

TI-RSLK

Texas Instruments Robotics System Learning Kit



TEXAS INSTRUMENTS



Module 8

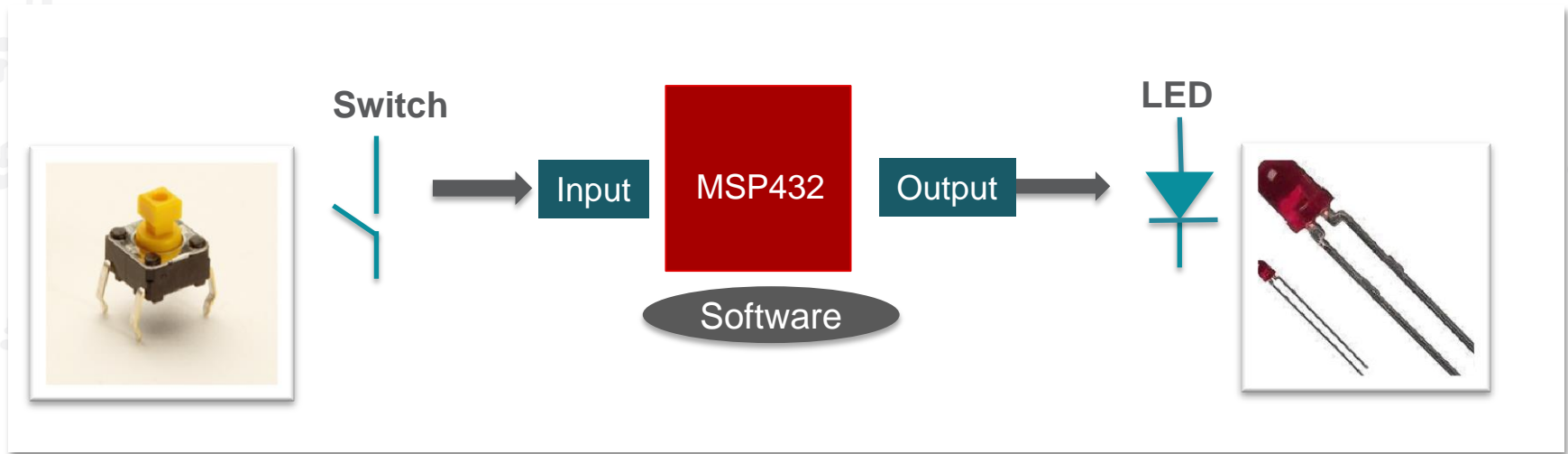
Lecture : Interfacing input and output - Switches



Interfacing input devices using Switches

You will learn in this module

- Fundamentals of switches
- How to interface switches TI's Launchpad Development board
- Software driver (set of functions to create an abstract module)
- Motivation for lab

