

CCS C Compiler Manual

PCB, PCM, PCH, and PCD



November 2021

**ALL RIGHTS RESERVED.
Copyright Custom Computer Services, Inc. 2021**

Table of Contents

Overview	20
PCB, PCM, PCH and PCD	20
Installation	21
Technical Support	21
Directories	22
File Formats	22
Invoking the Command Line Compiler	24
Menu	26
Editor Tabs	26
Slide Out Windows	26
Editor	26
Debugging Windows	26
Status Bar	27
Output Messages	27
Program Syntax	28
Comment	28
Trigraph Sequences	29
Multiple Project Files	30
Multiple Compilation Units	30
Full Example Program	31
Statements	33
if	33
while	34
do-while	35
for	35
switch	35
return	36
goto	36
label	37
break	37
continue	37
expr	38
stmt	38
Expressions	39

Constants.....	39
Identifiers	39
Operators	40
Operator Precedence	41
Data Definitions.....	42
Basic Types	42
Type Qualifiers	44
Enumerated Types.....	45
Structures and Unions.....	45
typedef.....	46
Non-RAM Data Definitions	47
Using Program Memory for Data	48
Named Registers	50
Function Definition.....	51
Overloaded Functions	52
Reference Parameters	52
Default Parameters	53
Variable Argument Lists	53
Functional Overview	55
I2C	55
ADC	56
Analog Comparator	58
CAN Bus	59
CCP	64
Code Profile	65
Configuration Memory	66
CRC	67
DAC	68
Data Eeprom.....	69
DCI.....	71
DMA.....	72
Data Signal Modulator.....	73
Extended RAM	74
External Memory	75
General Purpose I/O	75
Input Capture	76

Internal LCD.....	77
Internal Oscillator	78
Interrupts.....	80
Low Voltage Detect	81
Output Compare/PWM Overview	82
Motor Control PWM.....	83
PMP/EPMP	84
Power PWM.....	85
Program EEPROM.....	87
PSP.....	89
QEI.....	90
RS232 I/O	91
RTCC.....	92
RTOS.....	93
SPI.....	95
Timers.....	97
Timer0.....	98
Timer1.....	99
Timer2.....	100
Timer3.....	101
Timer4.....	101
Timer5.....	101
TimerA	102
TimerB	103
USB	104
Voltage Reference.....	107
WDT or Watch Dog Timer	107
Stream I/O.....	109
PreProcessor.....	112
__address__	112
_attribute_x	112
#asm, #endasm, #asm asis.....	113
#bank_dma	124
#bankx	124
#banky	125
#bit.....	125

__buildcount__	126
#build	126
#byte	129
#case	130
__date__	130
#define	131
#definedinc.....	132
#device	133
__device__	136
#if #else #elif #endif.....	136
#error	137
#export (options)	138
__file__	139
__filename__	140
#fill_rom	140
#fuses	141
#hexcomment.....	142
#id	142
#ifdef #ifndef #else #endif.....	143
#ignore_warnings.....	144
#import(options)	145
#include.....	146
#inline	147
#int_xxxx.....	147
#int_default	154
#int_global.....	155
__line__	156
#list	156
#line	157
#locate	157
#module	158
#nolist	159
#ocs	159
#opt.....	160
#org.....	160
#pin_select.....	162

__pcb__	167
__pcd__	167
__pcm__	168
__pch__	168
#pragma	169
#priority	169
#profile	170
#recursive	171
#reserve	171
#rom	172
#separate	173
#serialize	174
#task	176
__time__	177
#todo	177
#type	178
#undef	180
__unicode__	181
#use capture	182
#use_delay	183
#use dynamic_memory	185
#use fast_io	186
#use fixed_io	186
#use i2c	187
#use profile()	190
#use pwm()	190
#use rs232	192
use rtos	196
#use spi	197
#use standard_io	199
#use timer	200
#use touchpad	201
#warning	202
#word	203
#zero_local_ram	204
#zero_ram	205

Built-in Functions	206
abs()	206
sin() cos() tan() asin() acos() atan() sinh() cosh() tanh() atan2()	207
act_status()	209
adc_done() adc2_done() adc_done2()	209
adc_read()	210
adc_status()	211
adc_write()	212
assert()	212
atof()	213
atof48() atof64() strtof48()	214
atoi() atol() atoi32() atol32() atoi48() atoi64()	215
at_clear_interrupts()	216
at_disable_interrupts()	217
at_enable_interrupts()	218
at_get_capture()	219
at_get_missing_pulse_delay()	220
at_get_period()	221
at_get_phase_counter()	221
at_get_resolution()	222
at_get_set_point()	223
at_get_set_point_error()	223
at_get_status()	224
at_interrupt_active()	225
at_set_compare_time()	226
at_set_missing_pulse_delay()	227
at_set_resolution()	228
at_set_set_point()	228
at_setup_cc()	229
bit_clear()	230
bit_first()	231
bit_last()	232
bit_set()	232
bit_test()	233
brownout_enable()	234
bsearch()	235

calloc()	236
ceil()	237
clc1_setup_gate() clc2_setup_gate() clc3_setup_gate() clc4_setup_gate()	237
clc1_setup_input() clc2_setup_input() clc3_setup_input() clc4_setup_input()	238
clear_dmt()	239
clear_interrupt()	240
clear_pwm1_interrupt() clear_pwm2_interrupt() clear_pwm3_interrupt() clear_pwm4_interrupt() clear_pwm5_interrupt() clear_pwm6_interrupt()	241
cog_restart() cog2_restart() cog3_restart() cog4_restart()	242
cog_status() cog2_status() cog3_status() cog4_status()	242
crc_calc(mode)	243
crc_init(mode)	245
crc_read()	245
crc_write()	246
cwg_restart() cwg2_restart() cwg3_restart()	247
cwg_status() cwg2_status() cwg3_status()	247
dac_write()	248
dci_data_received()	249
dci_read()	250
dci_start()	251
dci_transmit_ready()	252
dci_write()	253
delay_cycles()	254
delay_ms()	254
delay_us()	256
disable_dmt()	257
disable_interrupts()	257
disable_pwm1_interrupt() disable_pwm2_interrupt() disable_pwm3_interrupt() disable_pwm4_interrupt() disable_pwm5_interrupt() disable_pwm6_interrupt()	259
div() ldiv()	260
dma_start()	261
dma_status()	263
dmt_status()	264
enable_dmt()	264
enable_interrupts()	265
erase_program_memory()	267

enable_pwm1_interrupt() enable_pwm2_interrupt() enable_pwm3_interrupt() enable_pwm4_interrupt() enable_pwm5_interrupt() enable_pwm6_interrupt()	268
erase_eeprom()	269
erase_program_memory()	269
exp()	270
ext_int_edge()	271
fabs()	272
getc() getch() getchar() fgetc()	272
gets() fgets()	274
floor()	275
fmod()	275
printf() fprintf()	276
putc() putchar() fputc()	278
puts() fputs()	279
free()	280
frexp()	281
scanf() fscanf()	282
get_adc_ports()	284
get_capture()	285
[PCD] get_capture()	286
get_capture32_ccp1() get_capture_ccp1() get_capture_ccp2() get_capture_ccp3() get_capture_ccp4() get_capture_ccp5()	287
[PCD] get_capture32_ccp1() get_capture32_ccp2() get_capture32_ccp3() get_capture32_ccp4() get_capture32_ccp5()	288
get_capture_event()	289
get_capture_time()	289
[PCD] get_capture32()	290
get_hspwm_capture()	291
get_hspwm_feedback()	291
get_hspwm_status()	292
get_motor_pwm_count()	293
get_nco_accumulator()	294
get_nco_inc_value()	295
get_ticks()	295
get_timerA()	296
get_timerB()	297
get_timerx()	297

get_timerxy()	299
get_timer_ccp1() get_timer_ccp2() get_timer_ccp3() get_timer_ccp4() get_timer_ccp5()	300
get_tris_x()	301
get_wdt()	301
getenv()	302
goto_address()	307
high_speed_adc_done()	308
hspwm_do_capture()	309
hspwm_stop_pwm()	310
hspwm_trigger_pwm()	310
hspwm_update()	311
i2c_init()	312
i2c_isr_state()	313
i2c_poll()	314
i2c_read()	315
i2c_slaveaddr()	316
i2c_speed()	317
i2c_start()	318
i2c_stop()	319
i2c_transfer()	320
i2c_transfer_in()	321
i2c_transfer_out()	322
i2c_write()	323
input()	324
input_change_x()	325
input_state()	326
input_x()	327
interrupt_active()	328
interrupt_enabled()	329
isalnum(char) isalpha(char) iscntrl(x) isdigit(char) isgraph(x) islower(char) isspace(char) isupper(char) isxdigit(char) isprint(x) ispunct(x)	330
isamong()	331
itoa()	332
jump_to_isr()	333
kbhit()	333
label_address()	335
labs()	335

lcd_contrast()	336
lcd_load()	337
lcd_symbol()	337
ldexp()	338
/load_slave_program()	339
log()	340
log10()	341
longjmp()	342
make8()	342
make16()	343
make32()	344
malloc()	345
memcpy() memmove()	345
memset()	346
modf()	347
msi_fifo_status()	348
msi_mailbox_status()	349
msi_read_fifo()	349
msi_read_mailbox()	350
msi_status()	351
msi_write_fifo()	352
msi_write_mailbox()	353
mul()	353
nargs()	354
offset() offsetofbit()	355
outputx()	356
output_bit()	357
output_drive()	358
output_float()	359
output_high()	360
output_low()	361
output_toggle()	362
perror()	363
pid_busy()	364
pid_get_result()	364
pid_read()	366

pid_write()	367
pin_select()	368
pll_locked()	369
pmp_address(address)	370
pmp_output_full() pmp_input_full() pmp_overflow() pmp_error() pmp_timeout()	370
pmp_read()	371
pmp_write()	372
port_a_current_source()	374
port_x_pullups()	374
pow() pwr()	375
prgx_status()	376
printf() fprintf()	377
profileout()	379
psmc_blanking()	380
psmc_deadband()	381
psmc_duty()	382
psmc_freq_adjust()	383
psmc_modulation()	384
psmc_pins()	385
psmc_shutdown()	386
psmc_sync()	387
psp_output_full() psp_input_full() psp_overflow() psp_error() psp_timeout()	388
psp_read()	389
psp_write	390
putc_send() fputc_send()	390
pwm_off()	392
pwm_set_duty()	392
pwm_set_duty_percent()	393
pwm_set_frequency()	394
pwm1_interrupt_active() pwm2_interrupt_active() pwm3_interrupt_active() pwm4_interrupt_active() pwm5_interrupt_active() pwm6_interrupt_active()	394
[PCD] qei_get_capture()	395
qei_get_count()	396
[PCD] qei_get_index_count()	397
[PCD] qei_get_interval_count()	398
[PCD] qei_get_velocity_count()	398
qei_set_count()	399

[PCD] qei_set_index_count()	400
qei_status()	401
qsort()	401
rand()	402
rcv_buffer_bytes()	403
rcv_buffer_full()	404
read_adc() [PCD] read_adc2()	404
read_bank()	406
read_calibration()	407
read_calibration_memory()	408
read_config_info()	409
read_configuration_memory()	409
read_device_info()	410
read_dmt()	411
read_eeprom()	412
read_extended_ram()	413
read_program_memory()	414
read_high_speed_adc()	414
read_program_memory()	416
read_program_memory()	417
read_program_memory8()	418
read_rom_memory()	418
read_sd_adc()	419
realloc()	420
release_io()	421
reset_cpu()	422
restart_cause()	422
restart_wdt()	423
rotate_left()	424
rotate_right()	425
rtc_alarm_read()	426
rtc_alarm_write()	427
rtc_read()	428
[PCD] rtc_status()	429
[PCD] rtc_tsx_read()	429
rtc_write()	430

rtos_wait()	431
rtos_disable()	432
rtos_enable()	432
rtos_msg_poll()	433
rtos_msg_read()	434
rtos_msg_send()	434
rtos_overrun()	435
rtos_run()	436
rtos_signal()	437
rtos_stats()	437
rtos_terminate()	438
rtos_wait()	439
rtos_yield()	440
set_adc_channel() set_adc2_channel()	441
set_adc_trigger()	442
set_analog_pins()	443
scanf() fscanf()	443
[PCD] sent_getd()	446
[PCD] sent_putd()	447
[PCD] sent_status()	448
set_ccp1_compare_time() set_ccp2_compare_time() set_ccp3_compare_time() set_ccp5_compare_time() set_ccp5_compare_time()	449
set_cog_blanking() set_cog2_blanking() set_cog3_blanking() set_cog4_blanking()	450
set_cog_dead_band() set_cog2_dead_band() set_cog3_dead_band() set_cog4_dead_band()	451
set_cog_phase() set_cog2_phase() set_cog3_phase() set_cog4_phase()	451
set_compare_time()	452
set_dedicated_adc_channel()	453
set_hspwm_event() set_hspwm_secondary_event()	455
set_hspwm_duty()	455
set_hspwm_duty_adjustment()	456
set_hspwm_override()	457
set_hspwm_period()	458
set_hspwm_phase()	459
set_hspwm_scaling()	460
set_hspwm_scaling()	461
set_input_level_x()	462
set_motor_pwm_duty()	463

set_motor_pwm_event()	463
set_motor_unit()	464
set_nco_accumulator()	465
set_nco_inc_value()	466
set_open_drain_x(value)	466
set_power_pwm_override()	467
set_power_pwm_x_duty()	468
set_pulldown()	469
set_pullup()	470
set_pwm1_duty() set_pwm2_duty() set_pwm3_duty() set_pwm4_duty() set_pwm5_duty()	470
set_pwm1_offset() set_pwm2_offset() set_pwm3_offset() set_pwm4_offset() set_pwm5_offset()	
set_pwm6_offset()	472
set_pwm1_period() set_pwm2_period() set_pwm3_period() set_pwm4_period() set_pwm5_period()	
set_pwm6_period()	473
set_pwm_x_phase()	474
set_timerx() set_rtcc() set_timer0() set_timer1() set_timer2() set_timer3() set_timer4() set_timer5()	475
set_ticks()	476
setup_sd_adc_calibration()	477
set_sd_adc_channel()	478
set_slow_slew_x()	479
set_timerA()	480
set_timerB()	480
set_timerxy()	481
set_timer_ccp1() set_timer_ccp2() set_timer_ccp3() set_timer_ccp4() set_timer_ccp5() set_timer_ccp6()	482
set_timer_period_ccp1() set_timer_period_ccp2() set_timer_period_ccp3() set_timer_period_ccp4()	
set_timer_period_ccp5() set_timer_period_ccp6()	483
set_tris()	484
set_uart_speed()	485
setjmp()	486
setup_act()	487
setup_adc(mode)	487
[PCD] setup_adc2(mode)	487
setup_adc_ports()	489
[PCD] setup_adc_ports2()	489
setup_adc_reference() setup_adc_reference2()	490
setup_adc_reference() setup_adc_reference2()	491

setup_at()	492
setup_capture()	493
setup_ccp1() setup_ccp2() setup_ccp3() setup_ccp4() setup_ccp5() setup_ccp6() setup_ccp8() setup_ccp9() setup_ccp10()	494
setup_clc1() setup_clc2() setup_clc3() setup_clc4()	497
setup_comparator()	498
[PCD]setup_comparator_dac()	500
setup_comparator_filter()	501
setup_comparator_mask()	502
[PCD] setup_comparator_slope()	503
setup_comparator_x()	504
setup_compare()	505
setup_counters()	505
setup_crc(mode)	507
setup_cog() setup_cog2()	508
setup_cwg() setup_cwg2() setup_cwg3()	509
[PCD] setup_current_source()	510
setup_dac()	510
setup_dci()	511
setup_dedicated_adc()	513
setup_dma()	514
setup_dmt()	515
setup_dsm()	516
setup_external_memory()	517
setup_high_speed_adc()	518
setup_high_speed_adc_pair()	519
setup_hspwm() setup_hspwm_secondary()	520
setup_hspwm_blanking()	521
setup_hspwm_chop_clock()	522
setup_hspwm_current_limit()	523
setup_hspwm_event()	524
setup_hspwm_fault()	525
setup_hspwm_feed_forward()	525
setup_hspwm_logic_x()	526
setup_hspwm_sync()	527
setup_hspwm_trigger()	528
setup_hspwm_unit()	529

setup_hspwm_unit_chop_clock().....	530
setup_lcd()	531
setup_low_volt_detect().....	533
setup_motor_pwm()	534
setup_msi()	535
setup_nco()	535
setup_opamp1() setup_opamp2() setup_opamp3() setup_opamp4().....	536
setup_opamp1() setup_opamp2() setup_opamp3() setup_opamp4().....	537
setup_oscillator().....	538
setup_pga()	540
setup_pid()	540
setup_pmp(option,address_mask).....	541
setup_power_pwm()	542
setup_power_pwm_faults()	544
setup_power_pwm_pins()	545
setup_prgx().....	545
setup_psmc()	546
setup_psp(option,address_mask).....	548
setup_pwm1() setup_pwm2() setup_pwm3() setup_pwm4().....	550
setup_qei()	550
setup_rtc()	551
setup_rtc_alarm()	553
setup_sd_adc()	553
[PCD] setup_sent().....	554
setup_smtx()	555
setup_spi() setup_spi2() setup_spi3() setup_spi4().....	556
setup_timerx()	557
setup_timerA().....	559
setup_timerB().....	560
setup_timer0()	560
setup_timer1()	561
setup_timer2()	562
setup_timer3()	563
setup_timer4()	564
setup_timer5()	565
setup_uart().....	565

setup_vref() setup_vref2()	567
setup_wdt()	568
setup_zcd()	570
shift_left()	571
shift_right()	572
sleep()	573
sleep_ulpwu()	574
smtx_read()	575
smtx_reset_timer()	576
smtx_start()	576
smtx_status()	577
smtx_stop()	578
smtx_write()	578
smtx_update()	579
spi_data_is_in() spi_data_is_in2() spi_data_is_in3()	580
spi_init()	581
spi_prewrite()	581
spi_read() spi_read2() spi_read3() spi_read4()	582
spi_set_txcnt()	584
spi_speed()	585
[PCD] spi_transfer_write()	585
spi_write() spi_write2() spi_write3() spi_write4()	586
spi_xfer()	588
spi_xfer_in()	589
sprintf()	589
sqrt()	590
srand()	591
STANDARD STRING FUNCTIONS() memchr() memcmp() strcat() strchr() strcmp()	
strcoll() strcspn() strerror() stricmp() strlen() strlwr() strncat() strncmp() strncpy()	
strpbrk() strrchr() strspn() strstr() strxfrm()	592
strcpy() strcpy()	593
strtod() [PCD] strtod() [PCD] strtod48()	594
strtok()	595
strtol()	596
strtoul()	597
swap()	598
tolower() toupper()	599

touchpad_getc()	599
touchpad_hit()	600
touchpad_state()	601
tx_buffer_available()	602
tx_buffer_bytes()	603
tx_buffer_full()	604
va_arg()	605
va_end()	605
va_start()	606
verify_slave_program()	607
write_bank()	608
write_configuration_memory()	609
write_eeprom()	610
write_external_memory()	611
write_extended_ram()	612
write_program_eeprom()	613
write_program_memory()	614
write_program_memory8()	616
zcd_status()	616
Standard C Include Files	618
errno.h	618
float.h	618
limits.h	619
locale.h	620
setjmp.h	620
stddef.h	620
stdio.h	620
stdlib.h	620
Software License Agreement	622

OVERVIEW

PCB, PCM, PCH and PCD

The PCB, PCM, and PCH are separate compilers. PCB is for 12-bit opcodes, PCM is for 14-bit opcodes, and PCH is for 16-bit opcode PIC® microcontrollers. Due to many similarities, all three compilers are covered in this reference manual. Features and limitations that apply to only specific microcontrollers are indicated within. These compilers are specifically designed to meet the unique needs of the PIC® microcontroller. This allows developers to quickly design applications software in a more readable, high-level language.

PCD is a C Compiler for Microchip's 24bit opcode family of microcontrollers, which include the dsPIC30, dsPIC33 and PIC24 families. The compiler is specifically designed to meet the unique needs of the dsPIC® microcontroller. This allows developers to quickly design applications software in a more readable, high-level language.

The compiler can efficiently implement normal C constructs, input/output operations, and bit twiddling operations. All normal C data types are supported along with pointers to constant arrays, fixed point decimal, and arrays of bits.

[PCD] Special built in functions to perform common functions in the MPU with ease.

[PCD] Extended constructs like bit arrays, multiple address space handling and effective implementation of constant data in Rom make code generation very effective.

IDE Compilers (PCW, PCWH and PCWHD) have the exclusive C Aware integrated development environment for compiling, analyzing and debugging in real-time. Other features and integrated tools can be viewed [here](#).

When compared to a more traditional C compiler, PCB, PCM, and PCH have some limitations. As an example of the limitations, function recursion is not allowed. This is due to the fact that the PIC® has no stack to push variables onto, and also because of the way the compilers optimize the code. The compilers can efficiently implement normal C constructs, input/output operations, and bit twiddling operations. All normal C data types are supported along with pointers to constant arrays, fixed point decimal, and arrays of bits.

PIC® MCU, MPLAB® IDE, MPLAB® ICD2, MPLAB® ICD3 and dsPIC® are registered trademarks of Microchip Technology Inc. in the U.S. and other countries. REAL ICE™, ICSP™ and In-Circuit Serial Programming™ are trademarks of Microchip Technology Inc. in the U.S. and other countries.

