FOR "P"
      MVI   D,1
      MVI   C,LEDOUT
      CALL  MOS

      MVI   E,11111011B         ;THE VALUE FOR "O."
      DCR   D
      CALL  MOS

      MVI   A,00110011B         ;INITIALIZE STEPPER MOTOR           ;
      STA   STEP                ;STORE IN STEP
      XRA   A                   ;CLR A REG
      STA   FINLPOS             ;CLR FINLPOS VARIABLE
      MOV   L,A                 ;CLR L REG
      MOV   B,A                 ;CLR B REG
      JMP   SKPCW               ;JUMP TO OUTPUT START POS TO STEPPER
MAIN:
      MOV   A,B                 ;NEW POSITION BECOMES OLD POSITION
      STA   FINLPOS

      CALL  DBLDECIN            ;GET KEY BOARD VALUE

      LDA   FINLPOS
      MOV   B,A
STEPLUP:
      MVI   D,0                 ;CLR D REG
      MOV   E,B                 ;PLACE CURRENT POSITION ON LED DISPLAY
      MVI   C,LEDDEC
```

```
      CALL  MOS

      MOV   A,L                 ;WHERE SUPPOSED TO BE
      SUB   B                   ;- WHERE AT
      JZ    MAIN                ;IF 0 EXIT LUP AND START OVER
      JC    CW                  ;IF NEG GOTO CW ELSE CCW
CCW:
      INR   B                   ;INC CURENT POSITION
      XRA   A                   ;CLR A REG

      MOV   E,A                 ;E = 0
      JMP   SKPCW
CW:
      DCR   B                   ;DEC CURRENT POS
      XRA   A                   ;CLR A REG
      INR   A                   ;A = 1
      MOV   E,A                 ;E = 1
SKPCW:
      MVI   D,SPEED             ;SET SPEED OF STEPR
      CALL  STEPR
      JMP   STEPLUP             ;REPEAT

;*******************************************************************
;DOUBLE DECIMAL IN
;INPUT: NOTHING.
;OUTPUT: L = BINARY VALUE OF A TWO DECIMAL DIGIT INPUT FROM KEYPAD
;
;-------------------------------------------------------------------
DBLDECIN:
      MVI   B,2                ;USED AS COUNTER TO CALL KEYIN TWICE
GETPOS:
      MVI   C,KEYIN
      CALL  MOS                ;CALL KEYIN
      MOV   A,L                ;A = KEY VALUE
      CPI   10                 ;IF VALUE IS > 10 ENTER AGAIN
      JNC   GETPOS
      DCR   B                  ;DEC LOOP COUNTER
      JZ    LOLBLE             ;IF ZERO THEN EXIT
      STA   HIDIG              ;IF NOT THEN STORE FIRST KEYPRESS AS
      JMP   GETPOS             ;HIGH DIGIT
LOLBLE:
      STA   LODIG              ;STORE SECOND DIGIT AS LOW DIGIT
      LDA   HIDIG              ;LOAD HIGH DIG
      MOV   B,A                ;MOV TO B
      CALL  MULTX10            ;MULTIPLY IT BY TEN
      LDA   LODIG              ;LOAD LOW DIG
      ADD   B                  ;ADD IT TO HI DIGIT
      MOV   L,A                ;STORE FINAL DEC VAL IN L
      RET
;*********************************************************************
; STEPR
; IN: D = SPEED. E = DIRECTION,1 = CW 0 = CCW
; OUT: NOTHING
;---------------------------------------------------------------------
STEPR:
      PUSH  PSW                ;SAVE A STATUS
      PUSH  B                  ;SAVE B STATUS
      MOV   A,E                ;
```

```
      RAR
      LDA   STEP          ;LOAD STEP
      JC    LEFT          ;IF E = 1 THEN GOTO LEFT
      RRC                 ;ELSE ROTATE STEP RIGHT
      JMP   SKIP          ;SKIP NEXT INSTRUCTION
LEFT:
      RLC                 ;ROTATE STEP LEFT
SKIP:
      STA   STEP          ;STORE BACK AS STEP