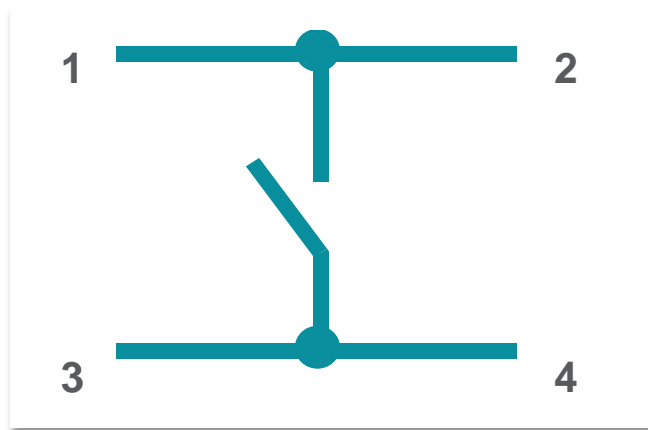




Switch Configuration

Not pressed $R = 100\text{M}\Omega$

Pressed $R = 0.1\Omega$



Not pressed

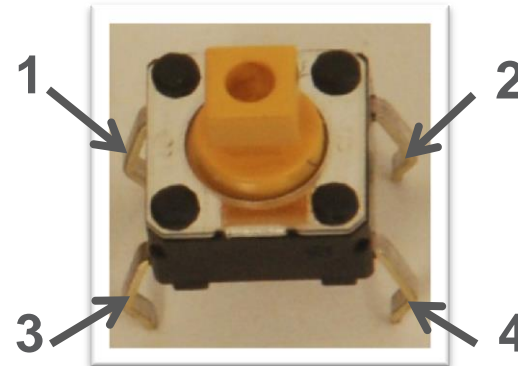
Pressed



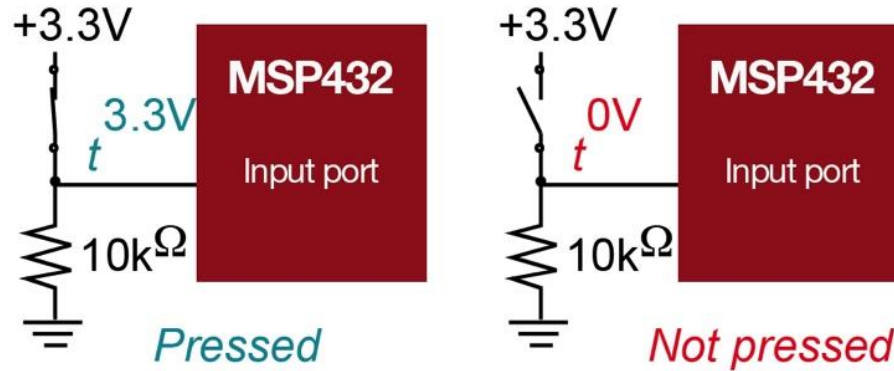
Open



Closed



Positive Logic Switch Interface

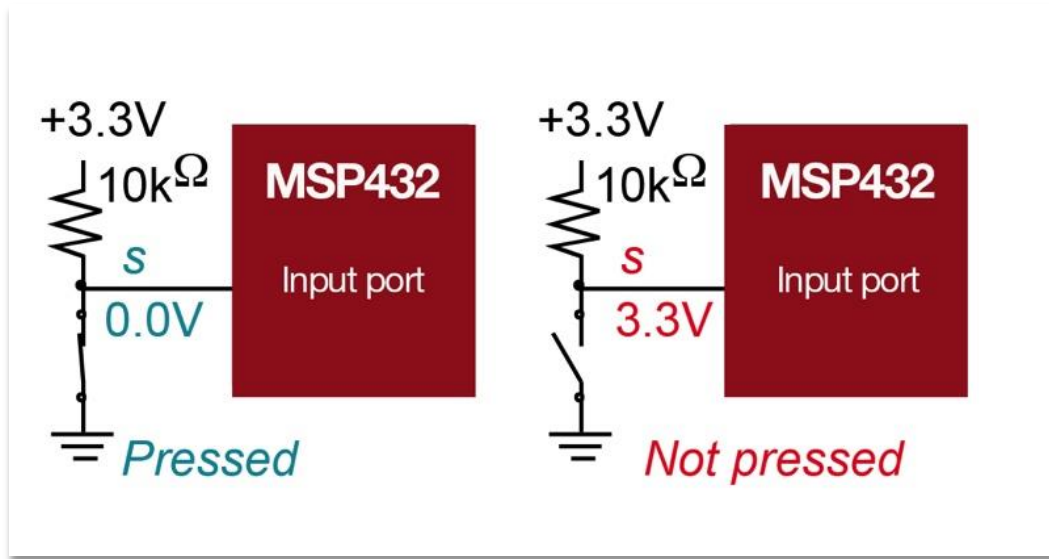


Positive Logic t

- pressed, 3.3V, true
- not pressed, 0V, false



Negative Logic Switch Interface

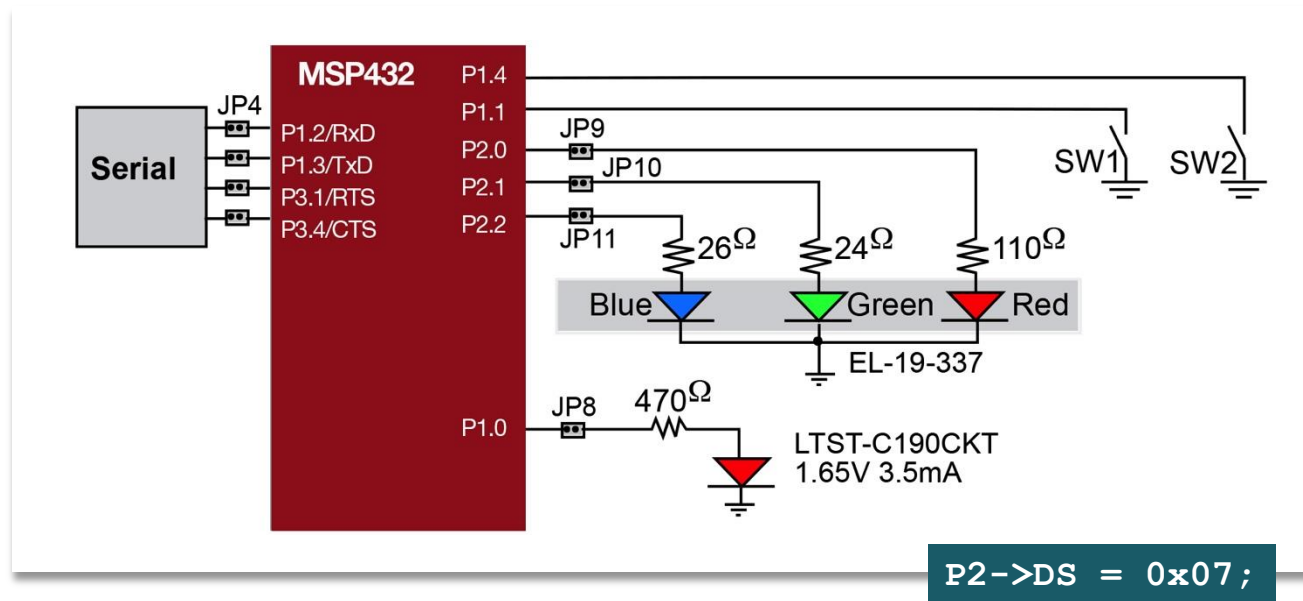


Negative Logic s

- pressed, 0V, true
- not pressed, 3.3V, false



LaunchPad Switches and LEDs



The Switches on the LaunchPad

- Negative logic
- Require internal pull-up

The LEDs are positive logic



Software Driver (inputs)

Initialization (executed once at beginning)

1. Set *DIR* to 0 for input
2. Enable pullup on inputs

Input from switches

1. Read from data input port
2. Mask (select) desired bits

```
all = P1->IN;  
in = all&0x01;
```

Mask



Software Driver (simple, not friendly)

```
#include "msp.h"

void Port1_Init(void){
    P1->DIR = 0x00;    // 1) make P1.4 and P1.1 in
    P1->REN = 0x12;    // 2) enable pull resistors on P1.4 P1.1
    P1->OUT = 0x12;    // P1.4 and P1.1 are pull-up
}

uint8_t Port1_Input(void){
    return (P1->IN&0x12); // read P1.4,P1.1 inputs
}
```

See [InputOutput_MSP432](#) example project



Software Driver (friendly)

```
#include "msp.h"

void Port1_Init(void) {
    P1->DIR &= ~0x12; // 1) make P1.4 and P1.1 in
    P1->REN |= 0x12; // 2) enable pull resistors on P1.4 P1.1
    P1->OUT |= 0x12; // P1.4 and P1.1 are pull-up
}

uint8_t Port1_Input(void) {
    return (P1->IN&0x12); // read P1.4,P1.1 inputs
}
```