Installation

Insert the CD ROM, select each of the programs you wish to install and follow the on-screen instructions.

If the CD does not auto start run the setup program in the root directory.

For help answering the version questions see the "Directories" Help topic.

Key Questions that may come up:

Keep Settings - Unless you are having trouble select this

Link Compiler Extensions - If you select this the file extensions like .c will start the compiler IDE when you double click on files with that extension. .hex files start the CCSLOAD program. This selection can be change in the IDE.

Install MP LAB Plug In - If you plan to use MPLAB and you don't select this you will need to download and manually install the Plug-In.

Install ICD2, ICD3...drivers-select if you use these microchip ICD units.

Delete Demo Files - Always a good idea

Install WIN8 APP- Allows you to start the IDE from the MDL style (AKA Metro) Start Menus.

Technical Support

Compiler, software, and driver updates are available to download at:
<http://www.ccsinfo.com/download>

Compilers come with 30 or 60 days of download rights with the initial purchase. One year maintenance plans may be purchased for access to updates as released.

The intent of new releases is to provide up-to-date support with greater ease of use and minimal, if any, transition difficulty.

To ensure any problem that may occur is corrected quickly and diligently. It is recommended to send an email to: support@ccsinfo.com or use the Technical Support Wizard in PCW. Include the version of the compiler, an outline of the problem and attach any files with the email request. CCS strives to answer technical support timely and thoroughly.

Technical Support is available by phone during business hours for urgent needs or if email responses are not adequate. Please call 262-522-6500 x32.

Directories

The compiler will search the following directories for Include files.

- Directories listed on the command line
- Directories specified in the **.CCSPJT** file (edit in the IDE under **Options>Project>Include**)
- Directories specified in the **ccs.ini** file found using **Start>All Programs>PICC>User Data Dir**
- The same directory as the source.directories in the **ccsc.ini** file

By default, the compiler files are put in **C:\Program Files\PICC** and the example programs are in **\PICC\EXAMPLES**. The include files are in **PICC\drivers**. The device header files are in **PICC\devices**.

The compiler itself is a DLL file. The DLL files are in a DLL directory by default in **\PICC\DLL\5.xxx**.

It is sometimes helpful to maintain multiple compiler versions. For example, a project was tested with a specific version, but newer projects use a newer version. When installing the compiler you are prompted for what version to keep on the PC. IDE users can change versions using **Help>about** and clicking "other versions." Command Line users use **start>all programs>PIC-C>compiler version**.

Two directories are used outside the PICC tree. Both can be reached with **start>all programs>PIC-C**.

- 1.) A project directory as a default location for your projects. By default put in "My Documents." This is a good place for VISTA and up.
- 2.) User configuration settings and PCWH loaded files are kept in **%APPDATA%\PICC**

File Formats

- .c** - This is the source file containing user C source code.
- .h** - These are standard or custom header files used to define pins, register, register bits, functions and preprocessor directives.
- .pjt** - This is the older pre- Version 5 project file which contains information related to the project.
- .ccspjt** - This is the project file which contains information related to the project.
- .lst** - This is the listing file which shows each C source line and the associated assembly code generated for that line.

The elements in the **.LST** file may be selected in PCW under
Options>Project>Output Files

- CCS Basic** - Standard assembly
- with Opcodes** - Includes the HEX opcode for each instruction
- Old Standard** -
- Symbolic** - Shows variable names instead of addresses
- Mach code** - Includes the HEX opcode for each instruction
- SRF names** - Instead of an address, a name is used. For example, instead of 044, will show CORCON
- Symbols** - Shows variable names instead of addresses
- Interpret** - Adds a pseudo code interpretation to the right of assembly instruction to help understand the operation. For example: LSR W4,#8,W5 : W5=W4>>8

- .sym** - This is the symbol map which shows each register location and what program variables are stored in each location.
- .sta** - The statistics file shows the RAM, ROM, and STACK usage. It provides information on the source codes structural and textual complexities using Halstead and McCabe metrics.
- .tre** - The tree file shows the call tree. It details each function and what functions it calls along with the ROM and RAM usage for each function.
- .hex** - The compiler generates standard HEX files that are compatible with all programmers. The compiler can output 8-bit hex, 16-bit hex, and binary files.
- .cof** - This is a binary containing machine code and debugging information. The debug files may be output as Microchip .COD file for MPLAB 1-5, Advanced Transdata .MAP file, expanded .COD file for CCS debugging or MPLAB 6 and up .xx .COF file. All file formats and extensions may be selected via Options File Associations option in Windows IDE.
- .cod** - This is the binary file containing debug information.
- .rtf** - The output of the Documentation Generator is exported in a Rich Text File format which can be viewed using the RTF editor or Wordpad.
- .rvf** - The Rich View Format is used by the RTF Editor within the IDE to view the Rich Text File.
- .dgr** - The .DGR file is the output of the flowchart maker.
- .esym or .xsym** - These files are generated for the IDE users. The file contains Identifiers and Comment information. This data can be used for automatic documentation generation and for the IDE helpers.

- .o** - Relocatable object file.
- .osym** - This file is generated when the compiler is set to export a relocatable object file.
This file is a .sym file for just the one unit.
- .err** - Compiler error file.
- .ccsload** - Used to link Windows Apps to CCSLoad
- .ccssiow** - Used to link WindowsApps to Serial Port Monitor

Invoking the Command Line Compiler

The command line compiler is invoked with the following command:

```
CCSC [options] [cfilename]
```

Valid options:

+FB	Select PCB (12 bit)	-D	Do not create debug file
+FM	Select PCM (14 bit)	+DS	Standard .COD format debug file
+FH	Select PCH (PIC18XXX)	+DM	.MAP format debug file
+Yx	Optimization level x (0-9)	+DC	Expanded .COD format debug file
+FD	Select PCD (dsPIC30/dsPIC33/PIC24)	+DF	Enables the output of an COFF debug file.
+FS	Select SXC (SX)	+EO	Old error file format
+ES	Standard error file	-T	Do not generate a tree file
+T	Create call tree (.TRE)	-A	Do not create stats file (.STA)
+A	Create stats file (.STA)	-EW	Suppress warnings (use with +EA)
+EW	Show warning messages	-E	Only show first error
+EA	Show all error messages and all warnings	+EX	Error/warning message format uses GCC's "brief format" (compatible with GCC editor environments)

The xxx in the following are optional. If included it sets the file extension:

+LNxxx	Normal list file	+O8xxx	8-bit Intel HEX output file
+LSxxx	MPASM format list file	+OWxxx	16-bit Intel HEX output file
+LOxxx	Old MPASM list file	+OBxxx	Binary output file
+LYxxx	Symbolic list file	-O	Do not create object file
-L	Do not create list file		
+P	Keep compile status window up after compile		
+Pxx	Keep status window up for xx seconds after compile		
+PN	Keep status window up only if there are no errors		
+PE	Keep status window up only if there are errors		

+Z	Keep scratch files on disk after compile
+DF	COFF Debug file
I+= "..."	Same as I= "... " Except the path list is appended to the current list
I= "..."	Set include directory search path, for example: I="c:\picc\examples;c:\picc\myincludes" If no I= appears on the command line the .PJT file will be used to supply the include file paths.
out="dir"	Use this directory for output files
-P	Close compile window after compile is complete
+M	Generate a symbol file (.SYM)
-M	Do not create symbol file
+J	Create a project file (.PJT)
-J	Do not create PJT file
+ICD	Compile for use with an ICD
#xxx="yyy"	Set a global #define for id xxx with a value of yyy, example: #debug="true"
+Gxxx="yyy"	Same as #xxx="yyy"
+?	Brings up a help file
-?	Same as +?
+STDOUT	Outputs errors to STDOUT (for use with third party editors)
+SETUP	Install CCSC into MPLAB (no compile is done)
sourcefile=	Allows a source line to be injected at the start of the source file. Example: CCSC +FM myfile.c sourcefile="#include <16F887.h>"
+V	Show compiler version (no compile is done)
+Q	Show all valid devices in database (no compile is done)

A / character may be used in place of a + character. The default options are as follows:
+FM +ES +J +DC +Y9 -T -A +M +LNlst +O8hex -P -Z

If @filename appears on the CCSC command line, command line options will be read from the specified file. Parameters may appear on multiple lines in the file.

If the file CCSC.INI exists in the same directory as CCSC.EXE, then command line parameters are read from that file before they are processed on the command line.

Examples:

```
CCSC +FM C:\PICSTUFF\TEST.C  
CCSC +FM +P +T TEST.C
```

The PCW IDE provides the user an easy to use editor and environment for developing microcontroller applications. The IDE comprises of many components, which are summarized below. For more information and details, use the Help>PCW in the compiler..

Many of these windows can be re-arranged and docked into different positions.

Menu

All of the IDE's functions are on the main menu. The main menu is divided into separate sections, click on a section title ('Edit', 'Search', etc) to change the section. Double clicking on the section, or clicking on the chevron on the right, will cause the menu to minimize and take less space.

Editor Tabs

All of the open files are listed here. The active file, which is the file currently being edited, is given a different highlight than the other files. Clicking on the X on the right closes the active file. Right clicking on a tab gives a menu of useful actions for that file.

Slide Out Windows

'Files' shows all the active files in the current project. 'Projects' shows all the recent projects worked on. 'Identifiers' shows all the variables, definitions, prototypes and identifiers in your current project.

Editor

The editor is the main work area of the IDE and the place where the user enters and edits source code. Right clicking in this area gives a menu of useful actions for the code being edited.

Debugging Windows

Debugger control is done in the debugging windows. These windows allow you set breakpoints, single step, watch variables and more.

Status Bar

The status bar gives the user helpful information like the cursor position, project open and file being edited.

Output Messages

Output messages are displayed here. This includes messages from the compiler during a build, messages from the programmer tool during programming or the results from find and searching.

PROGRAM SYNTAX

Every C program must contain a main function which is the starting point of the program execution. The program can be split into multiple functions according to their purpose and the functions could be called from main or the sub-functions. In a large project functions can also be placed in different C files or header files that can be included in the main C file to group the related functions by their category. CCS C also requires to include the appropriate device file using `#include` directive to include the device specific functionality. There are also some preprocessor directives like `#fuses` to specify the fuses for the chip and `#use delay` to specify the clock speed. The functions contain the data declarations, definitions, statements and expressions. The compiler also provides a large number of standard C libraries as well as other device drivers that can be included and used in the programs. CCS also provides a large number of built-in functions to access the various peripherals included in the PIC microcontroller.

Comment

Comments – Standard Comments

A comment may appear anywhere within a file except within a quoted string. Characters between `/*` and `*/` are ignored. Characters after a `//` up to the end of the line are ignored.

Comments for Documentation Generator

The compiler recognizes comments in the source code based on certain markups. The compiler recognizes these special types of comments that can be later exported for use in the documentation generator. The documentation generator utility uses a user selectable template to export these comments and create a formatted output document in Rich Text File Format. This utility is only available in the IDE version of the compiler. The source code markups are as follows.

Global Comments

These are named comments that appear at the top of your source code. The comment names are case sensitive and they must match the case used in the documentation template.

For example:

```
/**PURPOSE This program implements a Bootloader.
/**AUTHOR John Doe
```

A `/'` followed by an `*` will tell the compiler that the keyword which follows it will be the named comment. The actual comment that follows it will be exported as a paragraph to the documentation generator.

Multiple line comments can be specified by adding a `:` after the `*`, so the compiler will not concatenate the comments that follow. For example:

```
/**:CHANGES
    05/16/06 Added PWM loop
```

05/27.06 Fixed Flashing problem

*/

Variable Comments

A variable comment is a comment that appears immediately after a variable declaration. For example:

```
int seconds; // Number of seconds since last entry
long day,    // Current day of the month, /* Current Month */
long year;   // Year
```

Function Comments

A function comment is a comment that appears just before a function declaration. For example:

```
// The following function initializes outputs
void function_foo()
{
    init_outputs();
}
```

Function Named Comments

The named comments can be used for functions in a similar manner to the Global Comments. These comments appear before the function, and the names are exported as-is to the documentation generator.

For example:

```
/*PURPOSE This function displays data in BCD format
void display_BCD( byte n)
{
    display_routine();
}
```

Trigraph Sequences

The compiler accepts three character sequences instead of some special characters not available on all keyboards as follows:

Sequence	Same as
??=	#
??(	[
??/	\
??)	]
??'	^
??<	{

??!	
??>	}
??-	~

Multiple Project Files

When there are multiple files in a project they can all be included using the `#include` in the main file or the sub-files to use the automatic linker included in the compiler. All the header files, standard libraries and driver files can be included using this method to automatically link them.

For example: if you have `main.c`, `x.c`, `x.h`, `y.c`, `y.h` and `z.c` and `z.h` files in your project, you can say in:

main.c:

```
#include <device header file>
#include<x.c>
#include<y.c>
#include <z.c>
```

x.c:

```
#include<x.h>
```

y.c:

```
#include<y.h>
```

z.c:

```
#include<z.h>
```

In this example there are 8 files and one compilation unit. **Main.c** is the only file compiled.

Note that the `#module` directive can be used in any include file to limit the visibility of the symbol in that file.

To separately compile your files see the section "multiple compilation units".

Multiple Compilation Units

Multiple Compilation Units are only supported in the IDE compilers, PCW, PCWH, PCHWD and PCDIDE. When using multiple compilation units, care must be given that pre-processor commands that control the compilation are compatible across all units. It is recommended that directives such as `#FUSES`, `#USE` and the device header file all put

in an include file included by all units. When a unit is compiled it will output a relocatable object file (*.o) and symbol file (*.osym).

There are several ways to accomplish this with the CCS C Compiler. All of these methods and example projects are included in the MCU.zip in the examples directory of the compiler.

Full Example Program

Here is a sample program with explanation using CCS C to read adc samples over RS232:

```
#include <16F877A.h>                                // Loads chip specific
definitions
#fuses NOPROTECT                                    // Turn off code protection
#use delay(clock=20000000)                          // Specifies clock speed
#use rs232(baud=9600, xmit=PIN_C6, rcv=PIN_C7)       // Creates RS232 libraries
void main() {
    unsigned int8 i, value, min, max;
    printf("Sampling:");                             // Printf from the RS232 library

    setup_adc_ports(AN0);                            // Make AN0 a analog pin
    setup_adc(ADC_CLOCK_INTERNAL);                  // Start up the ADC
    set_adc_channel(0);                             // Set ADC channel to AN0

    do {
        min=255;
        max=0;
        for(i=0; i<=30; ++i) {
            delay_ms(100);                          // delay function from the delay
library
            value = read_adc();                      // Built-in A/D read function
            if(value<min)
                min=value;
            if(value>max)
                max=value;
        }

        printf("\r\nMin: %2X  Max: %2X\n\r",min,max);
    } while (TRUE);
}

-----
// This version of the example uses the C++ cout instead of printf
// and it also shows data streaming through the ICD instead of using
// an RS232 port
#include <16F877A.h>                                // Loads chip specific definitions
#fuses NOPROTECT                                    // Turn off code protection
#use delay(clock=20000000)                          // Specifies clock speed
#use rs232(ICD)                                      // Creates RS232 libraries (using the ICD)
#include <ios.h>
void main() {
    unsigned int8 i, value, min, max;
```

```
cout << "Sampling:" << endl;

setup_adc_ports(AN0);           // Make AN0 a analog pin
setup_adc(ADC_CLOCK_INTERNAL);  // Start up the ADC
set_adc_channel(0);             // Set ADC channel to AN0

do {
    min=255;
    max=0;
    for(i=0; i<=30; ++i) {
        delay_ms(100);          // delay function from the delay library
        value = read_adc();      // Built-in A/D read function
        if(value<min)
            min=value;
        if(value>max)
            max=value;
    }
    cout << hex << "Min: " << min << "  Max: " << max << endl;
} while (TRUE);
}
```


STATEMENTS

STATEMENT	Example
<u>if</u> (expr) stmt; [<u>else</u> stmt;]	<pre> if (x==25) x=0; else x=x+1; while (get_rtcc()!=0) putc('\n'); do { putc(c=getc()); } while (c!=0); for (i=1;i<=10;++i) printf("%u\r\n",i); switch (cmd) { case 0: printf("cmd 0");break; case 1: printf("cmd 1");break; default: printf("bad cmd");break; } return (5); goto loop; loop: i++; break; continue; i=1; ; {[stmt]} Zero or more declaration;</pre>

Note: Items in [] are optional

if

if-else

The if-else statement is used to make decisions.

The syntax is:

```

if (expr)
    stmt-1;
```

```
[else
    stmt-2;]
```

The expression is evaluated; if it is true stmt-1 is done. If it is false then stmt-2 is done.

else-if

This is used to make multi-way decisions.

The syntax is:

```
if (expr)
    stmt;
[else if (expr)
    stmt;]
...
[else
    stmt;]
```

The expressions are evaluated in order; if any expression is true, the statement associated with it is executed and it terminates the chain. If none of the conditions are satisfied the last else part is executed.

Example:

```
if (x==25)
    x=1;
else
    x=x+1;
```

Also See: [Statements](#)

while

Used as a loop/iteration statement.

The syntax is:

```
while (expr)
    statement
```

The expression is evaluated and the statement is executed until it becomes false in which case the execution continues after the statement.

Example:

```
while (get_rtcc() !=0)
    putc('n');
```

Also See: [Statements](#)

do-while

Differs from *while* and *for* loop in that the termination condition is checked at the bottom of the loop rather than at the top and so the body of the loop is always executed at least once. The syntax is:

```
do
    statement
while (expr);
```

The statement is executed; the **expr** is evaluated. If true, the same is repeated and when it becomes false the loop terminates.

Also See: [Statements](#) , [While](#)

for

Also used as a loop/iteration statement.

The syntax is:

```
for (expr1;expr2;expr3)
    statement
```

The expressions are loop control statements. expr1 is the initialization, expr2 is the termination check and expr3 is re-initialization. Any of them can be omitted.

Example:

```
for (i=1;i<=10;++i)
    printf("%u\r\n",i);
```

Also See: [Statements](#)

switch

Also a special multi-way decision maker.

The syntax is

```
switch (expr) {
    case const1: stmt sequence;
                break;
    ...
    [default:stmt]
}
```

This tests whether the expression matches one of the constant values and branches accordingly.

If none of the cases are satisfied the default case is executed. The break causes an immediate exit, otherwise control falls through to the next case.

Example:

```
switch (cmd) {  
    case 0:printf("cmd 0");  
        break;  
    case 1:printf("cmd 1");  
        break;  
    default:printf("bad cmd");  
        break; }
```

Also See: [Statements](#)

return

A **return** statement allows an immediate exit from a switch or a loop or function and also returns a value.

The syntax is:

```
return(expr);
```

Example:

```
return (5);
```

Also See: [Statements](#)

goto

The goto statement cause an unconditional branch to the label.

The syntax is:

```
goto label;
```

A label has the same form as a variable name, and is followed by a colon. The goto's are used sparingly, if at all.

Example:

```
goto loop;
```

Also See: [Statements](#)

label

The label a goto jumps to.

The syntax is:

label: stmt;

Example:

```
loop: i++;
```

Also See: [Statements](#)

break

The break statement is used to exit out of a control loop. It provides an early exit from while, for ,do and switch.

The syntax is

break;

It causes the innermost enclosing loop (or switch) to be exited immediately.

Example:

```
break;
```

Also See: [Statements](#)

continue

The **continue** statement causes the next iteration of the enclosing loop(While, For, Do) to begin.

The syntax is:

continue;

It causes the test part to be executed immediately in case of do and while and the control passes the re-initialization step in case of for.

Example:

```
continue;
```

Also See: [Statements](#)

expr

The syntax is:

`expr;`

Example:

`i=1;`

Also See: [Statements](#)

stmt

Zero or more semi-colon separated.

The syntax is:

`{[stmt]}`

Example:

`{ a=1;
 b=1; }`

Also See: [Statements](#)

EXPRESSIONS

Constants

123 - Decimal

123L - Forces type to & long (UL also allowed)

123LL - Forces type to & int32;

[PCD] 123LL - Forces type to & 64 for PCD ULL also allowed

0123 - Octal

0x123 - Hex

0b010010 - Binary

123.456 - Floating Point

123F - Floating Point (FL also allowed)

123.4E-5 - Floating Point in Scientific Notation

'x' - Character

'\010' - Octal Character

'\xA5' - Hex Character

'\c' - Special Character. Where c is one of:

- \n Line Feed - Same as \x0a
- \r Return Feed - Same as \x0d
- \t TAB - Same as \x09
- \b Backspace - Same as \x08
- \f Form Feed - Same as \x0c
- \a Bell - Same as \x07
- \v Vertical Space - Same as \x0b
- \? Question Mark - Same as \x3f
- \' Single Quote - Same as \x22
- \" Double Quote - Same as \x22
- \\ A Single Backslash - Same as \x5c

"abcdef" - String (null is added to the end)

Identifiers

ABCDE - Up to 32 characters beginning with a non-numeric. Valid characters are A-Z, 0-9 and _ (underscore). By default not case sensitive Use #CASE to turn on.