      IN    P OUT         ;MASK OFF 4 LSB OF OUTPUT PORT
      ANI   0F0H
      MOV   B,A
      LDA   STEP          ;LOAD STEP
      ANI   0FH           ;MASK OFF 4 MSB OF STEP
      ORA   B             ;OR WITH 4 LSB OF OUTPUT PORT
      OUT   P OUT         ;OUT STEP AS 4 LSB'S AND CURRENT STATUS OF 4
                          ;MSB'S OF OUTPUT PORT REMAIN UNCHANGED.
      PUSH  D
DELAY:
      MVI   B,0FFH        ;DELAY TO CONTROL SPEED OF STEPPER
DEL:
      DCR   B
      JNZ   DEL
      NOP
      DCR   D
      JNZ   DELAY
      POP   D
      POP   B
      POP   PSW
      RET
;*****************************************************************
;INPUT: B = VALUE TO MULT BY 10, MUST BE LESS THAN 25 DECIMAL
;-----------------------------------------------------------------
MULTX10:
      PUSH  PSW
      MOV   A,B
      RLC
      RLC
      ADD   B
      RLC
      MOV   B,A
      POP   PSW
      RET

HIDIG       DS    1
LODIG       DS    1
STEP        DS    1
FINLPOS     DS    1

      END
```

Application 10: Interfacing an 8255A PPI to the PRIMER

Purpose: To introduce the method of interfacing an I/O mapped device to the PRIMER by building a simple circuit using the 8255A PPI.

Materials:

(1) PRIMER trainer
(1) 8255A PPI Chip
(1) Breadboard
(2) 50 pin ribbon cable female header connector
(1) 6 inch portion of 50 wire ribbon cable
(1) 7 inches of wire-wrap wire and a wire-wrapping tool
(40) 18 gauge jumper wires 4 to 6 inches long
(1) 1K ohm 5% 1/4 watt resistor
(24) LED's

Introduction to the 8255A PPI:

The 8255A PPI (programmable peripheral interface) is a general purpose programmable I/O device designed to use with microprocessors. Its function is to interface peripheral equipment to the microcomputer system bus. The data I/O bus of the 8255A are the lines marked D0-D7. Input and output instructions from the microprocessor change the states of the RD*, WR* and CS* lines (read, write and chip select respectively) which in turn control the 8255A data I/O bus and determine whether it will be used for input, output or whether it will be disabled (in a high-impedance state).

The CS* pin is the Chip Select for the 8255A. A CS* pin can be thought of as a master select pin because unless it is in its active state (low) the 8255A is inactive and its data I/O bus is in a high-impedance state and all of its control pins are ignored (except RESET). A CS* pin is common among microprocessor peripherals and memories because it allows many devices to use a common data bus by allowing the microprocessor and its support circuitry to control which device will use the data bus.

If the 8255A's CS* pin is low, it is selected and the RD* and WR* pins determine whether data will be read from or written to it, and the A0 and A1 pins (address bus pins) determine which of the 3 read registers and 4 write registers will be used. This is shown in the chart below.

PORT SELECT CHARACTERISTICS

A1	A0	RD*	WR*	CS*	
(READ FROM 8255A)					
0	0	0	1	0	Port A
0	1	0	1	0	Port B
1	0	0	1	0	Port C
1	1	0	1	0	(illegal condition)
(WRITE TO 8255A)					
0	0	1	0	0	Port A
0	1	1	0	0	Port B
1	0	1	0	0	Port C
1	1	1	0	0	Control register
(DISABLE 8255A)					
X	X	X	X	1	3-state
1	1	0	1	0	illegal
X	X	1	1	0	3-state

There are three modes of operation that can be selected by the system software.

Mode 0 - Basic input/output
Mode 1 - Strobed Input/output
Mode 2 - Bi-Directional Bus

For this experiment we used mode 0. In this mode, the 8255A has three 8 bit I/O ports (ports A, B and C) which can be individually configured as inputs or outputs. Port C is unique in that it can be treated as two 4 bit ports which are programmed individually as inputs or outputs. When a "high" is seen at the 8255A's RESET pin, this clears all the internal registers, including the control register, and all ports are set to the input mode. In the circuit described below, the RESET pin is connected to the PRIMER reset circuit so the 8255A can be reset when the PRIMER reset button is pressed or when the PRIMER is powered up.

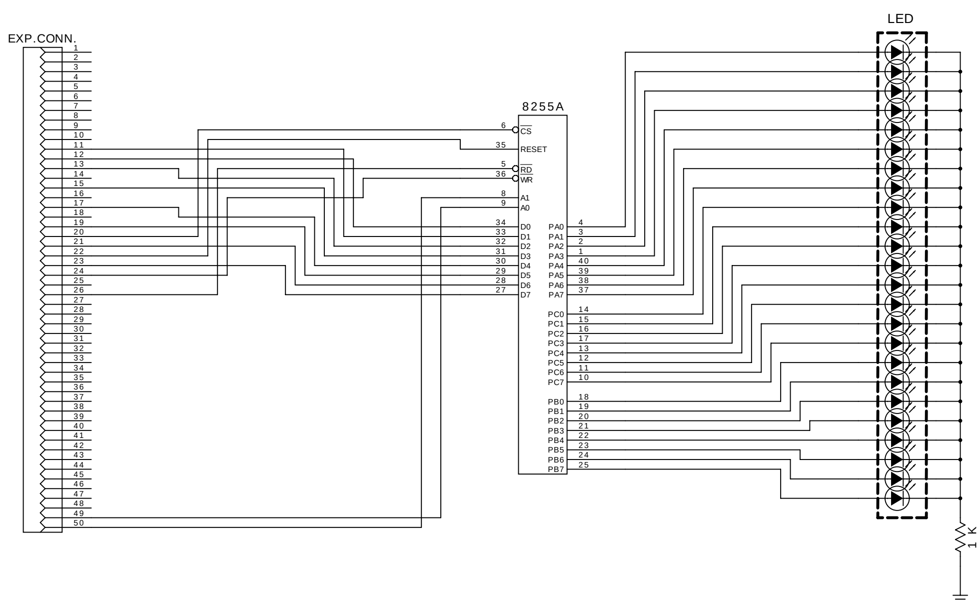
Circuit Description:

Refer to the schematic. The 8255A adapts easily to the 8085 architecture since it was originally designed to be an 8080/8085 peripheral. The necessary control lines and busses are on the expansion connector CN1 and have the same labels as the 8255A pins, except for EXTIOCS*. The EXTIOCS* is a I/O chip select output that is decoded on-board which is connected to CS* of the 8255A. The I/O address range where EXTIOCS* is active is from 0C0H to 0FFH. Since we are only using address lines A0 and A1 addresses 0C0H to 0C3H can be used to select the 8255A registers and ports.

The pins of ports A, B and C will be connected to LED's which are in turn connected to a common current limiting resistor. Note that it is allowable to use a common resistor if only one LED is active at a time. If a program is written which turns on more than one at a time, the LED's will become dim and you could possibly burn out the resistor if its power rating is too low.

The Vcc and ground pins are not shown on the schematic. Ground will come from pin 27 of CN1 and go to pin 7 of the 8255A (note that all references to pin numbers in this application are based on a 40 pin DIP package pinout). The section of wire-wrap wire can be used to connect the Vcc (+5v) supply available on CN3 pin 21 or 22, to pin 26 of the 8255A. If it is desired to have more than one LED on at a time, you should power the circuit with a separate 5v supply and install (24) 1k ohm resistors between ground and each LED. You will also need to determine the maximum power dissipation of your particular 8255A to make sure the load applied doesn't damage it.

All connections to the PRIMER will be made by connecting one end of a 50 pin ribbon cable to the expansion connector and using jumper wires to connect the other end to the breadboard. To make the 50 pin ribbon cable, we need to orient the ribbon and the 50 pin connectors so that when the cable is assembled and plugged into the PRIMER, the female connector on the other end is pointing up. Most 50 pin female connectors have an arrow or mark indicating pin 1. Orient the connector so it will connect to pin 1 of the header when the ribbon is pointed away from the board. Similarly, some 50 wire ribbon cables have one edge wire that is marked in some way.   If your cable is like this, the convention is to orient the cable so the marked wire is on the same side as pin 1 of the header. On the other end of the cable, the female connector should point up, with the female header mark for pin 1 on the same edge of the cable as the mark on the other female header. When the headers are properly oriented on the ribbon cable, they should be pressed into the cable wire with a vise. (Only apply enough pressure to close the protective back onto the header connector or it could be damaged). When the



cable is made this way, pin 1 is easily found on the cable and it can be used as a reference to find the other pins needed for this application.

Program Execution:

The program lights up 24 LED's in sequential order, one LED at a time. The sequence is: port A, port C, port B, repeat. The current port in the sequence starts with bit 0 high, and moves bit by bit to bit 7 then all its bits are cleared and the bit pattern is followed in the next port in sequence.

Refer to the assembly language listing below. The 8255A is put in mode 0, and Ports A, B, and C are programmed as outputs to drive the LED's. The carry flag is set and the accumulator is cleared, then the main loop is entered. The main loop has three loops nested within it: one for port A, C and B and they are executed in that order. Each of the nested loops perform the same function but for different ports. They rotate the carry bit through the accumulator and before each display there is a CALL to a delay routine to allow the previous output LED to be shown long enough to tell us where the bit is within the 24 port pins. When the carry bit has rotated out of the accumulator the loop falls through to the next nested loop. When all three nested loops are finished the program jumps back to the first nested loop.

Assembly language listing