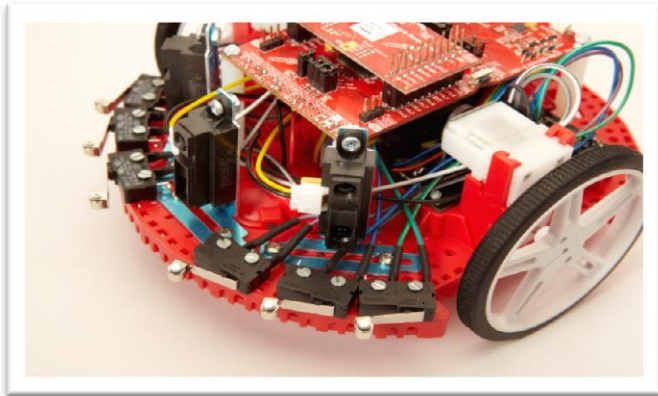
See [InputOutput_MSP432](#) example project



Application

Switches provide

1. Feedback to robot as bump sensors to determine if there is an obstruction
2. Control/command inputs to robot (e.g., start/stop)

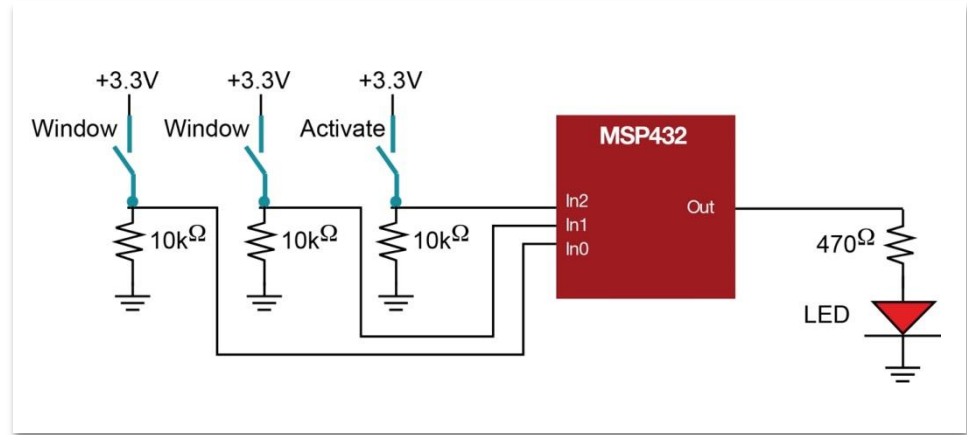




Summary

- Positive and negative logic
- Ohm's Law for resistors
- Switch interface with pullup or pulldown
- LaunchPad switches and LEDs
- Software driver
 - Initialization
 - Input/Output functions

$$V = I * R$$



Module 8

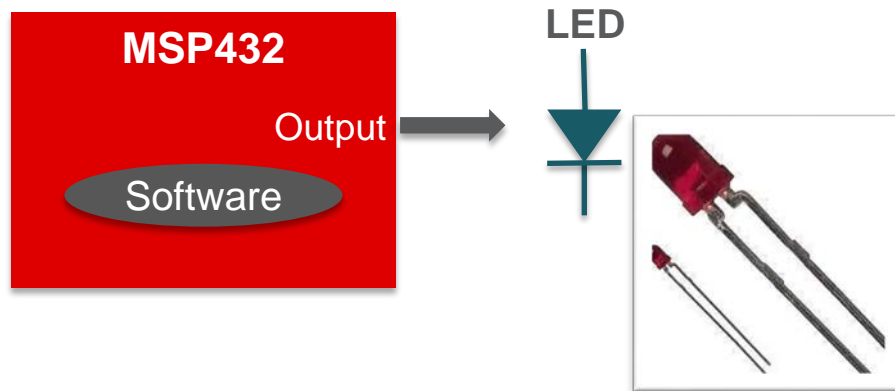
Lecture : Interfacing input and output - LEDs

Lecture

Interfacing output devices using LEDs

You will learn in this module

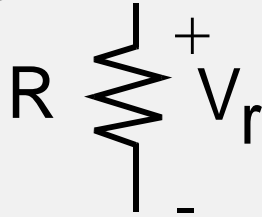
- Fundamentals of LEDs
- How to LEDs to TI's Launchpad Development board
- Software driver (set of functions to create an abstract module)
- Motivation for lab