ID[X] - Single Subscript

ID[X][X] - Multiple Subscripts

ID.ID - Structure or union reference

ID->ID - Structure or union reference

Operators

+	Addition Operator
+=	Addition assignment operator, $x+=y$, is the same as $x=x+y$
[]	Array subscript operator
&=	Bitwise and assignment operator, $x\&=y$, is the same as $x=x\&y$
&	Address operator
&	Bitwise and operator
^=	Bitwise exclusive or assignment operator, $x^{\wedge}=y$, is the same as $x=x^{\wedge}y$
^	Bitwise exclusive or operator
 =	Bitwise inclusive or assignment operator, $x =y$, is the same as $x=x y$
 	Bitwise inclusive or operator
?:	Conditional Expression operator
--	Decrement
/=	Division assignment operator, $x/=y$, is the same as $x=x/y$
/	Division operator
==	Equality
>	Greater than operator
>=	Greater than or equal to operator
++	Increment
*	Indirection operator
!=	Inequality
<=<=	Left shift assignment operator, $x<=<=y$, is the same as $x=x<<y$
<	Less than operator
<<	Left Shift operator
<=	Less than or equal to operator
&&	Logical AND operator
!	Logical negation operator
 	Logical OR operator
.	Member operator for structures and unions
%=	Modulus assignment operator $x\%=y$, is the same as $x=x\%y$
%	Modulus operator
*=	Multiplication assignment operator, $x*=y$, is the same as $x=x*y$
*	Multiplication operator
~	One's complement operator
>>=	Right shift assignment, $x>>=y$, is the same as $x=x>>y$

>>	Right shift operator
->	Structure Pointer operation
-=	Subtraction assignment operator, x-=y, is the same as x=x- y
-	Subtraction operator
sizeof	Determines size in bytes of operand

See also: [Operator Precedence](#)

Operator Precedence

Pln Descending Precedence				Associativity
(expr)	expr++	expr->expr	expr.expr	Left to Right
++expr	expr++	- -expr	expr - -	Left to Right
!expr	~expr	+expr	-expr	Right to Left
(type)expr	*expr	&value	sizeof (type)	Right to Left
expr*expr	expr/expr	expr%expr		Left to Right
expr+expr	expr-expr			Left to Right
expr<<expr	expr>>expr			Left to Right
expr<expr	expr<=expr	expr>expr	expr>=expr	Left to Right
expr==expr	expr!=expr			Left to Right
expr&expr				Left to Right
expr^expr				Left to Right
expr expr				Left to Right
expr&& expr				Left to Right
expr expr				Left to Right
expr ? expr: expr				Right to Left
lvalue = expr	lvalue+=expr	lvalue-=expr		Right to Left
lvalue *=expr	lvalue/=expr	lvalue%=expr		Right to Left
lvalue>>=expr	lvalue<<=expr	lvalue&=expr		Right to Left
lvalue^=expr	lvalue =expr			Right to Left
expr, expr				Left to Right

(Operators on the same line are equal in precedence)

DATA DEFINITIONS

This section describes what the basic data types and specifiers are and how variables can be declared using those types. In C all the variables should be declared before they are used. They can be defined inside a function (local) or outside all functions (global). This will affect the visibility and life of the variables.

A declaration consists of a type qualifier and a type specifier, and is followed by a list of one or more variables of that type.

For example:

```
int a,b,c,d;
mybit e,f;
mybyte g[3][2];
char *h;
colors j;
struct data_record data[10];
static int i;
extern long j;
```

Variables can also be declared along with the definitions of the *special* types.

For example:

```
enum colors{red, green=2,blue}i,j,k; // colors is the enum
type and i,j,k

//are variables of
that type
```

SEE ALSO:

[Type Specifiers/ Basic Types](#)

[Type Qualifiers](#)

[Enumerated Types](#)

[Structures & Unions](#)

[typedef](#)

[Named Registers](#)

Basic Types

Type-Specifier				
	Size	Unsigned	Signed	Digits
int1	1 bit number	0 to 1	N/A	1/2
int8	8 bit	0 to 255	-128 to 127	2-3

	number			
int16	16 bit number	0 to 65535	-32768 to 32767	4-5
int32	32 bit number	0 to 4294967295	-2147483648 to 2147483647	9-10
int48	48 bit number	0 to 281474976710655	-140737488355328 to 140737488355327	14-15
int64	64 bit number	N/A	-9223372036854775808 to 9223372036854775807	18-19
float32	32 bit float	-1.5 x 10 ⁴⁵ to 3.4 x 10 ³⁸		7-8
float48	48 bit float (higher precision)	-2.9 x 10 ³⁹ to 1.7 x 10 ³⁸ [PCD] -2.9 x 10 ³⁹ to 1.7 x 10 ³⁸		11-12
float64	64 bit float	-5.0 x 10 ³²⁴ to 1.7 x 10 ³⁰⁸ [PCD] -5.0 x 10 ³²⁴ to 1.7 x 10 ³⁰⁸		15-16

C Standard	Default Type	Default Type - PCD
short	int1	signed int8
char	unsigned int8	signed int8
int	int8	signed int16
long	int16	signed int32
long long	int32	signed int64
float	float32	float32
double	N/A	float64

Note: All types, default are unsigned. [PCD] All types, except float char, by default are signed. However, may be preceded by unsigned or signed (Except int64 may only be signed) . Short and long may have the keyword INT following them with no effect. Also see #TYPE to change the default size.

SHORT INT1 is a special type used to generate very efficient code for bit operations and I/O. Arrays of bits (INT1 or SHORT) in RAM are now supported. Pointers to bits are not permitted. The device header files contain defines for BYTE as an int8 and BOOLEAN as an int1.

Integers are stored in little endian format. The LSB is in the lowest address. Float formats are described in common questions.

SEE ALSO: [Declarations](#), [Type Qualifiers](#), [Enumerated Types](#), [Structures & Unions](#), [typedef](#), [Named Registers](#)

Type Qualifiers

static - Variable is globally active and initialized to 0. Only accessible from this compilation unit.

auto - Variable exists only while the procedure is active. This is the default and AUTO need not be used.

double - A reserved word but is not a supported data type.

extern - External variable used with multiple compilation units. No storage is allocated. Is used to make otherwise out of scope data accessible. There must be a non-extern definition at the global level in some compilation unit.

register - Is allowed as a qualifier however, has no effect.

[PCD] Is possible a CPU register instead of a RAM location.

_fixed(n) - Creates a fixed point decimal number where *n* is how many decimal places to implement.

unsigned - Data is always positive.

signed - Data can be negative or positive.

[PCD] **This is the default data type if not specified.**

volatile - Tells the compiler optimizer that this variable can be changed at any point during execution.

const - Data is read-only. Depending on compiler configuration, this qualifier may just make the data read-only -AND/OR- it may place the data into program memory to save space. (see #DEVICE const=)

rom - Forces data into program memory. Pointers may be used to this data but they can not be mixed with RAM pointers.

[PCD] **roml** - Same as rom except only the even program memory locations are used.

void - Built-in basic type. Type void is used to indicate no specific type in places where a type is required.

readonly - Writes to this variable should be dis-allowed.

_bif - Used for compiler built in function prototypes on the same line.

__attribute__ - Sets various attributes

SEE ALSO: Declarations, Type Specifiers, Enumerated Types, Structures & Unions, typedef, Named Registers

Enumerated Types

enum enumeration type: creates a list of integer constants.

enum	[id]	{ [id [= cexpr]] }
		One or more comma separated

The **id** after **enum** is created as a type large enough to the largest constant in the list. The **ids** in the list are each created as a constant. By default the first id is set to zero and they increment by one. If a **= cexpr** follows an **id** that **id** will have the value of the constant expression and the following list will increment by one.

For example:

```
enum colors{red, green=2, blue};    // red will be 0, green will be
2 and                               // blue will be 3
```

SEE ALSO: [Declarations](#), [Type Specifiers](#), [Type Qualifiers](#), [Structures & Unions](#), [typedef](#), [Named Registers](#)

Structures and Unions

Struct structure type: creates a collection of one or more variables, possibly of different types, grouped together as a single unit.

struct[*] [id] {	type-qualifier [*] id	[:bits];	} [id]
	One or more, semi-colon separated	1-8 Bits 1-16 Bits ^{PCD}	Zero or more

For example:

```
struct data_record {
    int  a[2];
    int  b : 2; /*2 bits */
    int  c : 3; /*3 bits*/
    int d;
} data_var;                                //data_record is a structure type
                                           //data_var is a variable
```

[PCD] Field Allocation:

- Fields are allocated in the order they appear.

- The low bits of a byte are filled first.
- Fields 16 bits and up are aligned to a even byte boundary. Some Bits may be unused.
- No Field will span from an odd byte to an even byte unless the field width is a multiple of 16 bits.

Union type: holds objects of different types and sizes, with the compiler keeping track of size and alignment requirements. They provide a way to manipulate different kinds of data in a single area of storage.

union[*] [id] {	type-qualifier [*] id	[:bits];	} [id]
	 One or more, semi-colon separated	1-8 Bits 1-16 Bits ^{PCD}	 Zero or more

For example:

```
union u_tag {
    int ival;
    long lval;
    float fval;
};           //u_tag is a union type that can hold a float
```

SEE ALSO: [Declarations](#), [Type Specifiers](#), [Type Qualifiers](#), [Enumerated Types](#), [typedef](#), [Named Registers](#)

typedef

If **typedef** is used with any of the basic or special types it creates a new type name that can be used in declarations. The identifier does not allocate space but rather may be used as a type specifier in other data definitions.

typedef - [type-qualifier] [type-specifier] [declarator];

For example:

```
typedef int mybyte;           // mybyte can be used in
declaration to               // specify the int type

typedef short mybit;         // mybyte can be used in
declaration to               // specify the int type

typedef enum {red, green=2,blue}colors; //colors can be used to declare
//variable of this enum type
```

SEE ALSO: [Declarations](#), [Type Specifiers](#), [Type Qualifiers](#), [Structures & Unions](#), [Enumerated Types](#), [Named Registers](#)

Non-RAM Data Definitions

CCS C compiler also provides a custom qualifier ***addressmod*** which can be used to define a memory region that can be RAM, program eeprom, data eeprom or external memory. ***Addressmod*** replaces the older ***typemod*** (with a different syntax).

The usage is :

```
addressmod
(name, read_function, write_function, start_address, end_address,
share);
```

Where the read_function and write_function should be blank for RAM, or for other memory should be the following prototype:

```
// read procedure for reading n bytes from the memory starting at location
addr
//
    void read_function(int32 addr,int8 *ram, int nbytes){
    }

//write procedure for writing n bytes to the memory starting at location addr

    void write_function(int32 addr,int8 *ram, int nbytes){
    }
```

For RAM the share argument may be true if unused RAM in this area can be used by the compiler for standard variables.

Example:

```
void DataEE_Read(int32 addr, int8 * ram, int bytes) {
    int i;
    for(i=0;i<bytes;i++,ram++,addr++)
        *ram=read_eeprom(addr);
}

void DataEE_Write(int32 addr, int8 * ram, int bytes) {
    int i;
    for(i=0;i<bytes;i++,ram++,addr++)
        write_eeprom(addr,*ram);
}

addressmod (DataEE,DataEE_read,DataEE_write,5,0xff);
// would define a region called DataEE between
```

```
// 0x5 and 0xff in the chip data EEPROM.

void main (void)
{
    int DataEE test;
    int x,y;
    x=12;
    test=x;    // writes x to the Data EEPROM
    y=test;    // Reads the Data EEPROM
}
```

Note: If the area is defined in RAM then read and write functions are not required, the variables assigned in the memory region defined by the addressmod can be treated as a regular variable in all valid expressions. Any structure or data type can be used with an addressmod. Pointers can also be made to an addressmod data type. The #type directive can be used to make this memory region as default for variable allocations.

The syntax is :

```
#type default=addressmodname    // all the variable declarations that
                                // follow will use this memory region
#type default=                  // goes back to the default mode
```

For example:

```
Type default=emi                //emi is the addressmod name defined
char buffer[8192];
#include <memoryhog.h>
#type default=
```

Using Program Memory for Data

CCS C Compiler provides a few different ways to use program memory for data. The different ways are discussed below:

Constant Data:

The **const** qualifier will place the variables into program memory. If the keyword **const** is used before the identifier, the identifier is treated as a constant. Constants should be initialized and may not be changed at run-time. This is an easy way to create lookup tables.

The **rom** Qualifier puts data in program memory with 3 bytes per instruction space. The address used for ROM data is not a physical address but rather a true byte address. The & operator can be used on ROM variables however the address is logical not physical.

The syntax is: `const type id[cexpr] = {value}`

For example:

Placing data into ROM: `const int table[16]={0,1,2...15}`

Placing a string into ROM: `const char cstring[6]="hello"`

Creating pointers to constants: `const char *cptr;`
`cptr = string;`

The **#org** preprocessor can be used to place the constant to specified address blocks.
 For example:

The constant ID will be at 1C00.

```
#ORG 0x1C00, 0x1C0F
CONST CHAR ID[10]= {"123456789"};
```

Note: Some extra code will precede the 123456789.

The function **label_address** can be used to get the address of the constant. The constant variable can be accessed in the code. This is a great way of storing constant data in large programs. Variable length constant strings can be stored into program memory.

A special method allows the use of pointers to ROM. This method does not contain extra code at the start of the structure as does constant.

For example:

```
char rom commands[] = {"put|get|status|shutdown"};
```

[PCD] ROML may be used instead of ROM if you only to use even memory locations.

The compiler allows a non-standard C feature to implement a constant array of variable length strings.

The syntax is:

```
const char id[n] [*] = { "string", "string" ...};
```

Where n is optional and id is the table identifier.

For example:

```
const char colors[] [*] = {"Red", "Green", "Blue"};
```

#ROM directive:

Another method is to use **#rom** to assign data to program memory.

The syntax is:

```
#rom address = {data, data, ... , data}
```

For example:

Places 1,2,3,4 to ROM addresses starting at 0x1000

```
#rom 0x1000 = {1, 2, 3, 4}
```

Places null terminated string in ROM

```
#rom 0x1000={"hello"}
```

This method can only be used to initialize the program memory.

Built-in-Functions:

The compiler also provides built-in functions to place data in program memory, they are:

Writes **data** to program memory

```
write_program_eeprom(address, data);
```

Writes **count** bytes of data from **dataptr** to **address** in program memory.

```
write_program_memory(address, dataptr, count);
```

[PCD] Every fourth byte of data will not be written, fill with 0x00.

Please refer to the help of these functions to get more details on their usage and limitations regarding erase procedures. These functions can be used only on chips that allow writes to program memory. The compiler uses the flash memory erase and write routines to implement the functionality.

The data placed in program memory using the methods listed above can be read from with the following functions:

Reads count bytes from program memory at address to RAM at dataptr.

```
read_program_memory(address, dataptr, count)
```

[PCD] Every fourth byte of data is read as 0x00

[PCD] Reads count bytes from program memory at the logical address to RAM at dataptr.

```
read_rom_memory((address, dataptr, count)
```

-

These functions can be used only on chips that allow reads from program memory. The compiler uses the flash memory read routines to implement the functionality.

Named Registers

The CCS C Compiler supports the new syntax for filing a variable at the location of a processor register. This syntax is being proposed as a C extension for embedded use. The same functionality is provided with the non-standard **#byte**, **#word**, **#bit** and **#locate**.

The syntax is:

```
register _name type id;
```

Or

```
register constant type id;
```

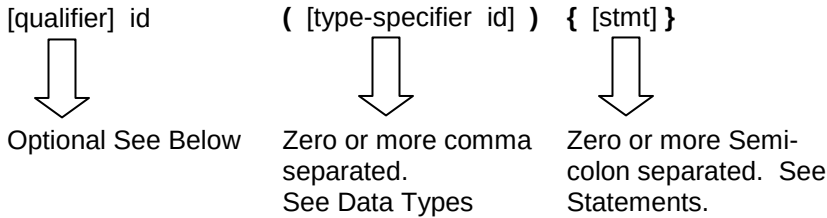
name is a valid SFR name with an underscore before it.

Examples:

```
register _status int8 status_reg;
register _T1IF int8 timer_interrupt;
register 0x04 int16 file_select_register;
```

FUNCTION DEFINITION

The format of a function definition is as follows:



The qualifiers for a function are as follows:

- VOID
- type-specifier
- #separate
- #inline
- #int_..

When one of the above are used and the function has a prototype (forward declaration of the function before it is defined) you must include the qualifier on both the prototype and function definition.

A (non-standard) feature has been added to the compiler to help get around the problems created by the fact that pointers cannot be created to constant strings. A function that has one CHAR parameter will accept a constant string where it is called. The compiler will generate a loop that will call the function once for each character in the string.

Example:

```
void lcd_putc(char c ) {
    ...
}

lcd_putc ("Hi There.");
```

SEE ALSO:

[Overloaded Functions](#), [Reference Parameters](#), [Default Parameters](#), [Variable Parameters](#)

Overloaded Functions

Overloaded functions allow the user to have multiple functions with the same name, but they must accept different parameters.

Here is an example of function overloading: Two functions have the same name but differ in the types of parameters. The compiler determines which data type is being passed as a parameter and calls the proper function.

This function finds the square root of a long integer variable.

```
long FindSquareRoot(long n){  
}
```

This function finds the square root of a float variable.

```
float FindSquareRoot(float n){  
}
```

FindSquareRoot is now called. If variable is of long type, it will call the first FindSquareRoot() example. If variable is of float type, it will call the second FindSquareRoot() example.

```
result=FindSquareRoot(variable);
```

Reference Parameters

The compiler has limited support for reference parameters. This increases the readability of code and the efficiency of some inline procedures. The following two procedures are the same. The one with reference parameters will be implemented with greater efficiency when it is inline.

```
funct_a(int*x,int*y){  
    /*Traditional*/  
    if(*x!=5)  
        *y=*x+3;  
}
```

```
funct_a(&a,&b);
```

```
funct_b(int&x,int&y){  
    /*Reference params*/  
    if(x!=5)  
        y=x+3;  
}
```

```
funct_b(a,b);
```

Default Parameters

Default parameters allows a function to have default values if nothing is passed to it when called.

```
int mygetc(char *c, int n=100){
}
```

This function waits n milliseconds for a character over RS232. If a character is received, it saves it to the pointer c and returns TRUE. If there was a timeout it returns FALSE.

```
mygetc(&c);           //gets a char, waits 100ms for timeout

mygetc(&c, 200);      //gets a char, waits 200ms for a timeout
```

Variable Argument Lists

The compiler supports a variable number of parameters. This works like the ANSI requirements except that it does not require at least one fixed parameter as ANSI does. The function can be passed any number of variables and any data types. The access functions are ***VA_START***, ***VA_ARG***, and ***VA_END***. To view the number of arguments passed, the ***NARGS*** function can be used.

```
/*
stdarg.h holds the macros and va_list data type needed for variable
number of parameters.
*/
#include <stdarg.h>
```

A function with variable number of parameters requires two things. First, it requires the ellipsis (...), which must be the last parameter of the function. The ellipsis represents the variable argument list. Second, it requires one more variable before the ellipsis (...). Usually you will use this variable as a method for determining how many variables have been pushed onto the ellipsis.

Here is a function that calculates and returns the sum of all variables:

```
int Sum(int count, ...)
{
    //a pointer to the argument list
    va_list al;
    int x, sum=0;
    //start the argument list
    //count is the first variable before the ellipsis
    va_start(al, count);
    while(count--) {
        //get an int from the list
        x = var_arg(al, int);
        sum += x;
    }
}
```

```
//stop using the list  
va_end(al);  
return(sum);  
}
```

Some examples of using this new function:

```
x=Sum(5, 10, 20, 30, 40, 50);  
y=Sum(3, a, b, c);
```

FUNCTIONAL OVERVIEW

I2C

I2C™ is a popular two-wire communication protocol developed by Phillips. Many PIC microcontrollers support hardware-based I2C™. CCS offers support for the hardware-based I2C™ and a software-based master I2C™ device. (For more information on the hardware-based I2C module, please consult the datasheet for your target device; not all PICs support I2C™.)

Relevant Functions:

`i2c_start()` - Issues a start command when in the I2C master mode

`i2c_write(data)` - Sends a single byte over the I2C interface

`i2c_read()` - Reads a byte over the I2C interface

`i2c_stop()` - Issues a stop command when in the I2C master mode

`i2c_poll()` - Returns a TRUE if the hardware has received a byte in the buffer

`i2c_transfer(address, wData, wCount, rData, rCount)` - Performs an I2C transfer to and from a device, function does start, restart, write, read, and stop I2C operations; when in I2C master mode.

`i2c_transfer_out(Address, wData, wCount)` - Performs an I2C transfer to a device, function does start, write, and stop I2C operations; when in I2C master mode.

Relevant Preprocessor:

`#USE I2C` - Configures the compiler to support I2C™ to your specifications

Relevant Interrupts:

`#INT_SSP` - I2C or SPI activity

`#INT_BUSCOL` - Bus Collision

`#INT_I2C` - I2C Interrupt (Only on 14000)

`#INT_BUSCOL2` - Bus Collision (Only supported on some PIC18's)

`#INT_SSP2` - I2C or SPI activity (Only supported on some PIC18's)

`[PCD] #INT_mi2c` - Interrupts on activity from the master I2C module

`[PCD] #INT_si2c` - Interrupts on activity from the slave I2C module

Relevant Include Files:

None - All functions built-in

Relevant getenv() Parameters:

I2C_SLAVE - Returns a 1 if the device has I2C slave H/W

I2C_MASTER - Returns a 1 if the device has a I2C master H/W

Example Code:

```
#define Device_SDA PIN_C3 // Pin defines
#define Device_SCL PIN_C4
#use i2c(master, sda=Device_SDA, scl=Device_SCL) // Configure Device as
Master
"
"
BYTE data; // Data to be transmitted
i2c_start(); // Issues a start command
when in
// the I2C master mode.
i2c_write(data); // Sends a single byte over
the I2C interface.
i2c_stop(); // Issues a stop command when
in the I2C master mode
```

ADC

These options let the user configure and use the analog to digital converter module. They are only available on devices with the ADC hardware. The options for the functions and directives vary depending on the chip and are listed in the device header file. On some devices there are two independent ADC modules, for these chips the second module is configured using secondary ADC setup functions (Ex. setup_ADC2).