```
PORTA    EQU       0C0H        ; 8255 PORT A
PORTB    EQU       0C1H        ; 8255 PORT B
PORTC    EQU       0C2H        ; 8255 PORT C
CONTRL   EQU       0C3H        ; CONTROL REG
DELAY    EQU       14H         ; SERVICE FOR READING KEYPAD
MOS      EQU       1000H       ; MOS CALL ADDRESS

         ORG       0FF01H
         MVI       A,80H       ; CONFIGURE MODE 0 WITH ALL PORTS OUTPUT
         OUT       CONTRL      ; WRITE TO CONTROL REG.

         MVI       A,0         ; START WITH ACC=0
         STC                   ; SET CY

SHPRTA:  CALL      SHFTDLY     ; SHIFT ACC WITH CY
         OUT       PORTA
         JNC       SHPRTA      ; LOOP TILL CY SET

SHPRTC:  CALL      SHFTDLY     ; SHIFT ACC WITH CY
         OUT       PORTC
         JNC       SHPRTC      ; LOOP TILL CY SET

SHPRTB:  CALL      SHFTDLY     ; SHIFT ACC WITH CY
         OUT       PORTB
         JNC       SHPRTB      ; LOOP TILL CY SET

         JMP       SHPRTA      ; DO PORT A AGAIN
```

... program continued on next page

```
;
; Rotate the Acc with the CY and delay if CY not set.
;
SHFTDLY: MVI        C,DELAY    ; SELECT THE DELAY SERVICE
         LXI        H,8000H    ; DELAY PERIOD
         CNC        MOS        ; DO A MOS SERVICE CALL IF NO CY
         RAL                   ; ROTATE LEFT THROUGH CY
         RET
```

Enter the following machine language program into memory and run it.

ADDRESS	DATA	DESCRIPTION	
FF01	3E	MVI	A,80
FF02	80		
FF03	D3	OUT	C3
FF04	C3		
FF05	3E	MVI	A,00
FF06	00		
FF07	37	STC	
FF08	CD	CALL	FF23
FF09	23		
FF0A	FF		
FF0B	D3	OUT	C0
FF0C	C0		
FF0D	D2	JNC	FF08
FF0E	08		
FF0F	FF		
FF10	CD	CALL	FF23
FF11	23		
FF12	FF		
FF13	D3	OUT	C2
FF14	C2		
FF15	D2	JNC	FF10
FF16	10		
FF17	FF		

ADDRESS	DATA	DESCRIPTION	
FF18	CD	CALL	FF23
FF19	23		
FF1A	FF		
FF1B	D3	OUT	C1
FF1C	C1		
FF1D	D2	JNC	FF18
FF1E	18		
FF1F	FF		
FF20	C3	JMP	FF08
FF21	08		
FF22	FF		
FF23	0E	MVI	C,14
FF24	14		
FF25	21	LXI	H,8000
FF26	00		
FF27	80		
FF28	D4	CNC	1000
FF29	00		
FF2A	10		
FF2B	17	RAL	
FF2C	C9	RET	