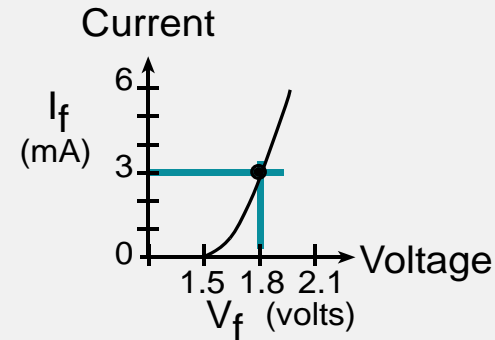
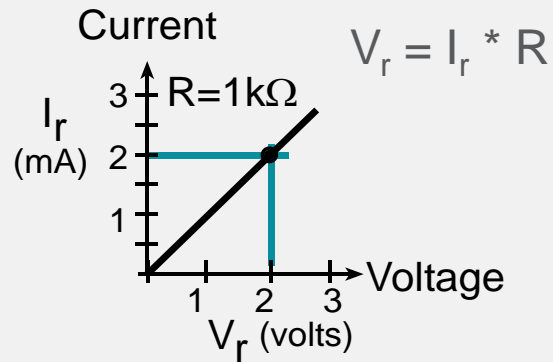
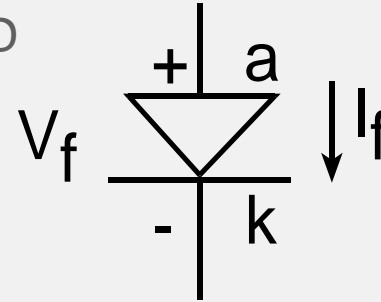


LED Interfacing

Resistor

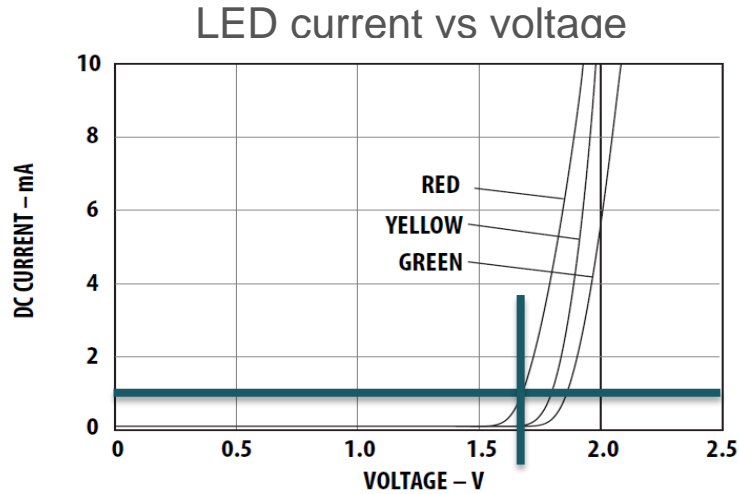


LED





LED Interfacing



1 mA, 1.6V

Brightness = power = $V \times I$

anode (+)