Relevant Functions:

setup_adc(mode) - Sets up the a/d mode like off, the adc clock etc.

setup_adc_ports(value) - Sets the available adc pins to be analog or digital.

set_adc_channel(channel) - Specifies the channel to be use for the a/d call.

read_adc(mode) - Starts the conversion and reads the value. The mode can also control the functionality.

adc_done() - Returns 1 if the ADC module has finished its conversion.

[PCDJ] setup_adc2(mode) - Sets up the ADC2 module, for example the ADC clock and ADC sample time.

[PCD] `setup_adc_ports2(ports, reference)` - Sets the available ADC2 pins to be analog or digital, and sets the voltage reference for ADC2.

[PCD] `set_adc_channel2(channel)` - Specifies the channel to use for the ADC2 input.

[PCD] `read_adc2(mode)` - Starts the sample and conversion sequence and reads the value. The mode can also control the functionality.

[PCD] `adc_done()` - Returns 1 if the ADC module has finished its conversion.

Relevant Preprocessor:

#DEVICE ADC=xx - Configures the `read_adc` return size. For example, using a PIC with a 10 bit A/D you can use 8 or 10 for xx- 8 will return the most significant byte, 10 will return the full A/D reading of 10 bits.

Relevant Interrupts:

INT_AD - Interrupt fires when A/D conversion is complete.

INT_ADOF - Interrupt fires when A/D conversion has timed out.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

ADC_CHANNELS - Number of A/D channels.

ADC_RESOLUTION - Number of bits returned by `read_adc`

Example Code:

```
#DEVICE ADC=10
...
long value;
...
|
...
setup_adc(ADC_CLOCK_INTERNAL);           // enables the a/d module and
sets the clock to                        // internal adc clock

setup_adc_ports(ALL_ANALOG);             // sets all the adc pins to
analog

set_adc_channel(0);                      // the next read_adc call will
read channel 0
delay_us(10);                            // a small delay is required
after setting channel                   // and before read

value=read_adc();                        // starts the conversion and
reads the result and
```

```

read_adc(ADC_START_ONLY);           // store it in value
                                     // only starts the conversion

value=read_adc(ADC_READ_ONLY);      // reads the result of the last
conversion                          // and store it in value.

Assuming the device had             // a10bit ADC module, value
will range between                  // 0-3FF. If #DEVICE ADC=8 had
been used instead                   // the result will yield 0-FF.

If #DEVICE ADC=16                   // had been used instead the
result will yield                   // 0-FFC0

```

Analog Comparator

These functions set up the analog comparator module. Only available in some devices.

Relevant Functions:

setup_comparator() - Enables and sets up the analog comparator module. The options vary depending on the device; refer to the device's header file for details.

[PCD] setup_comparator_filter() - Enables and sets up the analog comparator's digital filter. The options vary depending on the device; refer to the device's header file for details. Not all devices have a digital filter; refer to the device's header file to determine if available.

[PCD] setup_comparator_mask() - Enables and sets up the analog comparator's output blanking function. The options vary depending on the device; refer to the device's header file for details. Not all devices have an output blanking function; refer to the device's header file to determine if available.

[PCD] setup_comparator_dac() - Enables and sets up the the common settings analog comparator/DAC modules. The options vary depending on the device. Refer to the device's header file for details. Not all devices have this function. Refer to the device's header file to determine if available.

[PCD] setup_comparator_slope() - Sets up the analog comparator/DAC slope compensation settings. The options vary depending on the device. Refer to the device's header file for details. Not all devices have this function. Refer to the device's header file to determine if available.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_COMP - Interrupt fires on a comparator change of state.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

COMP - Returns 1 if the device has a comparator.

Example Code:

```
setup_comparator(A4_A5_NC_NC);
if(C1OUT)
    output_low(PIN_D0);
else
    output_high(PIN_D1);
```

[PCD]

```
setup_comparator(1, CXINB_CXINA);
if(C1OUT)
    output_low(PIN_D0);
else
    output_high(PIN_D1);
```

CAN Bus

These functions allow easy access to the Controller Area Network (CAN) features included with the MCP2515 CAN interface chip and the PIC18 MCU. These functions will only work with the MCP2515 CAN interface chip and PIC microcontroller units containing either a CAN or an ECAN module. Some functions are only available for the ECAN module and are specified by the word **(ECAN)** at the end of the description. The listed interrupts are no available to the MCP2515 interface chip.

[PCD]

These functions allow easy access to the Controller Area Network (CAN) features included with the MCP2515 CAN interface chip and the PIC24, dsPIC30 and dsPIC33 MCUs. These functions will only work with the MCP2515 CAN interface chip and PIC microcontroller units containing either a CAN or an ECAN module. Some functions are only available for the ECAN module and are specified by the word **(ECAN)** at the end of the description. The listed interrupts are not available to the MCP2515 interface chip.

Relevant Functions:

can_init(void); - Initializes the CAN module and clears all the filters and masks so that all messages can be received from any ID.

[PCD]

Initializes the module to 62.5k baud for ECAN and 125k baud for CAN and clears all the filters and masks so that all messages can be received from any ID.

can_set_baud(void); - Initializes the baud rate of the CAN bus to 125kHz, if using a 20 MHz clock and the default CAN-BRG defines, it is called inside the can_init() function so there is no need to call it.

can_set_mode(CAN_OP_MODE mode); - Allows the mode of the CAN module to be changed to configuration mode, listen mode, loop back mode, disabled mode, or normal mode.

can_set_functional_mode (CAN_FUN_OP_MODE mode); - Allows the functional mode of ECAN modules to be changed to legacy mode, enhanced legacy mode, or first in first out (fifo) mode. **(ECAN)**

can_set_id(int* addr, int32 id, int1 ext); - Can be used to set the filter and mask ID's to the value specified by addr. It is also used to set the ID of the message to be sent.

[PCDJ] can_set_id(int16 *addr, int32 id, int1 ext) - Can be used to set the filter and mask ID's to the value specified by addr. It is also used to set the ID of the message to be sent on CAN chips.

[PCDJ] can_set_buffer_id(BUFFER buffer, int32 id, int1 ext) - Can be used to set the ID of the message to be sent for ECAN devices. **(ECAN)**

[PCDJ] can_get_id(BUFFER buffer, int1 ext) - Returns the ID of a received message.

can_get_id(int * addr, int1 ext); - Returns the ID of a received message.

can_putd (int32 id, int * data, int len, int priority, int1 ext, int1 rtr); - Constructs a CAN packet using the given arguments and places it in one of the available transmit buffers.

[PCDJ] can_putd(int32 id, int8 *data, int8 &len, struct rx_stat &stat) - Constructs a CAN packet using the given arguments and places it in one of the available transmit buffers.

can_getd (int32 & id, int * data, int & len, struct rx_stat & stat); - Retrieves a received message from one of the CAN buffers and stores the relevant data in the referenced function parameters.

[PCDJ] can_getd(int32 id, int8 *data, int8 &len, struct rx_stat &stat) - Retrieves a received message from one of the CAN buffers and stores the relevant data in the referenced function parameters.

can_enable_rtr(PROG_BUFFER b); - Enables the automatic response feature which automatically sends a user created packet when a specified ID is received. **(ECAN)**

can_disable_rtr(PROG_BUFFER b); - Disables the automatic response feature. **(ECAN)**

[PCD] can_kbhit() - Returns a TRUE if valid CAN messages are available to be retrieved from one of the receive buffers.

can_load_rtr (PROG_BUFFER b, int * data, int len); - Creates and loads the packet that will automatically be transmitted when the triggering ID is received. **(ECAN)**

can_enable_filter(long filter); - Enables one of the extra filters included in the ECAN module. **(ECAN)**

can_disable_filter(long filter); - Disables one of the extra filters included in the ECAN module. **(ECAN)**

can_associate_filter_to_buffer(CAN_FILTER_ASSOCIATION_BUFFERS buffer,CAN_FILTER_ASSOCIATION filter); - Used to associate a filter to a specific buffer. This allows only specific buffers to be filtered and is available in the ECAN module. **(ECAN)**

can_associate_filter_to_mask(CAN_MASK_FILTER_ASSOCIATE mask,CAN_FILTER_ASSOCIATION filter); - Used to associate a mask to a specific buffer. This allows only specific buffer to have this mask applied. This feature is available in the ECAN module.

can_fifo_getd(int32 &id,int * data,int &len,struct rx_stat & stat); - Retrieves the next buffer in the fifo buffer. Only available in the ECAN module while operating in fifo mode. **(ECAN)**

[PCD] can_fifo_getd(int32 &id,int8 * data,int8 &len, rx_stat & stat); - Retrieves the next buffer in the fifo buffer. Only available in the ECAN module while operating in fifo mode. **(ECAN)**

[PCD] can_tbe() - Returns TRUE if a transmit buffer is available to send more data.

[PCD] can_abort() - Aborts all pending transmissions.

[PCD] can_enable_b_transfer(BUFFER b) - Sets the specified programmable buffer to be a transmit buffer. **(ECAN)**

[PCD] can_enable_b_receiver(BUFFER b) - Sets the specified programmable buffer to be a receive buffer. By default, all programmable buffers are set to be receive buffers. **(ECAN)**

[PCD] can_enable_rtr(BUFFER b) - Enables the automatic response feature. **(ECAN)**

[PCD] can_disable_rtr(BUFFER b) - Disables the automatic response feature. **(ECAN)**

[PCD] can_load_rtr(BUFFER b, int8 *data, int8 len) - Creates and loads the packet that will automatically be transmitted when the triggering ID is received. **(ECAN)**

[PCD] can_set_buffer_size(int8 size) - Set the number of buffers to use. Size can be 4, 6, 8, 12, 16, 24 and 32. By default can_init() sets size to 32. **(ECAN)**

[PCD] can_enable_filter(CAN_FILTER_CONTROLfilter) - Enables one of the acceptance filters included in the ECAN module. **(ECAN)**

[PCD] can_disable_filter(CAN_FILTER_CONTROLfilter) - Disables one of the acceptance filters included in the ECAN module. **(ECAN)**

[PCD] can_trb0_putd(int32 id, int8 *data, int8 len, int8 pri, int1 ext, int rtr) - Constructs a CAN packet using the given arguments and places it in transmit buffer 0. Similar functions available for all transmit buffers 0-7. Buffer must be made a transmit buffer with can_enable_b_transfer() function before function can be use. **(ECAN)**

[PCD] can_enable_interrupts(INTERRUPT setting) - Enables specified interrupt conditions that cause the #INT_CAN1 interrupt to be triggered. Available options:

TB - Transmit Buffer interrupt **(ECAN)**

RB - Receive Buffer interrupt **(ECAN)**

RXOV - Receive Buffer Overflow interrupt **(ECAN)**

FIFO - FIFO Almost Full interrupt **(ECAN)**

ERR - Error interrupt **(ECAN)**

WAK - Wake-Up interrupt **(ECAN)**

IVR - Invalid Message Received interrupt **(ECAN)**

RX0 - Receive Buffer 0 interrupt

RX1 - Receive Buffer 1 interrupt

TX0 - Transmit Buffer 0 interrupt

TX1 - Transmit Buffer 1 interrupt

TX2 - Transmit Buffer 2 interrupt

[PCD] can_disable_interrupts(INTERRUPT setting) - Disable specified interrupt conditions so they do not cause the #INT_CAN1 interrupt to be triggered. Available options are the same as for the can_enable_interrupts() function. By default, all conditions are disabled.

[PCD] can_config_DMA(void) - Configures the DMA buffers to use with the ECAN module. It is called inside the can_init() function so there is no need to call it. **(ECAN)**

For PIC microcontrollers that have two CAN or ECAN modules, all the above functions are available for the second module, and they begin with can2 instead of can.
can2_init(); or can2_kbhit();

Relevant Preprocessor:

None

Relevant Interrupts:

#int_canirx - This interrupt is triggered when an invalid packet is received on the CAN.

#int_canwake - This interrupt is triggered when the PIC is woken up by activity on the CAN.

#int_canerr - This interrupt is triggered when there is an error in the CAN module.

#int_cantx0 - This interrupt is triggered when transmission from buffer 0 has completed.

#int_cantx1 - This interrupt is triggered when transmission from buffer 1 has completed.

#int_cantx2 - This interrupt is triggered when transmission from buffer 2 has completed.

#int_canrx0 - This interrupt is triggered when a message is received in buffer 0.

#int_canrx1 - This interrupt is triggered when a message is received in buffer 1.

[PCD] #int_can1 - Interrupt for CAN or ECAN module 1. This interrupt is triggered when one of the conditions set by `can_enable_interrupts()` is met.

[PCD] #int_can2 - Interrupt for CAN or ECAN module 2. This interrupt is triggered when one of the conditions set by the `can2_enable_interrupts()` is met. This interrupt is only available on devices that have two CAN or ECAN modules.

Relevant Include Files:

can-mcp2510.c - Drivers for the MCP2510 and MCP2515 interface devices.

can-18xxx8.c - Drivers for the built-in CAN module.

can-18F4580.c - Drivers for the built-in ECAN module.

[PCD] can-dsPIC30.c - Drivers for the built-in CAN module on dsPIC30F devices.

[PCD] can-PIC24.c - Drivers for the built-in ECAN module on PIC24HF and dsPIC33FJ devices.

Relevant getenv() Parameters:

None

Example Code:

```
can_init(); // initializes the CAN bus
can_putd(0x300,data,8,3,TRUE,FALSE); // places a message on the CAN
bus with ID=0x300 // and eight bytes of data pointed
to by "data",
```

```
the FALSE                                     // the TRUE create an extended ID,
                                              // creates
    can_getd(ID,data,len,stat);               // retrieves a message from the
    CAN bus storing the                       // ID in the ID variable, the data
in the array                                // pointed to by "data", the number
of data bytes                              // in len, and statistics about the
data in                                     // the stat structure.
```

CCP

These options lets to configure and use the CCP module. There might be multiple CCP modules for a device. These functions are only available on devices with CCP hardware. They operate in 3 modes: capture, compare and PWM. The source in capture/compare mode can be timer1 or timer3 and in PWM can be timer2 or timer4. The options available are different for different devices and are listed in the device header file. In capture mode the value of the timer is copied to the CCP_X register when the input pin event occurs. In compare mode it will trigger an action when timer and CCP_x values are equal and in PWM mode it will generate a square wave.

Relevant Functions:

setup_ccp1(mode) - Sets the mode to capture, compare or PWM.

set_pwm1_duty(value) - The value is written to the pwm1 to set the duty.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_CCP1 - Interrupt fires when capture or compare on CCP1.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

CCP1 - Returns 1 if the device has CCP1

Example Code:

```
#int_ccp1
void isr()
{
    rise=CCP_1;                               // CCP_1 is the time the pulse went high
```



```
    fall=CCP2;                // CCP_2 is the time the pulse went low
    pulse_width=fall-rise;    // pulse width
}
...
setup_ccp1(CCP_CAPTURE_RE);   // Configure CCP1 to capture rise
setup_ccp2(CCP_CAPTURE_FE);   // Configure CCP2 to capture fall
setup_timer_1(T1_INTERNAL);   // Start timer 1
```

Some devices also have fuses which allows to multiplex the ccp/pwm on different pins. Be sure to check the fuses to see which pin is set by default, as well as fuses to enable/disable pwm outputs.

Code Profile

Profile a program while it is running. Unlike in-circuit debugging, this tool grabs information while the program is running and provides statistics, logging and tracing of it's execution. This is accomplished by using a simple communication method between the processor and the ICD with minimal side-effects to the timing and execution of the program. Another benefit of code profile versus in-circuit debugging is that a program written with profile support enabled will run correctly even if there is no ICD connected.

In order to use Code Profiling, several functions and pre-processor statements need to be included in the project being compiled and profiled. Doing this adds the proper code profile run-time support on the microcontroller.

See the help file in the Code Profile tool for more help and usage examples.

Relevant Functions:

profileout() - Send a user specified message or variable to be displayed or logged by the code profile tool.

Relevant Preprocessor:

#use profile() - Global configuration of the code profile run-time on the microcontroller.

#profile - Dynamically enable/disable specific elements of the profiler.

Relevant Interrupts:

The profiler can be configured to use a microcontroller's internal timer for more accurate timing of events over the clock on the PC. This timer is configured using the **#profile** pre-processor command.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
#include <18F4520.h>
#use delay(crystal=10MHz, clock=40MHz)
#profile functions, parameters
void main(void)
{
    int adc;
    setup_adc(ADC_CLOCK_INTERNAL);
    set_adc_channel(0);

    for(;;)
    {
        adc = read_adc();
        profileout(adc);
        delay_ms(250);
    }
}
```

Configuration Memory

The Configuration Memory is readable and writable on all PIC18, PIC24, dsPIC30 and dsPIC33 devices. Enhanced 16 devices have the configuration memory that is readable and the user ID is readable and writable..

[PCD] The Configuration Memory contains the configuration bits for items such as the oscillator mode, watchdog timer enable, etc. These configuration bits are set by the CCS C Compiler usually through a #fuse. CCS provides an API that allows for these bits to be changed in run-time.

Relevant Functions:

write_configuration_memory(ramaddress, count) - Writes count bytes, no erase needed.

write_configuration_memory(offset,ramaddress, count) - Writes count bytes, no erase needed starting at byte address offset.

write_configuration_memory(ramPtr, n); - Writes n bytes to configuration from ramPtr, no erase needed.

[PCD] write_configuration_memory(offset, ramPtr, n); - Read n bytes of configuration memory, save to ramPtr.

read_configuration_memory(ramaddress,count) - Read count bytes of configuration memory.

[PCD] read_configuration_memory(ramPtr, n); - Read n bytes of configuration memory is set through a #FUSE.

read_device_info() - Read count bytes from Device Information Area memory.

read_config_info() - Read count bytes from Device Configuration Information memory.

Relevant Preprocessor:

None

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
#int16 data=0xc32;
...
write_configuration_memory(data,2); // writes 2 bytes to the config
memory
```

CRC

The programmable Cyclic Redundancy Check (CRC) is a software configurable CRC checksum generator in select PIC24F, PIC24H, PIC24EP, and dsPIC33EP devices. The checksum is a unique number associated with a message or a block of data containing several bytes. The built-in CRC module has the following features:

- Programmable bit length for the CRC generator polynomial. (up to 32 bit length)
- Programmable CRC generator polynomial.
- Interrupt output.
- 4-deep, 8-deep, 16-bit, 16-deep or 32-deep, 8-bit FIFO for data input.
- Programmed bit length for data input. (32-bit CRC Modules Only)

Relevant Functions:

setup_crc(polynomial) - This will setup the CRC polynomial.

crc_init(data) - Sets the initial value used by the CRC module.

crc_calc(data) - Returns the calculated CRC value.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_CRC - On completion of CRC calculation.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
int16 data[8];
int16 result;

setup_crc(15, 3, 1);           //CRC Polynomial is X16+X15+X3+X1 +1
                                //or polynomial=8005h
crc_init(0xFEEE);              //Starts the CRC accumulator outo f 0xFEEE
result=crc_calc(&data[0],8): //Calculates the CRC
```

DAC

These options let the user configure and use the digital to analog converter module. They are only available on devices with the DAC hardware. The options for the functions and directives vary depending on the chip and are listed in the device header file.

Relevant Functions:

setup_dac(divisor) - Sets up the DAC e.g. Reference voltages.

dac_write(value) - Writes the 8-bit value to the DAC module.

[PCD] setup_dac(mode, divisor) - Sets up the d/a mode e.g. Right enable, clock divisor.

[PCD] dac_write(channel, value) - Writes the 16-bit value to the specified channel.

Relevant Preprocessor:

#USE DELAY - Must add an auxiliary clock in the #use delay preprocessor.

For example: **#USE DELAY**(clock=20M, Aux: crystal=6M, clock=3M)

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
int8 i=0;
setup_dac (DAC_VSS_VDD);
while (TRUE) {
    itt;
    dac_write(i);
}
```

[PCD]

```
int16 i = 0;
setup_dac(DAC_RIGHT_ON, 5);           // enables the d/a module with right
channel                               // enabled and a division of the

clock by 5
While(1){
    i++;
    dac_write(DAC_RIGHT, i);          // writes i to the right DAC channel
}
```

Data Eeprom

The data eeprom memory is readable and writable in some chips. These options lets the user read and write to the data eeprom memory. These functions are only available in flash chips.

Relevant Functions:

read_eeprom(address) - Reads the data EEPROM memory location

write_eeprom(address, value) - Erases and write value to data EEPROM location address. Except for PCB devices with EEPROM, such as PIC12F519; it only writes the value.

erase_eeprom(address) - Erases a row of the EEPROM of Flash memory. Only available on PCB devices with EEPROM, such as PIC12F599.

read_eeprom(address, [N]) - Reads N bytes of data EEPROM starting at memory location address. The maximum return size is int64.

read_eeprom(address, [variable]) - Reads from EEPROM to fill variable starting at address.

read_eeprom(address, pointer, N) - Reads N bytes, starting at address, to pointer.

write_eeprom(address, value) - Writes value to EEPROM address.

write_eeprom(address, pointer, N) - Writes N bytes to address from pointer

Relevant Preprocessor:

#ROM address={list} - Can also be used to put data EEPROM memory data into the hex file.

write_eeprom = noint - Allows interrupts to occur while the write_eeprom() operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.