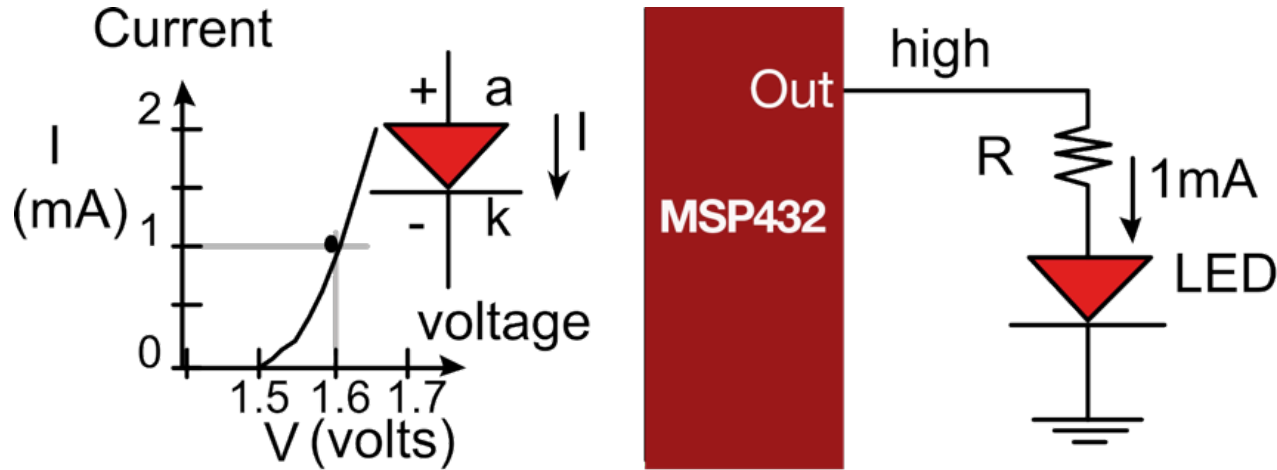


cathode (-)

“big voltage connects to big pin”



LED Interfacing ($I < 6 \text{ mA}$), Positive Logic



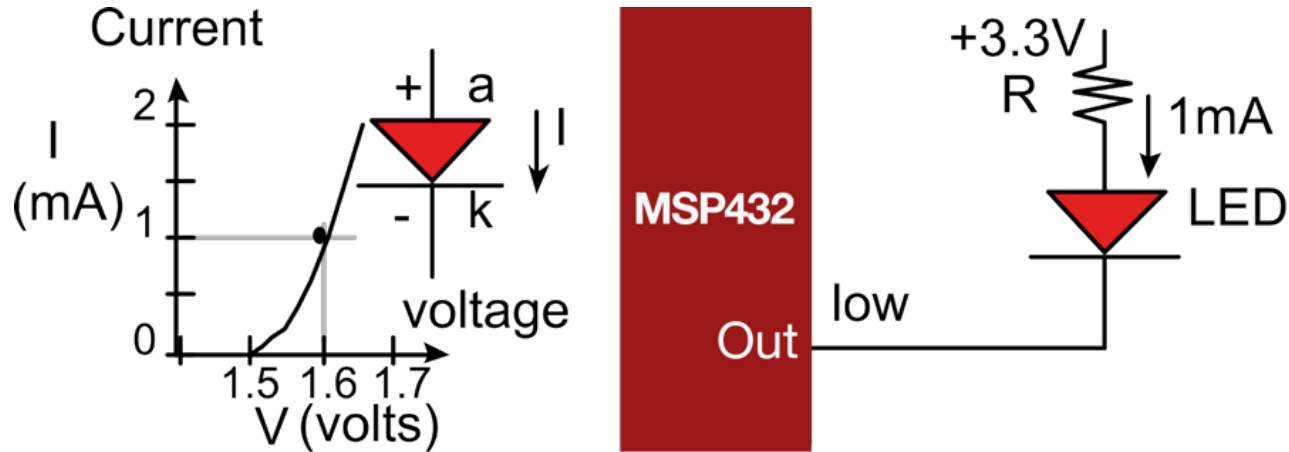
$$R = (3.3\text{V} - 1.6)/0.001\text{A} = 1.7 \text{ k}\Omega$$

Standard $R = 1.6 \text{ k}\Omega$

Brightness = power = $V \cdot I$



LED Interfacing ($I < 6 \text{ mA}$), Negative Logic



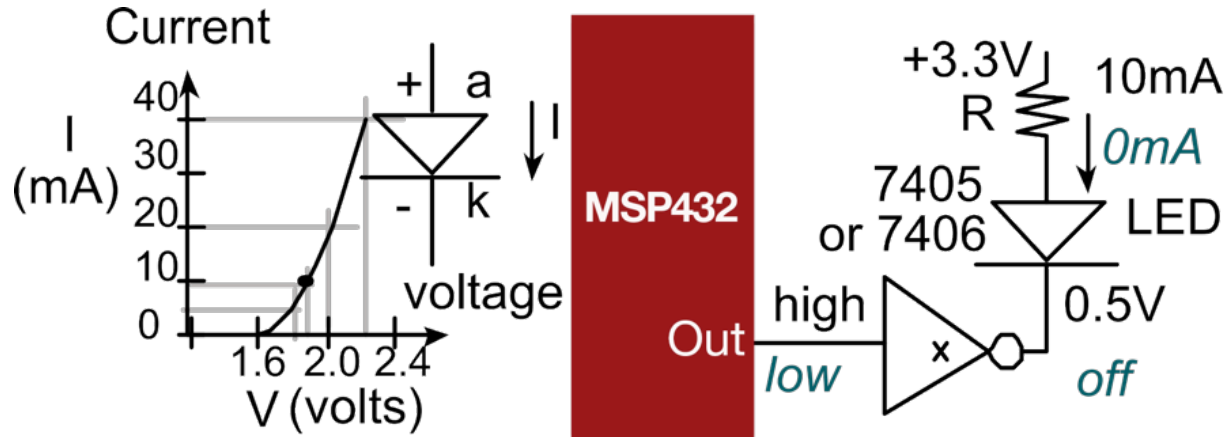
$$R = (3.3\text{V} - 1.6)/0.001\text{A} = 1.7 \text{ k}\Omega$$

Standard $R = 1.6 \text{ k}\Omega$

$$\text{Brightness} = \text{power} = V \cdot I$$



LED Interfacing ($I > 6 \text{ mA}$)



LED may contain several diodes in series

$$R = (3.3 - 1.8 - 0.5) / 0.01 = 100 \, \Omega$$

$$\text{Brightness} = \text{power} = V \cdot I$$



Software Driver (outputs)

Initialization (executed once at beginning)

1. Set *DIR* to 1 for output
2. Activate increased drive strength on output

Output to LED

1. Read from data output port
2. Modify bits as desired
3. Write to data output port

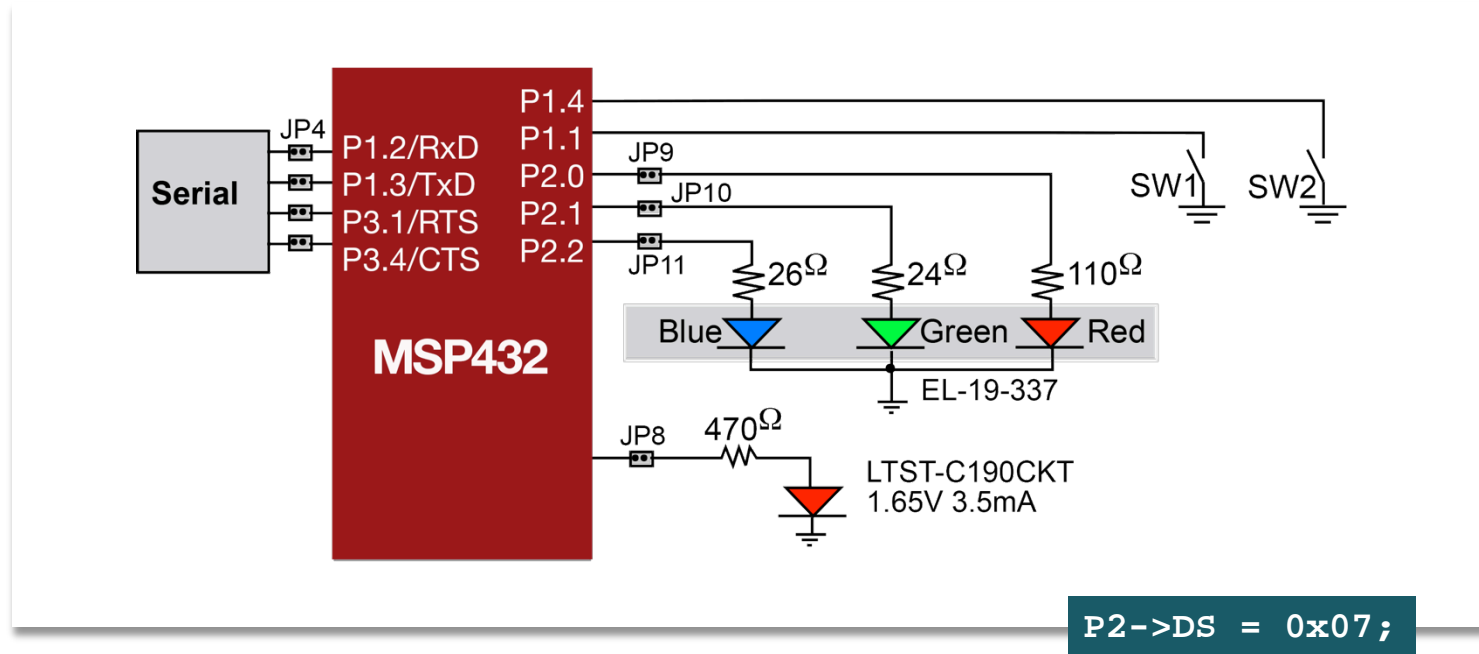
```
data = P2->OUT;  
data |= 0x01;  
P2->OUT = data;
```