Relevant Interrupts:

INT_EEPROM - Interrupt fires when EEPROM write is complete.

Relevant Include Files:

None, all functions built-in.

Relevant getevn() Parameters:

DATA_EEPROM - Size of data EEPROM memory.

Example Code:

For 18F452

```
#rom 0xf00000={1,2,3,4,5}    //inserts this data into the hex file.
                             //The data eeprom address differs for
different                    // family of devices. Please refer to the
                             //programming specs to find the value for
the device.

write_eeprom(0x0,0x12);      //write 0x12 to data eeprom location 0
    value=read_eeprom(0x)    // reads data eeprom location 0x0
returns 0x12

#ROM 0x007FFC00={1,2,3,4,5}  //Inserts this data into the hex file.
    The data                  //EEPROM address differs between PICs.
                             //Please refer to the device editor for
device                        //specific values.

write_eeprom(10,0x1337)      //Writes 0x1337 to data EEPROM location
10.                           //Reads data EEPROM location 10 returns
value=read_eeprom(10);       0x1337
0x1337
```

DCI

DCI is an interface that is found on several dsPIC devices in the 30F and the 33FJ families. It is a multiple-protocol interface peripheral that allows the user to connect to many common audio codecs through common (and highly configurable) pulse code modulation transmission protocols. Generic multichannel protocols, I2S and AC'97 (16 & 20 bit modes) are all supported.

Relevant Functions:

`setup_dci(configuration, data size, rx config, tx config, sample rate);` - Initializes the DCI module.

`setup_adc_ports(value)` - Sets the available ADC pins to be analog or digital.

`set_adc_channel(channel)` - Specifies the channel to be used for the A/D call.

`read_adc(mode)` - Starts the conversion and reads the value. The mode can also control the functionality.

`adc_done()` - Returns 1 if the ADC module has finished its conversion.

Relevant Preprocessor:

`#DEVICE ADC=xx` - Configures the `read_adc` return size. For example, using a PIC with a 10 bit A/D you can use 8 or 10 for `xx`- 8 will return the most significant byte, 10 will return the full A/D reading of 10 bits.

Relevant Interrupts:

`INT_DCI` - Interrupt fires on a number (user configurable) of data words received.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
signed int16 left_channel, right_channel;

dci_initialize((I2S_MODE|DCI_MASTER|DCI_CLOCK_OUT|
SAMPLE_RISING_EDGE|UNDERFLOW_LAST|MULTI_DEVICE_BUS),DCI_1WORD_FRAME|
DCI_16BIT_WORD|DCI_2WORD_INTERRUPT, RECEIVE_SLOT0|RECEIVE_SLOT1,
TRANSMIT_SLOT0|TRANSMIT_SLOT1, 6000);
...
dci_start();
...
while(1)
{
```

```
    dci_read(&left_channel, &right_channel);  
    dci_write(&left_channel, &right_channel);  
}
```

DMA

The Direct Memory Access (DMA) controller facilitates the transfer of data between the CPU and its peripherals without the CPU's assistance. The transfer takes place between peripheral data registers and data space RAM. The module has 8 channels and since each channel is unidirectional, two channels must be allocated to read and write to a peripheral. Each DMA channel can move a block of up to 1024 data elements after it generates an interrupt to the CPU to indicate that the lock is available for processing. Some of the key features of the DMA module are:

- Eight DMA Channels.
- Byte or word transfers.
- CPU interrupt after half or full block transfer complete.
- One-Shot or Auto-Repeat block transfer modes.
- Ping-Pong Mode (automatic switch between two DSPRAM start addresses after each block transfer is complete).

Relevant Functions:

setup_dma(channel, peripheral, mode) - Configures the DMA module to copy data from the specified peripheral to RAM allocated for the DMA channel.

dma_start(channel, mode, address) - Starts the DMA transfer for the specified channel in the specified mode of operation.

dma_status(channel) - This function will return the status of the specified channel in the DMA module.

Relevant Preprocessor:

None

Relevant Interrupts:

#INT_DMAX - Interrupt on channel X after DMA block or half block transfer.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
setup_dma(1,DMA_IN_SIP1,DMA_BYTE); // Setup channel 1 of the DMA
module to                               // read the SPI1 channel in byte
mode.
dma_start(1,DMA_CONTINUOUS|DMA_PING_PONG, 0x2000);
DMA                                     // Start the DMA channel with the
                                     // RAM address of 0x2000
```

Data Signal Modulator

The Data Signal Modulator (DSM) allows the user to mix a digital data stream (the “modulator signal”) with a carrier signal to produce a modulated output. Both the carrier and the modulator signals are supplied to the DSM module, either internally from the output of a peripheral, or externally through an input pin. The modulated output signal is generated by performing a logical AND operation of both the carrier and modulator signals and then it is provided to the MDOUT pin. Using this method, the DSM can generate the following types of key modulation schemes:

- Frequency Shift Keying (FSK)
- Phase Shift Keying (PSK)
- On-Off Keying (OOK)

Relevant Functions: *(8 bit or 16 bit depending on the device)*

setup_dsm(mode,source,carrier) - Configures the DSM module and selects the source signal and carrier signals.

setup_dsm(TRUE) - Enables the DSM module.

setup_dsm(FALSE) - Disables the DSM module.

Relevant Preprocessor:

None

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```

setup_dsm(DSM_ENABLED|DSM_OUTPUT_ENABLED,DSM_SOURCE_UART1,
DSM_CARRIER_HIGH_VSS|DSM_CARRIER_LOW_OC1);
//Enables DSM module with the output enabled and selects UART1
//as the source signal and VSS as the high carrier signal and OC1's
//PWM output as the low carrier signal.

if(input(PIN_B0))                                //Disable DSM module
    setup_dsm(FALSE);
else
    setup_dsm(TRUE);                            //Enable DSM module

```

Extended RAM

Some PIC24 devices have more than 30K of RAM. For these devices a special method is required to access the RAM above 30K. This extended RAM is organized into pages of 32K bytes each, the first page of extended RAM starts on page 1.

Relevant Functions:

write_extended_ram(p,addr,ptr,n); - Writes n bytes from ptr to extended RAM page p starting at address addr.

read_extended_ram(p,addr,ptr,n); - Reads n bytes from extended RAM page p starting at address addr to ptr.

Relevant Preprocessor:

None

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```

write_extended_ram(1,0x100,WriteData,8); //Writes 8 bytes from
WriteData to                                //addresses 0x100 to 0x107 of
                                           //extended RAM page 1.
read_extended_ram(1,0x100,ReadData,8);    //Reads 8 bytes from addresses
0x100                                     //to 0x107 of extended RAM page
1                                         //to ReadData.

```

External Memory

Some PIC18 devices have the external memory functionality where the external memory can be mapped to external memory devices like (Flash, EPROM or RAM). These functions are available only on devices that support external memory bus.

General Purpose I/O

These options let the user configure and use the I/O pins on the device. These functions will affect the pins that are listed in the device header file.

Relevant Functions:

output_high(pin) - Sets the given pin to high state.

output_low(pin) - Sets the given pin to the ground state.

output_float(pin) - Sets the specified pin to the input mode. This will allow the pin to float high to represent a high on an open collector type of connection.

output_x(value) - Outputs an entire byte to the port.

output_bit(pin,value) - Outputs the specified value (0,1) to the specified I/O pin.

input(pin) - The function returns the state of the indicated pin.

input_state(pin) - This function reads the level of a pin without changing the direction of the pin as INPUT() does.

set_tris_x(value) - Sets the value of the I/O port direction register. A '1' is an input and '0' is for output.

input_change_x() - This function reads the levels of the pins on the port, and compares them to the last time they were read to see if there was a change, 1 if there was, 0 if there was not.

set_open_drain_x(value) - This function sets the value of the I/O port Open-Drain register. A 1 makes the output open-drain and 0 makes the output push-pull.

set_input_level_x(value) - This function sets the value of the I/O port Input Level Register. A 1 sets the input level to ST and 0 sets the input level to TTL.

[PCD] set_open_drain_x() - Sets the value of the I/O port Open-Drain Control register. A '1' sets it as an open-drain output, and a '0' sets it as a digital output.

Relevant Preprocessor:

#USE STANDARD_IO(port) - This compiler will use this directive by default and it will automatically insert code for the direction register whenever an I/O function like output_high() or input() is used.

#USE FAST_IO(port) - This directive will configure the I/O port to use the fast method of performing I/O. The user will be responsible for setting the port direction register using the set_tris_x() function.

#USE FIXED_IO (port_outputs=;in,pin?) - This directive sets particular pins to be used as input or output, and the compiler will perform this setup every time this pin is used.

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

PIN:pb ----Returns a 1 if bit b on port p is on this part

Example Code:

```
#use fast_io(b) \
...
Int8 Tris_value= 0x0F;
int1 Pin_value;
set_tris_b(Tris_value); //Sets B0:B3 as input and B4:B7 as output
output_high(PIN_B7);    //Set the pin B7 to High
If(input(PIN_B0)) {     //Read the value on pin B0, set B7 to low if
                        //pin B0 is high
    output_high(PIN_B7);
}
```

Input Capture

These functions allow for the configuration of the input capture module. The timer source for the input capture operation can be set to either Timer 2 or Timer 3. In capture mode the value of the selected timer is copied to the ICxBUF register when an input event occurs and interrupts can be configured to fire as needed.

Relevant Functions:

setup_capture(x, mode) - Sets the operation mode of the input capture module x

get_capture(x, wait) - Reads the capture event time from the ICxBUF result register. If wait is true, program flow waits until a new result is present. Otherwise the oldest value in the buffer is returned.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_ICx - Interrupt fires on capture event as configured

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
setup_timer3(TMR_INTERNAL|TMR_DIV_BY_8);
setup_capture(2, CAPTURE_FE|CAPTURE_TIMER3);
while(TRUE){
    timerValue=get_capture(2,TRUE);
    printf("A module 2 capture event occurred: %LU", timerValue);
}
```

Internal LCD

Some families of PIC microcontrollers can drive a glass segment LCD directly, without the need of an LCD controller. For example, the PIC16C92X, PIC16F91X, and PIC16F193X series of chips have an internal LCD driver module.

Relevant Functions:

setup_lcd(mode, prescale, [segments]) - Configures the LCD Driver Module to use the specified mode, timer prescaler, and segments. For more information on valid modes and settings, see the setup_lcd() manual page and the *.h header file for the PIC micro-controller being used.

lcd_symbol(symbol, segment_b7 ... segment_b0) - The specified symbol is placed on the desired segments, where segment_b7 to segment_b0 represent SEGXX pins on the PIC micro-controller. For example, if bit 0 of symbol is set, then segment_b0 is set, and if segment_b0 is 15, then SEG15 would be set.

lcd_load(ptr, offset, length) - Writes length bytes of data from pointer directly to the LCD segment memory, starting with offset.

lcd_contrast (contrast) - Passing a value of 0 – 7 will change the contrast of the LCD segments, 0 being the minimum, 7 being the maximum.

Relevant Preprocessor:

None

Relevant Interrupts:

#INT_LCD - LCD frame is complete, all pixels displayed

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

LCD - Returns TRUE if the device has an Internal LCD Driver Module.

Example Code:

```

// How each segment of
the LCD is set
// (on or off) for the
ASCII digits to 9.
byte CONST DIGIT_MAP[10]={0xFC, 0x60, 0xDA, 0xF2, 0x66, 0xB6, 0xBE,
0xE0, 0xFE, 0xE6};

// Define the segment
information for the
// first digit of the LCD
#define DIGIT1 COM1+20, COM1+18, COM2+18, COM3+20, COM2+28, COM1+28,
COM2+20, COM3+18

// Displays the digits 0
to 9 on the first
// digit of the LCD.

for(i = 0; i <= 9; i++) {
    lcd_symbol( DIGIT_MAP[i], DIGIT1 );
    delay_ms( 1000 );
}
```

Internal Oscillator

Many chips have internal oscillator. There are different ways to configure the internal oscillator. Some chips have a constant 4 Mhz factory calibrated internal oscillator. The value is stored in some location (mostly the highest program memory) and the compiler moves it to the osccal register on startup. The programmers save and restore this value but if this is lost they need to be programmed before the oscillator is functioning properly. Some chips have factory calibrated internal oscillator that offers software selectable frequency range(from 31Kz to 8 Mhz) and they have a default value and can be switched

to a higher/lower value in software. They are also software tunable. Some chips also provide the PLL option for the internal oscillator.

[PCD] Two internal oscillators are present in PCD compatible devices, a fast RC and slow RC oscillator circuit. In many cases (consult the target datasheet or family datasheet for target specifics). The fast RC oscillator may be connected to a PLL system, allowing a broad range of frequencies to be selected. The Watchdog timer is derived from the slow internal oscillator.

Relevant Functions:

setup_oscillator(mode, finetune) - Sets the value of the internal oscillator and also tunes it. The options vary depending on the chip and are listed in the device header files.

setup_oscillator() - Explicitly configures the oscillator.

Relevant Preprocessor:

[PCD] `c#FUSES` - Specifies the values loaded in the device configuration memory. May be used to setup the oscillator configuration.

Relevant Interrupts:

INT_OSC_FAIL or **INT_OSCF** - Interrupt fires when the system oscillator fails and the processor switches to the internal oscillator.

[PCD] `#INT_OSCFAIL` - Interrupts on oscillator failure

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

[PCD] `CLOCK` - Returns the clock speed specified by `#use delay()`

[PCD] `FUSE_SETxxx` - Returns 1 if the fuse `xxxx` is set.

Example Code:

For PIC18F8722

```
setup_oscillator(OSC_32MHZ); //sets the internal oscillator to 32Mhz
(PLL enabled)
```

If the internal oscillator fuse option are specified in the `#fuses` and a valid clock is specified in the `#use delay(clock=xxx)` directive the compiler automatically sets up the oscillator. The `#use delay` statements should be used to tell the compiler about the oscillator speed.

Interrupts

The following functions allow for the control of the interrupt subsystem of the microcontroller. With these functions, interrupts can be enabled, disabled, and cleared. With the preprocessor directives, a default function can be called for any interrupt that does not have an associated ISR, and a global function can replace the compiler generated interrupt dispatcher.

Relevant Functions:

disable_interrupts() - Disables the specified interrupt.

enable_interrupts() - Enables the specified interrupt.

ext_int_edge() - Enables the edge on which the edge interrupt should trigger. This can be either rising or falling edge.

clear_interrupt() - This function will clear the specified interrupt flag. This can be used if a global isr is used, or to prevent an interrupt from being serviced.

interrupt_active() - This function checks the interrupt flag of specified interrupt and returns true if flag is set.

interrupt_enabled() - This function checks the interrupt enable flag of the specified interrupt and returns TRUE if set.

Relevant Preprocessor:

#DEVICE HIGH_INTS= - This directive tells the compiler to generate code for high priority interrupts.

#INT_XXX fast - This directive tells the compiler that the specified interrupt should be treated as a high priority interrupt.

[PCD] #INT_XXX level=x - x is an int 0-7, that selects the interrupt priority level for that interrupt.

[PCD] #INT_XXX fast - This directive makes use of shadow registers for fast register save. This directive can only be used in one ISR

Relevant Interrupts:

#int_default - This directive specifies that the following function should be called if an interrupt is triggered but no routine is associated with that interrupt.

#int_global - This directive specifies that the following function should be called whenever an interrupt is triggered. This function will replace the compiler generated interrupt dispatcher.

#int_xxx - This directive specifies that the following function should be called whenever the xxx interrupt is triggered. If the compiler generated interrupt dispatcher is used, the compiler will take care of clearing the interrupt flag bits.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
#int_timer0
void timer0interrupt()           // #int_timer associates the following
function with                    // the interrupt service routine that should
                                // be called.
enable_interrupts(TIMER0);      // enables the timer0 interrupt
disable_interrupts(TIMER0);     // disables the timer0 interrupt
clear_interrupt(TIMER0);        // clears the timer0 interrupt flag.
```

Low Voltage Detect

These functions configure the high/low voltage detect module. Functions available on the chips that have the low voltage detect hardware.

Relevant Functions:

setup_low_volt_detect(mode) - Sets the voltage trigger levels and also the mode (below or above in case of the high/low voltage detect module). The options vary depending on the chip and are listed in the device header files.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_LOWVOLT - Interrupt fires on low voltage detect

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

For PIC18F8722

```
setup_low_volt_detect(LVD_36|LVD_TRIGGER_ABOVE);
                                // sets the trigger level as 3.6
volts and
                                // trigger direction as above. The
interrupt
```

```
voltage is                                     // if enabled is fired when the
                                              // above 3.6 volts.
```

Output Compare/PWM Overview

The following functions are used to configure the output compare module. The output compare has three modes of functioning. Single compare, dual compare, and PWM. In single compare the output compare module simply compares the value of the OCxR register to the value of the timer and triggers a corresponding output event on match. In dual compare mode, the pin is set high on OCxR match and then placed low on an OCxRS match. This can be set to either occur once or repeatedly. In PWM mode the selected timer sets the period and the OCxRS register sets the duty cycle. Once the OC module is placed in PWM mode the OCxR register becomes read only so the value needs to be set before placing the output compare module in PWM mode. For all three modes of operation, the selected timer can either be Timer 2 or Timer 3.

Relevant Functions:

setup_comparex (x, mode) - Sets the *mode* of the output compare / PWM module x

set_comparex_time (x, ocr, [ocrs]) - Sets the OCR and optionally OCRS register values of module x.

set_pwm_duty (x, value) - Sets the PWM duty cycle of module x to the specified *value*

Relevant Preprocessor:

None

Relevant Interrupts:

INT_OCx - Interrupt fires after a compare event has occurred.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
OC2 pin                                     //Outputs a 1 second pulse on the
with                                       //using dual compare mode on a PIC
int16 OCR_2=0x1000;                       //an instruction clock of (20Mhz/4)
0x1000                                     //Start pulse when timer is at
```

```
int15 OCRS_2=0x5C4B;                                //End pulse after 0x04C4B timer
counts                                              // (0x1000+0x04C4B
                                                    // (1sec)/[(4/20000000*256)=0x04C4B
                                                    // 256-timer prescaler value (set in
code)
set_compare_time(2, OCR_2, OCRS_2);
setup_compare(2, COMPARE_SINGLE_PULSE|COMPARE_TIMER3);
setup_timer3(TMR_INTERNAL|TMR_DIV_BY_256);
```

Motor Control PWM

These options lets the user configure the Motor Control Pulse Width Modulator (MCPWM) module. The MCPWM is used to generate a periodic pulse waveform which is useful is motor control and power control applications. The options for these functions vary depending on the chip and are listed in the device header file.

Relevant Functions:

setup_motor_pwm(pwm,options, timebase); - Configures the motor control PWM module.

set_motor_pwm_duty(pwm,unit,time) - Configures the motor control PWM unit duty.

set_motor_pwm_event(pwm,time) - Configures the PWM event on the motor control unit.

set_motor_unit(pwm,unit,options, active_deadtime, inactive_deadtime); - Configures the motor control PWM unit.

get_motor_pwm_event(pwm); - Returns the PWM event on the motor control unit.

Relevant Preprocessor:

None

Relevant Interrupts:

#INT_PWM1 - PWM Timebase Interrupt

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
                                                    //Sets up the motor PWM module
setup_motor_pwm(1,MPWM_FREE_RUN|MPWM_SYNC_OVERRIDES,timebase);
```

```

                                //Sets the PWM1, Group 1 duty cycle value to
0x55
set_motor_pwm_duty(1,1,0x55);

                                //Sets the motor PWM event
set_motor_pwm_event(pwm,time);

                                //Enable pwm pair
set_motor_unit(1,1,mpwm_ENABLE,0,0);
                                //Enables pwm1, Group 1 in complementary
mode,
                                //no deadtime.

```

PMP/EPMP

The Parallel Master Port (PMP)/Enhanced Parallel Master Port (EPMP) is a parallel 8-bit/16-bit I/O module specifically designed to communicate with a wide variety of parallel devices. Key features of the PMP module are:

- 8 or 16 Data lines
- Up to 16 or 32 Programmable Address Lines
- Up to 2 Chip Select Lines
- Programmable Strobe option
- Address Auto-Increment/Auto-Decrement
- Programmable Address/Data Multiplexing
- Programmable Polarity on Control Signals
- Legacy Parallel Slave(PSP) Support
- Enhanced Parallel Slave Port Support
- Programmable Wait States

Relevant Functions:

setup_psp (options,address_mask) - This will setup the PSP module for various mode and specifies which address lines to be used.

setup_pmp_csx(options,[offset]) - Sets up the Chip Select X Configuration, Mode and Base Address registers.

[PCD] setup_pmp (options,address_mask) - This will setup the PMP/EPMP module for various mode and specifies which address lines to be used.

setup_psp_cs(options) - Sets up the Chip Select X Configuration and Mode registers.

psp_output_full() - This will return the status of the output buffers.

[PCD] pmp_address(address) - Configures the address register of the PMP module with the destination address during Master mode operation.

[PCD] **pmp_input_full ()** - This will return the status of the input buffers.

[PCD] **psp_input_full()** - This will return the status of the input buffers.

[PCD] **pmp_output_full()** - This will return the status of the output buffers.