Set bit

```
data = P2->OUT;  
data = data&0xFE;  
P2->OUT = data;
```

Clear bit

LaunchPad Switches and LEDs



The LEDs are positive logic



Software Driver (simple, not friendly)

```
#include "msp.h"
void Port2_Init(void){
    P2->DIR = 0x07;    // 1) make P2.2-P2.0 out
    P2->DS = 0x07;      // 2) activate increased drive strength
    P2->OUT = 0x00;     //    all LEDs off
}
void Port2_Output(uint8_t data){ // write P2.2-P2.0 outputs
    P2->OUT = data;
}
```

See [InputOutput_MSP432](#) example project



Software Driver (friendly)

```
void Port2_Init(void){
    P2->DIR |= 0x07;    // 1) make P2.2-P2.0 out
    P2->DS |= 0x07;      // 2) activate increased drive strength
    P2->OUT &= ~0x07;    //    all LEDs off
}
void Port2_Output(uint8_t data){ // write P2.2-P2.0 outputs
    P2->OUT = (P2->OUT&0xF8)|data;
}
```

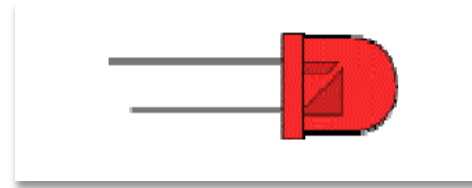
See [InputOutput_MSP432](#) example project



Application

Debugging

1. Control
2. Observability



LEDs provide

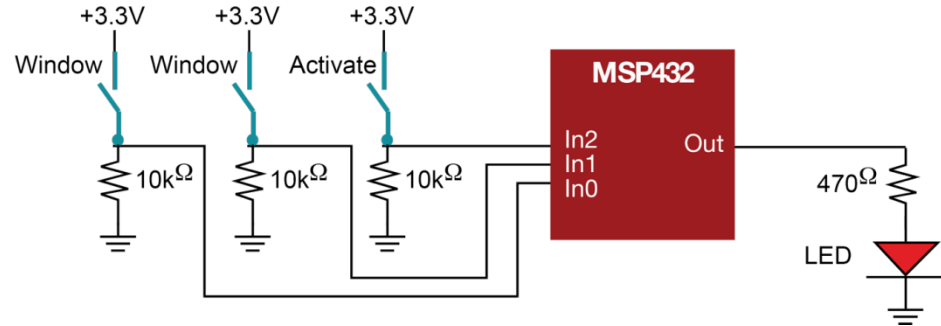
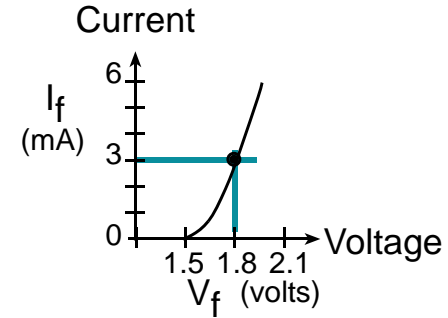
1. Diagnostic information for debugging (e.g., heartbeat)
2. Visualization of state (e.g., flashing rate signifies status)



Summary

- Positive and negative logic
- Ohm's Law for resistors
- LED nonlinear curve
- LED interface
 - Low current uses just a resistor
 - High current needs a driver
- Software driver
 - Initialization
 - Input/Output functions

$$V_r = I_r * R$$



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