[PCD] **pmp_overflow ()** - This will return the status of the output buffer underflow bit.

[PCD] **pmp_read()** - Reads a byte of data.

[PCD] **psp_read(address)/ psp_read()** - psp_read() will read a byte of data from the next buffer location and psp_read (address) will read the buffer location address.

[PCD] **pmp_write (data)** - Write the data byte to the next buffer location.

[PCD] **psp_write(address,data)/ psp_write(data)** - This will write a byte of data to the next buffer location or will write a byte to the specified buffer location.

Relevant Preprocessor:

None

Relevant Interrupts:

#INT_PMP - Interrupt on read or write strobe

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
setup_pmp( PAR_ENABLE |                // Sets up Master mode with
          PAR_MASTER_MODE_1 |           // address lines  PMA0:PMA7
          PAR_STOP_IN_IDLE, 0xFF );

if (pmp_output_full())
{
    pmp_write(next_byte);
}
```

Power PWM

These options lets the user configure the Pulse Width Modulation (PWM) pins. They are only available on devices equipped with PWM. The options for these functions vary depending on the chip and are listed in the device header file.

Relevant Functions:

setup_power_pwm(config) - Sets up the PWM clock, period, dead time etc.

setup_power_pwm_pins(module x) - Configure the pins of the PWM to be in Complementary, ON or OFF mod.

set_power_pwm_duty(duty) - Stores the value of the duty cycle in the PDCXL/H register. This duty cycle value is the time for which the PWM is in active state.

set_power_pwm_override(pwm,override,value) - This function determines whether the OVDCONS or the PDC registers determine the PWM output .

Relevant Preprocessor:

None

Relevant Interrupts:

#INT_PWM_TB - PWM Timebase Interrupt (Only available on PIC18XX31)

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
....
long duty_cycle, period;
...
// Configures PWM pins to be
ON, OFF // or in Complimentary mode.

setup_power_pwm_pins(PWM_COMPLEMENTARY ,PWM_OFF, PWM_OFF,
PWM_OFF_);
// Sets up PWM clock , postscale
and // period. Here period is used
to set the // PWM Frequency as follows:
// Frequency=Fosc/(4* (period+1)
// *postscale)

setup_power_pwm(PWM_CLOCK_DIV_4|PWM_FREE_RUN,1,0,period,0,1,0);
set_power_pwm0_duty(duty_cycle)); // Sets the duty cycle of
the PWM 0,1 in // Complementary mode
```

Program EEPROM

The Flash program memory is readable and writable in some chips and is just readable in some. These options allows the user to read and write to the Flash program memory. These functions are only available in Flash chips.

Relevant Functions:

read_program_eeprom(address) - Reads the program memory location (16-bit or 32-bit depending on the device).

write_program_eeprom(address, value) - Writes value to program memory location address.

erase_program_eeprom(address) - Erases FLASH_ERASE_SIZE bytes in program memory.

write_program_memory(address,dataptr,count) - Writes count bytes to program memory from dataptr to address. When address is a mutiple of FLASH_ERASE_SIZE an erase is also performed.

[PCD] When address is a mutiple of FLASH_ERASE_SIZE an erase is also performed.

read_program_memory(address,dataptr,count) - Read count bytes from program memory at address to dataptr.

read_calibration_memory(cal_word) - Read one of the calibration words from calibration memory on MCP191xx devices.

[PCD] read_rom_memory(address,dataptr,count) - Reads count bytes from program memory from address.

-

Relevant Preprocessor:

#ROM address={list} - Can be used to put program memory data into the hex file.

#DEVICE(WRITE_EEPROM=ASYNC) - Can be used with #DEVICE to prevent the write function from hanging. When this is used make sure the eeprom is not written both inside and outside the ISR.

Relevant Interrupts:

INT_EEPROM - Interrupts fire when EEPROM write is complete.

Relevant Include Files:

None, all functions built-in

Relevant getenv() Parameters:

PROGRAM_MEMORY - Size of program memory.

READ_PROGRAM - Returns 1 if program memory can be read.

FLASH_WRITE_SIZE - Smallest number of bytes written in Flash.

FLASH_ERASE_SIZE - Smallest number of bytes erased in Flash.

[PCD] MIN_FLASH_WRITE - Smallest number of bytes that can be written to Flash with write_program_memory() function.

Example Code:

For 18F452 where the write size is 8 bytes and erase size is 64 bytes

```
#rom 0xa00={1,2,3,4,5}           //inserts this data into the hex
file.
erase_program_eeprom(0x1000);      //erases 64 bytes starting at
0x1000
write_program_eeprom(0x1000,0x1234); //writes 0x1234 to 0x1000
value=read_program_eeprom(0x1000); //reads 0x1000 returns 0x1234
write_program_memory(0x1000,data,8); //of 64 and writes 8 bytes from
data to 0x1000
read_program_memory(0x1000,value,8); //reads 8 bytes to value from
0x1000
erase_program_eeprom(0x1000);      //erases 64 bytes starting at
0x1000
write_program_memory(0x1010,data,8); //writes 8 bytes from data to
0x1000
read_program_memory(0x1000,value,8); //reads 8 bytes to value from
0x1000
```

For chips where getenv("FLASH_ERASE_SIZE") > getenv("FLASH_WRITE_SIZE")

WRITE_PROGRAM_EEPROM - Writes 2 bytes, does not erase (use ERASE_PROGRAM_EEPROM)

WRITE_PROGRAM_MEMORY - Writes any number of bytes, will erase a block whenever the first (lowest) byte in a block is written to. If the first address is not the start of a block that block is not erased.

ERASE_PROGRAM_EEPROM - Will erase a block. The lowest address bits are not used.

For chips where getenv("FLASH_ERASE_SIZE") = getenv("FLASH_WRITE_SIZE")

WRITE_PROGRAM_EEPROM - Writes 2 bytes, no erase is needed.

WRITE_PROGRAM_MEMORY - Writes any number of bytes, bytes outside the range of the write block are not changed. No erase is needed.

ERASE_PROGRAM_EEPROM - Not available.

[PCD]

```
#rom 0x1000={1,2,3,4}           //Inserts this data into the hex
file
erase_program_memory(0x1000);    //Erases flash page containing
address
                                //0x1000, erase size depends on
                                //FLASH_ERASE_SIZE
write_program_memory(0x1000,data,12); //Write 12 bytes from data
program memory
                                //starting at address 0x1000, if
address
```



```
        //0x1000 is the start of a flash erase
        //block, then erase will be done first.
read_program_memory(0x1000,value,12); //Reads 12 bytes to value from
program
        //memory starting at address 0x1000.
WRITE_PROGRAM_MEMORY //Writes any number of bytes that is a
        //multiple of MIN_FLASH_WRITE. Will
        //erase a block whenever the first
(lowest) //byte in a block is written to. If the
        //first address is not the start of a block
        //that block is not erased.
ERASE_PROGRAM_MEMORY //Erases a block of size FLASH_ERASE_SIZE.
        //The lowest address bit are not used.
        //i.e. any address passed to function will
        cause block it is contained in to be erased.
```

PSP

These options let to configure and use the Parallel Slave Port on the supported devices.

Relevant Functions:

setup_psp(mode) - Enables/disables the psp port on the chip.

psp_output_full() - Returns 1 if the output buffer is full(waiting to be read by the external bus).

psp_input_full() - Returns 1 if the input buffer is full(waiting to read by the cpu).

psp_overflow() - Returns 1 if a write occurred before the previously written byte was read.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_PSP - Interrupt fires when PSP data is in

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

PSP - Returns 1 if the device has PSP

Example Code:

```
while(psp_output_full()); //waits till the output buffer is
cleared
psp_data=command;         //writes to the port
```

```
while(!input_buffer_full()); //waits till input buffer is
cleared
if (psp_overflow())
    error=true                //if there is an overflow set the
error flag
else
    data=psp_data;           //if there is no overflow then read
the port
```

QEI

The Quadrature Encoder Interface (QEI) module provides the interface to incremental encoders for obtaining mechanical positional data.

Relevant Functions:

setup_qei(options, filter,maxcount) - Configures the QEI module.

qei_status() - Returns the status of the QEI module

qei_set_count(value) - Writes a 16-bit value to the position counter.

qei_get_count() - Reads the current 16-bit value of the position counter.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_QEI - Interrupt on rollover or underflow of the position counter

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
int16 value;
setup_qei(QEI_MODE_X2|           //Setup the QEI module
QEI_TIMER_INTERNAL,
QEI_FILTER_DIV_2,QEI_FORWARD);

Value=qei_get_count();           //Read the count
```

RS232 I/O

These functions and directives can be used for setting up and using RS232 I/O functionality.

Relevant Functions:

getc() or getch() / getchar() or fgetc() - Gets a character on the receive pin (from the specified stream in case of fgetc, stdin by default). Use KBHIT to check if the character is available.

gets() or fgets() - Gets a string on the receive pin (from the specified stream in case of fgets, STDIN by default). Use getc to receive each character until return is encountered.

putc() or putchar() or fputc() - Puts a character over the transmit pin (on the specified stream in the case of fputc, stdout by default).

puts() or fputs() - Puts a string over the transmit pin (on the specified stream in the case of fputc, stdout by default). Uses putc to send each character.

printf() or fprintf() - Prints the formatted string (on the specified stream in the case of fprintf, stdout by default). Refer to the printf help for details on format string.

kbhit() - Return true when a character is received in the buffer in case of hardware RS232 or when the first bit is sent on the RCV pin in case of software RS232. Useful for polling without waiting in getc.

setup_uart(baud,[stream]) or setup_uart_speed(baud,[stream]) - Used to change the baud rate of the hardware UART at run-time. Specifying stream is optional. Refer to the help for more advanced options.

assert(condition) - Checks the condition and if false prints the file name and line to STDERR. Will not generate code if #DEFINE NODEBUG is used.

perror(message) - Prints the message and the last system error to STDERR.

putc_send() or fputc_send() - When using transmit buffer, used to transmit data from buffer. See function description for more detail on when needed.

rcv_buffer_bytes() - When using receive buffer, returns the number of bytes in buffer that still need to be retrieved.

tx_buffer_bytes() - When using transmit buffer, returns the number of bytes in buffer that still need to be sent.

tx_buffer_full() - When using transmit buffer, returns TRUE if transmit buffer is full.

receive_buffer_full() - When using receive buffer, returns TRUE if receive buffer is full.

tx_buffer_available() - When using transmit buffer, returns number of characters that can be put into transmit buffer before it overflows.

#useRS232 - Configures the compiler to support RS232 to specifications.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_RDA - Interrupt fires when the receive data available.

INT_TBE - Interrupt fires when the transmit data empty.

*Some devices have more than one hardware UART, hence more interrupts.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

UART - Returns the number UARTs on this device.

AUART - Returns TRUE if this UART is an advanced UART.

UART_RX - Returns the receive pin for the first UART on this device (see PIN_XX)

UART_TX - Returns the transmit pin for the first UART on this device.

UART2_RX - Returns the receive pin for the second UART on this device.

UART2-TX - Returns the transmit pin for the second UART on this device.

Example Code:

```
/*configure and enable uart, use first hardware UART on PIC*/
#use rs232(uart1, baud=9600)

/* print a string*/
printf("enter a character");

/* get a character*/
if (kbhit())                                //check if a character has
been received                               //read character from UART
    c=getc();
```

RTCC

The Real Time Clock and Calendar (RTCC) module is intended for applications where accurate time must be maintained for extended periods of time with minimum or no intervention from the CPU. The key features of the module are:

- Time: Hour, Minute and Seconds.
- 24-hour format (Military Time)
- Calendar: Weekday, Date, Month and Year.

- Alarm Configurable.
- Requirements: External 32.768 kHz Clock Crystal.

Relevant Functions:

setup_rtc(options, calibration); - This will setup the RTCC module for operation and also allows for calibration setup.

rtc_write(rtc_time_t datetime) - Writes the date and time to the RTCC module.

rtc_read(rtctime_t datetime) - Reads the current value of Time and Date from the RTCC module.

setup_rtc_alarm(options, mask, repeat); - Configures the alarm of the RTCC module.

rtc_alarm_write(rtctime_t datetime); - Writes the date and time to the alarm in the RTCC module.

rtc_alarm_read(rtctime_t datetime); - Reads the date and time to the alarm in the RTCC module.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_RTC - Interrupt on Alarm Event on half alarm frequency.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

```
setup_rtc(RTC_ENABLE|RTC_OUTPUT_SECONDS,0x00); //Enable RTCC module
with seconds                                     //clock and no

calibration.                                     //Write the value of Date and
rtc_write(datetime);                             //to the RTC module.
Time                                              //Reads the value to a

rtc_read(datetime);
structure time_t.
```

RTOS

These functions control the operation of the CCS Real Time Operating System (RTOS). This operating system is cooperatively multitasking and allows for tasks to be scheduled

to run at specified time intervals. Because the RTOS does not use interrupts, the user must be careful to make use of the `rtos_yield()` function in every task so that no one task is allowed to run forever.

Relevant Functions:

`rtos_run()` - Begins the operation of the RTOS. All task management tasks are implemented by this function.

`rtos_terminate()` - This function terminates the operation of the RTOS and returns operation to the original program. Works as a return from the `rtos_run()` function.

`rtos_enable(task)` - Enables one of the RTOS tasks. Once a task is enabled, the `rtos_run()` function will call the task when its time occurs. The parameter to this function is the name of task to be enabled.

`rtos_disable(task)` - Disables one of the RTOS tasks. Once a task is disabled, the `rtos_run()` function will not call this task until it is enabled using `rtos_enable()`. The parameter to this function is the name of the task to be disabled.

`rtos_msg_poll()` - Returns true if there is data in the task's message queue.

`rtos_msg_read()` - Returns the next byte of data contained in the task's message queue.

`rtos_msg_send(task,byte)` - Sends a byte of data to the specified task. The data is placed in the receiving task's message queue.

`rtos_yield()` - Called with in one of the RTOS tasks and returns control of the program to the `rtos_run()` function. All tasks should call this function when finished.

`rtos_signal(sem)` - Increments a semaphore which is used to broadcast the availability of a limited resource.

`rtos_wait(sem)` - Waits for the resource associated with the semaphore to become available and then decrements to semaphore to claim the resource.

`rtos_await(expre)` - Will wait for the given expression to evaluate to true before allowing the task to continue.

`rtos_ouerrun(task)` - Will return true if the given task over ran its allotted time.

`rtos_stats(task,stat)` - Returns the specified statistic about the specified task. The statistics include the minimum and maximum times for the task to run and the total time the task has spent running.

Relevant Preprocessor:

`#USE RTOS(options)` - This directive is used to specify several different RTOS attributes including the timer to use, the minor cycle time and whether or not statistics should be enabled.

`#TASK(options)` - This directive tells the compiler that the following function is to be an RTOS task.

#TASK - Specifies the rate at which the task should be called, the maximum time the task shall be allowed to run, and how large its queue should be.

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in.

Relevant getenv() Parameters:

None

Example Code:

```
#USE_RTOS(timer=0,minor_cycle=20ms)    // RTOS will use timer zero,
minor_cycle                             // will be 20ms

...
int sem;
...
#TASK(rate=1s,max=20ms,queue=5)        // Task will run at a rate of
once per second                        // with a maximum running time
void task_name();                      // a 5 byte queue
of 20ms and                            // begins the RTOS
                                        // ends the RTOS
                                        // enables the previously
rtos_run();                             // disables the previously
rtos_terminate();                       // places the value 5 in
rtos_enable(task_name);                 task_names queue.
declared task                           // yields control to the RTOS
rtos_disable(task_name);                 // signals that the resource
declared task                           // sem is available.
rtos_msg_send(task_name,5);
rtos_yield();
rtos_signal(sem);
represented by
```

For more information on the CCS RTOS please

SPI

SPI™ is a fluid standard for 3 or 4 wire, full duplex communications named by Motorola. Most PIC devices support most common SPI™ modes. CCS provides a support library for taking advantage of both hardware and software based SPI™ functionality. For software support, see #USE SPI.

Relevant Functions:

setup_spi(mode), setup_spi2(mode) - Configure the hardware SPI to the specified mode. The mode configures setup_spi2(mode) thing such as master or slave mode, clock speed and clock/data trigger configuration.

Note: for devices with dual SPI interfaces a second function, setup_spi2(), is provided to configure the second interface.

spi_data_is_in(), spi_data_is_in2() - Returns TRUE if the SPI receive buffer has a byte of data.

spi_write(value), spi_write2(value) - Transmits the value over the SPI interface. This will cause the data to be clocked out on the SDO pin.

spi_read(value), spi_read2(value) - Performs an SPI transaction, where the value is clocked out on the SDO pin and data clocked in on the SDI pin is returned. If you just want to clock in data then you can use spi_read() without a parameter.

spi_set_txcnt(value) - Sets the number of SPI transfers to drive SS1 pin to active level. Only available on PIC18 devices with a dedicated SPI peripheral.

Relevant Preprocessor:

None

Relevant Interrupts:

#int_ssp, #int_ssp2 - Transaction (read or write) has completed on the indicated peripheral.

[PCD] #int_spi1 - Interrupts on the activity from the first SPI module.

[PCD] #int_spi2 - Interrupts on the activity from the second SPI module.

Relevant Include Files:

None, all functions built-in to the compiler.

Relevant getenv() Parameters:

SPI - Returns TRUE if the device has an SPI peripheral.

Example Code:

```

//configure the device to be a
master,
//data transmitted on H-to-L clock
transition
setup_spi(SPI_MASTER|SPI_H_TO_L|SPI_CLK_DIV_16);
spi_write(0x80); //write 0x80 to SPI device
value=spi_read(); //read a value from the
SPI device
```



```
value=spi_read(0x80);           //write 0x80 to SPI device
the same                        //time reading a value.
                                //drives SS1 pin to active
spi_set_txcnt(3);
level                            //for 3 SPI transfers
```

Timers

The 16-bit DSC and MCU families implement 16 bit timers. Many of these timers may be concatenated into a hybrid 32 bit timer. Also, one timer may be configured to use a low power 32.768 kHz oscillator which may be used as a real time clock source.

Timer1 is a 16-bit timer. It is the only timer that may not be concatenated into a hybrid 32-bit timer. However, it alone may use a synchronous external clock. This feature may be used with a low power 32.768 kHz oscillator to create a real-time clock source.

Timers 2 through 9 are 16-bit timers. They may use external clock sources only asynchronously and they may not act as low power real time clock sources. They may however be concatenated into 32-bit timers. This is done by configuring an even numbered timer (timer 2, 4, 6 or 8) as the least significant word, and the corresponding odd numbered timer (timer 3, 5, 7 or 9, respectively) as the most significant word of the new 32-bit timer.

Timer interrupts will occur when the timer overflows. Overflow will happen when the timer surpasses its period, which by default is 0xFFFF. The period value may be changed when using **setup_timer_X**.

Relevant Functions:

setup_timer_X() - Configures the timer peripheral. X may be any valid timer for the target device. Consult the target datasheet or use getenv to find the valid timers.

get_timerX() - Retrieves the current 16-bit value of the timer.

get_timerXY() - Gets the 32-bit value of the concatenated timers X and Y (where XY may only be 23, 45, 67, 89).

set_timerX() - Sets the value of timerX.

set_timerXY() - Sets the 32-bit value of the concatenated timers X and Y (where XY may only be 23, 45, 67, 89).

Relevant Preprocessor:

None

Relevant Interrupts:

#int_timerX - Interrupts on timer overflow (period match). X is any valid timer number.

*When using a 32-bit timer, the odd numbered timer-interrupt of the hybrid timer must be used (i.e. when using 32-bit Timer 23, #int_timer3).

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMERX - Returns 1 if the device has the timer peripheral X. X may be 1-9.

Example Code:

```
/*Setup timer1 as an external realtime clock that increments every 16
clock cycles*/
setup_timer1(T1_EXTERNAL_RTC|T2_DIV_BY_16);

/*Setup timer2 as a timer that increments on every instruction cycle
and has
a period of 0x0100*/
setup_timer2(TMR_INTERNAL,0x0100);
byte value=0x00
value=get_timer2();           //retrieve the current value of timer2
```

Timer0

These options lets the user configure and use timer0. It is available on all devices and is always enabled. The clock/counter is 8-bit on PIC16 and 8 or 16 bit on PIC18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:

setup_timer_0(mode) - Sets the source, prescale etc for timer0

set_timer0(value) or set_rtcc(value) - Initializes the timer0 clock/counter. Value may be a 8-bit or 16-bit depending on the device.

value=get_timer0 - Returns the value of the timer0 clock/counter.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMER0 or INT_RTCC - Interrupt fires when timer0 overflows.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMER0 - Returns 1 if the device has timer0

Example Code:

For PIC18F452:

```
setup_timer_0(RTCC_INTERNAL|RTCC_DIV_@|RTCC_8_BIT);  
                                     //sets the internal clock as source  
                                     //and prescale 2. At 20Mhz timer0  
                                     //will increment every 0.4us in this  
                                     //setup and overflows every 102.4us  
set_timer0(0);                       //this sets timer0 register to 0  
time-get_timer0();                   this will read the timer0 register  
value
```

Timer1

These options lets the user configure and use timer1. The clock/counter is 16-bit on PIC16s and PIC18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:

setup_timer_1(mode) - Disables or sets the source and prescale for timer1.

set_timer1(value) - Initializes the timer1 clock/counter.

value=get_timer1 - Returns the value of the timer1 clock/counter.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMER1 - Interrupt fires when timer1 overflows

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMER1 - Returns 1 if the device has timer1

Example Code:

For PIC18452:

```
setup_timer_1(T1_DISABLED);           //disables timer1
setup_timer_1(T1_INTERNAL|T1_DIV_BY_8); //sets the internal clock as
source                                //and prescale as 8. At 20Mhz

timer1                                //will increment every 1.6us in

this                                  //setup and overflows every

104.896ms                             //this sets timer1 register to
set_timer1(0);                         0
time=get_timer1();                     //this will read the timer1
register value
```

Timer2

These options lets the user configure and use timer2. The clock/counter is 8-bit on PIC16s and PIC18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:

setup_timer_2(mode,period,postscale) - Disables or sets the prescale, period and a postscale for timer2.

set_timer2(value) - Initializes the timer2 clock/counter.

value=get_timer2 - Returns the value of the timer2 clock/counter.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMER2 - Interrupt fires when timer2 overflows

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMER2 - Returns 1 if the device has timer2

Example Code:

For PIC18452:

```
setup_timer_2(T2_DISABLED);           //disables timer2
setup_timer_2(T2_INTERNAL|T2_DIV_BY_4,0xc0,2); //sets the prescale as
4, period                               //as 0xc0 and postscales
```

```
as 2.                                     //At 20Mhz timer2 will
increment                                // very .8us in this
setup                                    // and overflows every
154.4us                                  //and interrupt every
308.2us                                  //this sets timer2
set_timer2(0);                           //this will read timer2
register to 0
time=get_timer2();
register value
```

Timer3

Timer3 is very similar to timer1. So please refer to the [Timer1](#) section for more details.

Timer4

Timer4 is very similar to Timer2. So please refer to the [Timer2](#) section for more details.

Timer5

These options lets the user configure and use timer5. The clock/counter is 16-bit and is available only on 18Fxx31 devices. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:

setup_timer_5(mode) - Disables or sets the source and prescale for timer5.

set_timer5(value) - Initializes the timer5 clock/counter.

value=get_timer5 - Returns the value of the timer5 clock/counter

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMER5 - Interrupt fires when timer5 overflows.

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMER5 - Returns 1 if the device has timer5.

Example Code:

For PIC18F4431

```
setup_timer_5(T5_DISABLED);           //disables timer5
setup_timer_5(T5_INTERNAL|T5_DIV_BY_1); //sets the internal clock as
source and                             //prescale as 1. At 20Mhz

timer5 will                             //increment every .2us in this

setup                                  //and overflows every 13.1072ms
                                        //this sets timer5 register to
set_timer5(0);                         //this will read the timer5
0
time=get_timer5();                     //this will read the timer5
register value
```

TimerA

These options lets the user configure and use timerA. It is available on devices with Timer A hardware. The clock/counter is 8 bit. It counts up and also provides interrupt on overflow. The options available are listed in the device's header file.

Relevant Functions:

setup_timer_A(mode) - Disable or sets the source and prescale for timerA.

set_timerA(value) - Initializes the timerA clock/counter.

value=get_timerA() - Returns the value of the timerA clock/counter

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMER_A - Interrupt fires timerA overflows

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMERA - Returns 1 if the device has timerA

Example Code:

```
setup_timer_A(TA_OFF);                 //disable timerA
setup_timer_A(TA_INTERNAL|TA_DIV_8); //sets the internal clock as
source                                //and prescale as 8. At 20Mhz

timerA
```

```

this                                     //will increment every 1.6us in

set_timerA(0):                          //setup and overflows every 409.6us
time=get_timerA();                      //this sets timerA register to 0
register value                          //this will read the timerA
```

TimerB

These options lets the user configure and use timerB. It is available on devices with TimerB hardware. The clock/counter is 8-bit. It counts up and also provides interrupt on overflow. The options available are listed in the device's header file.

Relevant Functions:

setup_timer_B(mode) - Disable or set the source and prescale for timerB.

set_timerB(value) - Initializes the timerB clock/counter.

value=get_timerB() - Returns the value of the timerB clock/counter.

Relevant Preprocessor:

None

Relevant Interrupts:

INT_TIMERB - Interrupt fires when timerB overflows

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

TIMERB - Returns 1 if the device has timerB

Example Code:

```

setup_timer_B(TB_OFF);                  //disable timer
setup_timer_B(TB_INTERNAL|TB_DIV_8);    //sets the internal clock as
source                                 //and prescale as 8. At 20Mhz

timerB                                 //will increment every 1.6us in

this                                  //setup and overflows every 409.6us

set_timerB(0):                          //this sets timerB register to 0
time=get_timerB();                      //this will read the timerB
register value
```

USB

Universal Serial Bus, or USB, is used as a method for peripheral devices to connect to and talk to a personal computer. CCS provides libraries for interfacing a PIC to PC using USB by using a device with an internal USB peripheral (like the PIC16C765 or the PIC18F4550 family) or by using any device with an external USB peripheral (the National USBN9603 family).

Relevant Functions:

usb_init() - Initializes the USB hardware. Will then wait in an infinite loop for the USB peripheral to be connected to bus (but that doesn't mean it has been enumerated by the PC). Will enable and use the USB interrupt.

usb_init_cs() - The same as **usb_init()**, but does not wait for the device to be connected to the bus. This is useful if your device is not bus powered and can operate without a USB connection.

usb_task() - If you use connection sense, and the **usb_init_cs()** for initialization, then you must periodically call this function to keep an eye on the connection sense pin. When the PIC is connected to the BUS, this function will then prepare the USB peripheral. When the PIC is disconnected from the BUS, it will reset the USB stack and peripheral. Will enable and use the USB interrupt.

Note: In your application you must define **USB_CON_SENSE_PIN** to the connection sense pin.

usb_detach() - Removes the PIC from the bus. Will be called automatically by **usb_task()** if connection is lost, but can be called manually by the user.

usb_attach() - Attaches the PIC to the bus. Will be called automatically by **usb_task()** if connection is made, but can be called manually by the user.

usb_attached() - If using connection sense pin (**USB_CON_SENSE_PIN**), returns TRUE if that pin is high. Else will always return TRUE.

usb_enumerated() - Returns TRUE if the device has been enumerated by the PC. If the device has been enumerated by the PC, that means it is in normal operation mode and you can send/receive packets.

usb_put_packet(endpoint, data, len, tgl) - Places the packet of data into the specified endpoint buffer. Returns TRUE if success, FALSE if the buffer is still full with the last packet.

usb_puts(endpoint, data, len, timeout) - Sends the following data to the specified endpoint. **usb_puts()** differs from **usb_put_packet()** in that it will send multi packet messages if the data will not fit into one packet.

usb_kbhit(endpoint) - Returns TRUE if the specified endpoint has data in it's receive buffer

usb_get_packet(endpoint, ptr, max) - Reads up to max bytes from the specified endpoint buffer and saves it to the pointer ptr. Returns the number of bytes saved to ptr.

usb_gets(endpoint, ptr,max, timeout) - Reads a message from the specified endpoint. The difference usb_get_packet() and usb_gets() is that usb_gets() will wait until a full message has received, which a message may contain more than one packet. Returns the number of bytes received.

Relevant CDC Functions:

A CDC USB device will emulate an RS-232 device, and will appear on your PC as a COM port. The follow functions provide you this virtual RS-232/serial interface.

Note: When using the CDC library, you can use the same functions above, but do not use the packet related function such as: usb_kbhit(), usb_get_packet(), etc.

usb_cdc_kbhit() - The same as kbhit(), returns TRUE if there is 1 or more character in the receive buffer.

usb_cdc_getc() - The same as getc(), reads and returns a character from the receive buffer. If there is no data in the receive buffer it will wait indefinitely until there a character has been received.

usb_cdc_putc(c) - The same as putc(), sends a character. It actually puts a character into the transmit buffer, and if the transmit buffer is full will wait indefinitely until there is space for the character.

usb_cdc_putc_fast(c) - The same as usb_cdc_putc(), but will not wait indefinitely until there is space for the character in the transmit buffer. In that situation the character is lost.

usb_cdc_puts(*str) - Sends a character string (null terminated) to the USB CDC port. Will return FALSE if the buffer is busy, TRUE if buffer is string was put into buffer for sending. Entire string must fit into endpoint, if string is longer than endpoint buffer then excess characters will be ignored.

usb_cdc_putready() - Returns TRUE if there is space in the transmit buffer for another character.

Relevant Preprocessor:

None

Relevant Interrupts:

#int_usb - A USB event has happened, and requires application intervention. The USB library that CCS provides handles this interrupt automatically.

Relevant Include Files:

pic_usb.h - Hardware layer driver for the PIC16C765 family PICmicro controllers with an internal USB peripheral.

pic18_usb.h - Hardware layer driver for the PIC18F4550 family PICmicro controllers with an internal USB peripheral.

usbn960x.h - Hardware layer driver for the National USBN9603/USBN9604 external USB peripheral. You can use this external peripheral to add USB to any microcontroller.

usb.h - Common definitions and prototypes used by the USB driver.

usb.c - The USB stack, which handles the USB interrupt and USB Setup Requests on Endpoint 0.

usb_cdc.h - A driver that takes the previous include files to make a CDC USB device, which emulates an RS232 legacy device and shows up as a COM port in the MS Windows device manager.

Relevant getenv() Parameters:

USB - Returns TRUE if the device has an integrated internal USB peripheral.

Example Code:

Due to the complexity of USB example code will not fit here. But you can find the following examples installed with your CCS C Compiler:

ex_usb_hid.c - A simple HID device

ex_usb_mouse.c - A HID Mouse, when connected to the PC, the mouse cursor will go in circles.

ex_usb_kbmouse.c - An example of how to create a USB device with multiple interfaces by creating a keyboard and mouse in one device.

ex_usb_kbmouse2.c - An example of how to use multiple HID report IDs to transmit more than one type of HID packet, as demonstrated by a keyboard and mouse on one device.

ex_usb_scope.c - A vendor-specific class using bulk transfers is demonstrated.

ex_usb_serial.c - The CDC virtual RS232 library is demonstrated with this RS232 < - > USB example.

ex_usb_serial2.c - Another CDC virtual RS232 library example, this time a port of the ex_intee.c example to use USB instead of RS232.

Voltage Reference

These functions configure the voltage reference module. These are available only in the supported chips.

Relevant Functions:

setup_vref(mode | value) - Enables and sets up the internal voltage reference value. Constants are defined in the device's .h file.

Relevant Preprocessor:

None

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

VREF - Returns 1 if the device has VREF

Example Code:

```
#INT_COMP //comparator interrupt handler
void isr() {
    safe_conditions = FALSE;
    printf("WARNING!!!! Voltage level is above 3.6V. \r\n");
}

setup_comparator(A1_VR_OUT_ON_A2) //sets 2 comparators (A1 and VR and A2
as output)
{
    setup_vref(VREF_HIGH | 15); //sets 3.6 (vdd * value/32 + vdd/4) if
vdd is 5.0V
    enable_interrupts(INT_COMP); // enable the comparator interrupt
    enable_interrupts(GLOBAL); //enable global interrupts
}
```

WDT or Watch Dog Timer

Different chips provide different options to enable/disable or configure the WDT.

Relevant Functions:

setup_wdt() - Enables/disables the wdt or sets the prescaler.

restart_wdt() - Restarts the wdt, if wdt is enabled this must be periodically called to prevent a timeout reset.

For PCB/PCM chips it is enabled/disabled using WDT or NOWDT fuses whereas on PCH device it is done using the `setup_wdt` function.

The timeout time for PCB/PCM chips are set using the `setup_wdt` function and on PCH using fuses like WDT16, WDT256 etc.

RESTART_WDT when specified in #USE DELAY, #USE I2C and #USE RS232 statements like this #USE DELAY(clock=20000000, restart_wdt) will cause the wdt to restart if it times out during the delay or I2C_READ or GETC.

Relevant Preprocessor:

#FUSES WDT/NOWDT - Enables/Disables WDT in PCB/PCM devices.

#FUSES WDT16 - Sets up the timeout/timein in PCH devices.

Relevant Interrupts:

None

Relevant Include Files:

None, all functions are built-in

Relevant getenv() Parameters:

None

Example Code:

For PIC16F877

```
#fuses wdt    setup_wdt(WDT_2304MS);
    while(true){
        restart_wdt();
        perform_activity();
    }
```

For PIC18F452

```
#fuse WDT1
setup_wdt(WDT_ON);
while(true){
    restart_wdt();
    perform_activity();
}
```

Some of the PCB chips share the WDT prescaler bits with timer0 so the WDT prescaler constants can be used with `setup_counters` or `setup_timer0` or `setup_wdt` functions.

Stream I/O

Syntax:

#include <ios.h> is required to use any of the ios identifiers.

Ouput:

output:

```
stream << variable_or_constant_or_manipulator ;
```

one or more repeats

stream may be the name specified in the #use RS232 stream= option or for the default stream use cout.

stream may also be the name of a char array. In this case the data is written to the array with a 0 terminator.

stream may also be the name of a function that accepts a single char parameter. In this case the function is called for each character to be output.

variables/constants: May be any integer, char, float or fixed type. Char arrays are output as strings and all other types are output as an address of the variable.

Manipulators:

hex -Hex format numbers

dec- Decimal format numbers (default)

setprecision(x) -Set number of places after the decimal point

setw(x) -Set total number of characters output for numbers

boolalpha- Output int1 as true and false

noboolalpha -Output int1 as 1 and 0 (default)

fixed Floats- in decimal format (default)

scientific Floats- use E notation

iosdefault- All manipulators to default settings

endl -Output CR/LF

ends- Outputs a null ('\000')

Examples:

```
cout << "Value is " << hex << data << endl;
```

```
cout << "Price is $" << setw(4) << setprecision(2) << cost << endl;
lcdputc << '\f' << setw(3) << count << "    " << min << "    " << max;
string1 << setprecision(1) << sum / count;
string2 << x << ',' << y;
```

Input:

`stream >> variable_or_constant_or_manipulator ;`

one or more repeats

stream may be the name specified in the #use RS232 stream= option or for the default stream use cin.

stream may also be the name of a char array. In this case the data is read from the array up to the 0 terminator.

stream may also be the name of a function that returns a single char and has no parameters. In this case the function is called for each character to be input. Make sure the function returns a \r to terminate the input statement.

variables/constants: May be any integer, char, float or fixed type. Char arrays are input as strings. Floats may use the E format. Reading of each item terminates with any character not valid for the type. Usually items are separated by spaces. The termination character is discarded. At the end of any stream input statement characters are read until a return (\r) is read. No termination character is read for a single char input.

Manipulators:

hex -Hex format numbers

dec- Decimal format numbers (default)

noecho- Suppress echoing

strspace- Allow spaces to be input into strings

nostrspace- Spaces terminate string entry (default)

iosdefault -All manipulators to default settings

Examples:

```
cout << "Enter number: ";
cin >> value;
cout << "Enter title: ";
cin >> strspace >> title;
cin >> data[i].recordid >> data[i].xpos >> data[i].ypos >>
data[i].sample ;
```

```
string1 >> data;  
lcdputc << "\fEnter count";  
lcdputc << keypadgetc >> count;    // read from keypad, echo to lcd  
                                     // This syntax only works with  
                                     // user defined functions.
```

PREPROCESSOR

address

Syntax:

A predefined symbol `__address__` may be used to indicate a type that must hold a program memory address.

Examples:

```
__address__ testa = 0x1000 //will allocate 16 bits for test a
and
//initialize to 0x1000
```

attribute x

Syntax:

`__attribute__ x`

Elements:

`x` is the attribute you want to apply. Valid values for `x` are as follows: **((packed))**

By default each element in a struct or union are padded to be evenly spaced by the size of 'int'. This is to prevent an address fault when accessing an element of struct. See the following example:

```
struct
{
    int8 a;
    int16 b;
} test;
```

On architectures where 'int' is 16bit (such as dsPIC or PIC24 microcontrollers), 'test' would take 4 bytes even though it is comprised of 3 bytes. By applying the 'packed' attribute to this struct then it would take 3 bytes as originally intended:

```
struct __attribute__((packed))
{
    int8 a;
    int16 b;
} test;
```

Care should be taken by the user when accessing individual elements of a packed struct – creating a pointer to 'b' in 'test' and attempting to dereference that pointer would cause an address fault. Any attempts to read/write 'b' should be done in context of 'test' so the compiler knows it is packed:

```
test.b = 5;
```


((aligned(y)) - By default the compiler will allocate a variable in the first free memory location. The aligned attribute will force the compiler to allocate a location for the specified variable at a location that is modulus of the y parameter. For example:

```
int8 array[256] __attribute__((aligned(0x1000)));
```

This will tell the compiler to try to place 'array' at either 0x0, 0x1000, 0x2000, 0x3000, 0x4000, etc.

Description:

To alter some specifics as to how the compiler operates.

Examples:

```
struct __attribute__((packed))
{
    int8 a;
    int8 b;
} test;
int8 array[256] __attribute__((aligned(0x1000)));
```

#asm, #endasm, #asm asis

Syntax:

#ASM or #ASM ASIS code #ENDASM

Elements:

Code is a list of assembly language instructions.

Description:

12 Bit and 14 Bit	
ADDWF f,d	ANDWF f,d
CLRF f	CLRW
COMF f,d	DECF f,d
DECFSZ f,d	INCF f,d
INCFSZ f,d	IORWF f,d
MOVF f,d	MOVPHW
MOVPLW	MOVWF f
NOP	RLF f,d
RRF f,d	SUBWF f,d
SWAPF f,d	XORWF f,d
BCF f,b	BSF f,b
BTFSC f,b	BTFSS f,b

ANDLW k	CALL k
CLRWDT	GOTO k
IORLW k	MOVLW k
RETLW k	SLEEP
XORLW	OPTION
TRIS k	
	14 Bit
	ADDLW k
	SUBLW k
	RETFIE
	RETURN

f	may be a constant (file number) or a simple variable
d	may be a constant (0 or 1) or W or F
f,b	may be a file (as above) and a constant (0-7) or it may be just a bit variable reference.
k	may be a constant expression

***Note that all expressions and comments are in C like syntax.**

PIC 18					
ADDWF	f,d	ADDWFC	f,d	ANDWF	f,d
CLRF	f	COMF	f,d	CPFSEQ	f
CPFSGT	f	CPFSLT	f	DECF	f,d
DECFSZ	f,d	DCFSNZ	f,d	INCF	f,d
INFSNZ	f,d	IORWF	f,d	MOVF	f,d
MOVFF	fs,d	MOVWF	f	MULWF	f
NEGF	f	RLCF	f,d	RLNCF	f,d
RRCF	f,d	RRNCF	f,d	SETF	f
SUBFWB	f,d	SUBWF	f,d	SUBWFB	f,d
SWAPF	f,d	TSTFSZ	f	XORWF	f,d
BCF	f,b	BSF	f,b	BTFSC	f,b
BTFSS	f,b	BTG	f,d	BC	n
BN	n	BNC	n	BNN	n
BNOV	n	BNZ	n	BOV	n
BRA	n	BZ	n	CALL	n,s
CLRWDT	-	DAW	-	GOTO	n
NOP	-	NOP	-	POP	-
PUSH	-	RCALL	n	RESET	-
RETFIE	s	RETLW	k	RETURN	s

SLEEP	-	ADDLW	k	ANDLW	k
IORLW	k	LF SR	f,k	MOVLB	k
MOVLW	k	MULLW	k	RETLW	k
SUBLW	k	XORLW	k	TBLRD	*
TBLRD	*+	TBLRD	*_	TBLRD	+*
TBLWT	*	TBLWT	*+	TBLWT	*_
TBLWT	+*				

The compiler will set the access bit depending on the value of the file register.

If there is just a variable identifier in the #asm block then the compiler inserts an & before it. And if it is an expression it must be a valid C expression that evaluates to a constant (no & here). In C an un-subscripted array name is a pointer and a constant (no need for &).

[PCD]

PIC24 and dsPIC		
ADD	Wa,Wb,Wd	Wd = Wa+Wb
ADD	f,W	W0 = f+Wd
ADD	lit10,Wd	Wd = lit10+Wd
ADD	Wa,lit5,Wd	Wd = lit5+Wa
ADD	f,F	f = f+Wd
ADD	acc	Acc = AccA+AccB
ADD	Wd,{lit4},acc	Acc = Acc+(Wa shifted slit4)
ADD.B	lit10,Wd	Wd = lit10+Wd (byte)
ADD	Wd,{lit4},acc	Acc = Acc+(Wa shifted slit4)
ADD.B	lit10,Wd	Wd = lit10+Wd (byte)
ADD.B	f,F	f = f+Wd (byte)
ADD.B	Wa,Wb,Wd	Wd = Wa+Wb (byte)
ADD.B	Wa,lit5,Wd	Wd = lit5+Wa (byte)
ADD.B	f,W	W0 = f+Wd (byte)
ADDC	f,W	Wd = f+Wa+C
ADDC	lit10,Wd	Wd = lit10+Wd+C
ADDC	Wa,lit5,Wd	Wd = lit5+Wa+C
ADDC	f,F	Wd = f+Wa+C
ADDC	Wa,Wb,Wd	Wd = Wa+Wb+C
ADDC.B	lit10,Wd	Wd = lit10+Wd+C (byte)
ADDC.B	Wa,Wb,Wd	Wd = Wa+Wb+C (byte)
ADDC.B	Wa,lit5,Wd	Wd = lit5+Wa+C (byte)
ADDC.B	f,W	Wd = f+Wa+C (byte)
ADDC.B	f,F	Wd = f+Wa+C (byte)
AND	Wa,Wb,Wd	Wd = Wa.&Wb

AND	lit10,Wd	Wd = lit10.&.Wd
AND	f,W	W0 = f.&.Wa
AND	f,F	f = f.&.Wa
AND	Wa,lit5,Wd	Wd = lit5.&.Wa
AND.B	f,W	W0 = f.&.Wa (byte)
AND.B	Wa,Wb,Wd	Wd = Wa.&.Wb (byte)
AND.B	lit10,Wd	Wd = lit10.&.Wd (byte)
AND.B	f,F	f = f.&.Wa (byte)
AND.B	Wa,lit5,Wd	Wd = lit5.&.Wa (byte)
ASR	f,W	W0 = f >> 1 arithmetic
ASR	f,F	f = f >> 1 arithmetic
ASR	Wa,Wd	Wd = Wa >> 1 arithmetic
ASR	Wa,lit4,Wd	Wd = Wa >> lit4 arithmetic
ASR	Wa,Wb,Wd	Wd = Wa >> Wb arithmetic
ASR.B	f,F	f = f >> 1 arithmetic (byte)
ASR.B	f,W	W0 = f >> 1 arithmetic (byte)
ASR.B	Wa,Wd	Wd = Wa >> 1 arithmetic (byte)
BCLR	f,B	f.bit = 0
BCLR	Wd,B	Wa.bit = 0
BCLR.B	Wd,B	Wa.bit = 0 (byte)
BRA	a	Branch unconditionally
BRA	Wd	Branch PC+Wa
BRA BZ	a	Branch if Zero
BRA C	a	Branch if Carry (no borrow)
BRA GE	a	Branch if greater than or equal
BRA GEU	a	Branch if unsigned greater than or equal
BRA GT	a	Branch if greater than
BRA GTU	a	Branch if unsigned greater than
BRA LE	a	Branch if less than or equal
BRA LEU	a	Branch if unsigned less than or equal
BRA LT	a	Branch if less than
BRA LTU	a	Branch if unsigned less than
BRA N	a	Branch if negative
BRA NC	a	Branch if not carry (Borrow)
BRA NN	a	Branch if not negative
BRA NOV	a	Branch if not Overflow
BRA NZ	a	Branch if not Zero
BRA OA	a	Branch if Accumulator A overflow
BRA OB	a	Branch if Accumulator B overflow
BRA OV	a	Branch if Overflow
BRA SA	a	Branch if Accumulator A Saturate

BRA SB	a	Branch if Accumulator B Saturate
BRA Z	a	Branch if Zero
BREAK		ICD Break
BSET	Wd,B	Wa.bit = 1
BSET	f,B	f.bit = 1
BSET.B	Wd,B	Wa.bit = 1 (byte)
BSW.C	Wa,Wd	Wa.Wb = C
BSW.Z	Wa,Wd	Wa.Wb = Z
BTG	Wd,B	Wa.bit = ~Wa.bit
BTG	f,B	f.bit = ~f.bit
BTG.B	Wd,B	Wa.bit = ~Wa.bit (byte)
BTSC	f,B	Skip if f.bit = 0
BTSC	Wd,B	Skip if Wa.bit4 = 0
BTSS	f,B	Skip if f.bit = 1
BTSS	Wd,B	Skip if Wa.bit = 1
BTST	f,B	Z = f.bit
BTST.C	Wa,Wd	C = Wa.Wb
BTST.C	Wd,B	C = Wa.bit
BTST.Z	Wd,B	Z = Wa.bit
BTST.Z	Wa,Wd	Z = Wa.Wb
BTSTS	f,B	Z = f.bit; f.bit = 1
BTSTS.C	Wd,B	C = Wa.bit; Wa.bit = 1
BTSTS.Z	Wd,B	Z = Wa.bit; Wa.bit = 1
CALL	a	Call subroutine
CALL	Wd	Call [Wa]
CLR	f,F	f = 0
CLR	acc,da,dc,pi	Acc = 0; prefetch=0
CLR	f,W	W0 = 0
CLR	Wd	Wd = 0
CLR.B	f,W	W0 = 0 (byte)
CLR.B	Wd	Wd = 0 (byte)
CLR.B	f,F	f = 0 (byte)
CLRWDT		Clear WDT
COM	f,F	f = ~f
COM	f,W	W0 = ~f
COM	Wa,Wd	Wd = ~Wa
COM.B	f,W	W0 = ~f (byte)
COM.B	Wa,Wd	Wd = ~Wa (byte)
COM.B	f,F	f = ~f (byte)
CP	W,f	Status set for f - W0
CP	Wa,Wd	Status set for Wb - Wa

CP	Wd,lit5	Status set for Wa $\hat{=}$ lit5
CP.B	W,f	Status set for f - W0 (byte)
CP.B	Wa,Wd	Status set for Wb $\hat{=}$ Wa (byte)
CP.B	Wd,lit5	Status set for Wa $\hat{=}$ lit5 (byte)
CP0	Wd	Status set for Wa $\hat{=}$ 0
CP0	W,f	Status set for f $\hat{=}$ 0
CP0.B	Wd	Status set for Wa $\hat{=}$ 0 (byte)
CP0.B	W,f	Status set for f $\hat{=}$ 0 (byte)
CPB	Wd,lit5	Status set for Wa $\hat{=}$ lit5 $\hat{=}$ C
CPB	Wa,Wd	Status set for Wb $\hat{=}$ Wa $\hat{=}$ C
CPB	W,f	Status set for f $\hat{=}$ W0 - C
CPB.B	Wa,Wd	Status set for Wb $\hat{=}$ Wa $\hat{=}$ C (byte)
CPB.B	Wd,lit5	Status set for Wa $\hat{=}$ lit5 $\hat{=}$ C (byte)
CPB.B	W,f	Status set for f $\hat{=}$ W0 - C (byte)
CPSEQ	Wa,Wd	Skip if Wa = Wb
CPSEQ.B	Wa,Wd	Skip if Wa = Wb (byte)
CPSGT	Wa,Wd	Skip if Wa > Wb
CPSGT.B	Wa,Wd	Skip if Wa > Wb (byte)
CPSLT	Wa,Wd	Skip if Wa < Wb
CPSLT.B	Wa,Wd	Skip if Wa < Wb (byte)
CPSNE	Wa,Wd	Skip if Wa $\neq$ Wb
CPSNE.B	Wa,Wd	Skip if Wa $\neq$ Wb (byte)
DAW.B	Wd	Wa = decimal adjust Wa
DEC	Wa,Wd	Wd = Wa $\hat{=}$ 1
DEC	f,W	W0 = f $\hat{=}$ 1
DEC	f,F	f = f $\hat{=}$ 1
DEC.B	f,F	f = f $\hat{=}$ 1 (byte)
DEC.B	f,W	W0 = f $\hat{=}$ 1 (byte)
DEC.B	Wa,Wd	Wd = Wa $\hat{=}$ 1 (byte)
DEC2	Wa,Wd	Wd = Wa $\hat{=}$ 2
DEC2	f,W	W0 = f $\hat{=}$ 2
DEC2	f,F	f = f $\hat{=}$ 2
DEC2.B	Wa,Wd	Wd = Wa $\hat{=}$ 2 (byte)
DEC2.B	f,W	W0 = f $\hat{=}$ 2 (byte)
DEC2.B	f,F	f = f $\hat{=}$ 2 (byte)
DISI	lit14	Disable Interrupts lit14 cycles
DIV.S	Wa,Wd	Signed 16/16-bit integer divide
DIV.SD	Wa,Wd	Signed 16/16-bit integer divide (dword)
DIV.U	Wa,Wd	UnSigned 16/16-bit integer divide
DIV.UD	Wa,Wd	UnSigned 16/16-bit integer divide (dword)
DIVF	Wa,Wd	Signed 16/16-bit fractional divide

DO	lit14,a	Do block lit14 times
DO	Wd,a	Do block Wa times
ED	Wd*Wd,acc,da,db	Euclidean Distance (No Accumulate)
EDAC	Wd*Wd,acc,da,db	Euclidean Distance
EXCH	Wa,Wd	Swap Wa and Wb
FBCL	Wa,Wd	Find bit change from left (Msb) side
FEX		ICD Execute
FF1L	Wa,Wd	Find first one from left (Msb) side
FF1R	Wa,Wd	Find first one from right (Lsb) side
GOTO	a	GoTo
GOTO	Wd	GoTo [Wa]
INC	f,W	$W0 = f + 1$
INC	Wa,Wd	$Wd = Wa + 1$
INC	f,F	$f = f + 1$
INC.B	Wa,Wd	$Wd = Wa + 1$ (byte)
INC.B	f,F	$f = f + 1$ (byte)
INC.B	f,W	$W0 = f + 1$ (byte)
INC2	f,W	$W0 = f + 2$
INC2	Wa,Wd	$Wd = Wa + 2$
INC2	f,F	$f = f + 2$
INC2.B	f,W	$W0 = f + 2$ (byte)
INC2.B	f,F	$f = f + 2$ (byte)
INC2.B	Wa,Wd	$Wd = Wa + 2$ (byte)
IOR	lit10,Wd	$Wd = \text{lit10} \mid Wd$
IOR	f,F	$f = f \mid Wa$
IOR	f,W	$W0 = f \mid Wa$
IOR	Wa,lit5,Wd	$Wd = Wa. \mid .\text{lit5}$
IOR	Wa,Wb,Wd	$Wd = Wa. \mid .Wb$
IOR.B	Wa,Wb,Wd	$Wd = Wa. \mid .Wb$ (byte)
IOR.B	f,W	$W0 = f \mid Wa$ (byte)
IOR.B	lit10,Wd	$Wd = \text{lit10} \mid Wd$ (byte)
IOR.B	Wa,lit5,Wd	$Wd = Wa. \mid .\text{lit5}$ (byte)
IOR.B	f,F	$f = f \mid Wa$ (byte)
LAC	Wd,{lit4},acc	$\text{Acc} = Wa$ shifted slit4
LNK	lit14	Allocate Stack Frame
LSR	f,W	$W0 = f >> 1$
LSR	Wa,lit4,Wd	$Wd = Wa >> \text{lit4}$
LSR	Wa,Wd	$Wd = Wa >> 1$
LSR	f,F	$f = f >> 1$
LSR	Wa,Wb,Wd	$Wd = Wb >> Wa$
LSR.B	f,W	$W0 = f >> 1$ (byte)

LSR.B	f,F	$f = f \gg 1$ (byte)
LSR.B	Wa,Wd	$Wd = Wa \gg 1$ (byte)
MAC	Wd*Wd,acc,da,dc	$Acc = Acc + Wa * Wa$; {prefetch}
MAC	Wd*Wc,acc,da,dc,pi	$Acc = Acc + Wa * Wb$; {[W13] = Acc}; {prefetch}
MOV	W,f	$f = Wa$
MOV	f,W	$W0 = f$
MOV	f,F	$f = f$
MOV	Wd,?	$F = Wa$
MOV	Wa+lit,Wd	$Wd = [Wa + Slit10]$
MOV	?,Wd	$Wd = f$
MOV	lit16,Wd	$Wd = lit16$
MOV	Wa,Wd	$Wd = Wa$
MOV	Wa,Wd+lit	$[Wd + Slit10] = Wa$
MOV.B	lit8,Wd	$Wd = lit8$ (byte)
MOV.B	W,f	$f = Wa$ (byte)
MOV.B	f,W	$W0 = f$ (byte)
MOV.B	f,F	$f = f$ (byte)
MOV.B	Wa+lit,Wd	$Wd = [Wa + Slit10]$ (byte)
MOV.B	Wa,Wd+lit	$[Wd + Slit10] = Wa$ (byte)
MOV.B	Wa,Wd	$Wd = Wa$ (byte)
MOV.D	Wa,Wd	$Wd:Wd+1 = Wa:Wa+1$
MOV.D	Wa,Wd	$Wd:Wd+1 = Wa:Wa+1$
MOVSAC	acc,da,dc,pi	Move ? to ? and ? To ?
MPY	Wd*Wc,acc,da,dc	$Acc = Wa * Wb$
MPY	Wd*Wd,acc,da,dc	Square to Acc
MPY.N	Wd*Wc,acc,da,dc	$Acc = -(Wa * Wb)$
MSC	Wd*Wc,acc,da,dc,pi	$Acc = Acc \hat{+} Wa * Wb$
MUL	W,f	$W3:W2 = f * Wa$
MUL.B	W,f	$W3:W2 = f * Wa$ (byte)
MUL.SS	Wa,Wd	$\{Wd+1, Wd\} = \text{sign}(Wa) * \text{sign}(Wb)$
MUL.SU	Wa,Wd	$\{Wd+1, Wd\} = \text{sign}(Wa) * \text{unsign}(Wb)$
MUL.SU	Wa,lit5,Wd	$\{Wd+1, Wd\} = \text{sign}(Wa) * \text{unsign}(lit5)$
MUL.US	Wa,Wd	$\{Wd+1, Wd\} = \text{unsign}(Wa) * \text{sign}(Wb)$
MUL.UU	Wa,Wd	$\{Wd+1, Wd\} = \text{unsign}(Wa) * \text{unsign}(Wb)$
MUL.UU	Wa,lit5,Wd	$\{Wd+1, Wd\} = \text{unsign}(Wa) * \text{unsign}(lit5)$
NEG	f,F	$f = -f$
PUSH	Wd	Push Wa to TOS
PUSH.D	Wd	PUSH double $Wa:Wa + 1$ to TOS
PUSH.S		PUSH shadow registers
PWRSAB	lit1	Enter Power-saving mode lit1
RCALL	a	Call (relative)

RCALL	Wd	Call Wa
REPEAT	lit14	Repeat next instruction (lit14 + 1) times
REPEAT	Wd	Repeat next instruction (Wa + 1) times
RESET		Reset
RETFIE		Return from interrupt enable
RETLW	lit10,Wd	Return; Wa = lit10
RETLW.B	lit10,Wd	Return; Wa = lit10 (byte)
RETURN		Return
RLC	Wa,Wd	Wd = rotate left through Carry Wa
RLC	f,F	f = rotate left through Carry f
RLC	f,W	W0 = rotate left through Carry f
RLC.B	f,F	f = rotate left through Carry f (byte)
RLC.B	f,W	W0 = rotate left through Carry f (byte)
RLC.B	Wa,Wd	Wd = rotate left through Carry Wa (byte)
RLNC	Wa,Wd	Wd = rotate left (no Carry) Wa
RLNC	f,F	f = rotate left (no Carry) f
RLNC	f,W	W0 = rotate left (no Carry) f
RLNC.B	f,W	W0 = rotate left (no Carry) f (byte)
RLNC.B	Wa,Wd	Wd = rotate left (no Carry) Wa (byte)
RLNC.B	f,F	f = rotate left (no Carry) f (byte)
RRC	f,F	f = rotate right through Carry f
RRC	Wa,Wd	Wd = rotate right through Carry Wa
RRC	f,W	W0 = rotate right through Carry f
RRC.B	f,W	W0 = rotate right through Carry f (byte)
RRC.B	f,F	f = rotate right through Carry f (byte)
RRC.B	Wa,Wd	Wd = rotate right through Carry Wa (byte)
RRNC	f,F	f = rotate right (no Carry) f
RRNC	f,W	W0 = rotate right (no Carry) f
RRNC	Wa,Wd	Wd = rotate right (no Carry) Wa
RRNC.B	f,F	f = rotate right (no Carry) f (byte)
RRNC.B	Wa,Wd	Wd = rotate right (no Carry) Wa (byte)
RRNC.B	f,W	W0 = rotate right (no Carry) f (byte)
SAC	acc,{lit4},Wd	Wd = Acc slit 4
SAC.R	acc,{lit4},Wd	Wd = Acc slit 4 with rounding
SE	Wa,Wd	Wd = sign-extended Wa
SETM	Wd	Wd = 0xFFFF
SETM	f,F	W0 = 0xFFFF
SETM.B	Wd	Wd = 0xFFFF (byte)
SETM.B	f,W	W0 = 0xFFFF (byte)
SETM.B	f,F	W0 = 0xFFFF (byte)
SFTAC	acc,Wd	Arithmetic shift Acc by (Wa)

SFTAC	acc,lit5	Arithmetic shift Acc by Slit6
SL	f,W	$W0 = f \ll 1$
SL	Wa,Wb,Wd	$Wd = Wa \ll Wb$
SL	Wa,lit4,Wd	$Wd = Wa \ll \text{lit4}$
SL	Wa,Wd	$Wd = Wa \ll 1$
SL	f,F	$f = f \ll 1$
SL.B	f,W	$W0 = f \ll 1$ (byte)
SL.B	Wa,Wd	$Wd = Wa \ll 1$ (byte)
SL.B	f,F	$f = f \ll 1$ (byte)
SSTEP		ICD Single Step
SUB	f,F	$f = f \hat{=} W0$
SUB	f,W	$W0 = f \hat{=} W0$
SUB	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb$
SUB	Wa,lit5,Wd	$Wd = Wa \hat{=} \text{lit5}$
SUB	acc	$\text{Acc} = \text{AccA} \hat{=} \text{AccB}$
SUB	lit10,Wd	$Wd = Wd \hat{=} \text{lit10}$
SUB.B	Wa,lit5,Wd	$Wd = Wa \hat{=} \text{lit5}$ (byte)
SUB.B	lit10,Wd	$Wd = Wd \hat{=} \text{lit10}$ (byte)
SUB.B	f,W	$W0 = f \hat{=} W0$ (byte)
SUB.B	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb$ (byte)
SUB.B	f,F	$f = f \hat{=} W0$ (byte)
SUBB	f,W	$W0 = f \hat{=} W0 \hat{=} C$
SUBB	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb \hat{=} C$
SUBB	f,F	$f = f \hat{=} W0 \hat{=} C$
SUBB	Wa,lit5,Wd	$Wd = Wa \hat{=} \text{lit5} - C$
SUBB	lit10,Wd	$Wd = Wd \hat{=} \text{lit10} \hat{=} C$
SUBB.B	lit10,Wd	$Wd = Wd \hat{=} \text{lit10} \hat{=} C$ (byte)
SUBB.B	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb \hat{=} C$ (byte)
SUBB.B	f,F	$f = f \hat{=} W0 \hat{=} C$ (byte)
SUBB.B	Wa,lit5,Wd	$Wd = Wa \hat{=} \text{lit5} - C$ (byte)
SUBB.B	f,W	$W0 = f \hat{=} W0 \hat{=} C$ (byte)
SUBBR	Wa,lit5,Wd	$Wd = \text{lit5} \hat{=} Wa - C$
SUBBR	f,W	$W0 = W0 \hat{=} f \hat{=} C$
SUBBR	f,F	$f = W0 \hat{=} f \hat{=} C$
SUBBR	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb - C$
SUBBR.B	f,F	$f = W0 \hat{=} f \hat{=} C$ (byte)
SUBBR.B	f,W	$W0 = W0 \hat{=} f \hat{=} C$ (byte)
SUBBR.B	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb - C$ (byte)
SUBBR.B	Wa,lit5,Wd	$Wd = \text{lit5} \hat{=} Wa - C$ (byte)
SUBR	Wa,lit5,Wd	$Wd = \text{lit5} \hat{=} Wb$
SUBR	f,F	$f = W0 \hat{=} f$

SUBR	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb$
SUBR	f,W	$W0 = W0 \hat{=} f$
SUBR.B	Wa,Wb,Wd	$Wd = Wa \hat{=} Wb$ (byte)
SUBR.B	f,F	$f = W0 \hat{=} f$ (byte)
SUBR.B	Wa,lit5,Wd	$Wd = lit5 \hat{=} Wb$ (byte)
SUBR.B	f,W	$W0 = W0 \hat{=} f$ (byte)
SWAP	Wd	Wa = byte or nibble swap Wa
SWAP.B	Wd	Wa = byte or nibble swap Wa (byte)
TBLRDH	Wa,Wd	$Wd = ROM[Wa]$ for odd ROM
TBLRDH.B	Wa,Wd	$Wd = ROM[Wa]$ for odd ROM (byte)
TBLRDL	Wa,Wd	$Wd = ROM[Wa]$ for even ROM
TBLRDL.B	Wa,Wd	$Wd = ROM[Wa]$ for even ROM (byte)
TBLWTH	Wa,Wd	$ROM[Wa] = Wd$ for odd ROM
TBLWTH.B	Wa,Wd	$ROM[Wa] = Wd$ for odd ROM (byte)
TBLWTL	Wa,Wd	$ROM[Wa] = Wd$ for even ROM
TBLWTL.B	Wa,Wd	$ROM[Wa] = Wd$ for even ROM (byte)
ULNK		Deallocate Stack Frame
URUN		ICD Run
XOR	Wa,Wb,Wd	$Wd = Wa \wedge Wb$
XOR	f,F	$f = f \wedge W0$
XOR	f,W	$W0 = f \wedge W0$
XOR	Wa,lit5,Wd	$Wd = Wa \wedge lit5$
XOR	lit10,Wd	$Wd = Wd \wedge lit10$
XOR.B	lit10,Wd	$Wd = Wd \wedge lit10$ (byte)
XOR.B	f,W	$W0 = f \wedge W0$ (byte)
XOR.B	Wa,lit5,Wd	$Wd = Wa \wedge lit5$ (byte)
XOR.B	Wa,Wb,Wd	$Wd = Wa \wedge Wb$ (byte)
XOR.B	f,F	$f = f \wedge W0$ (byte)
ZE	Wa,Wd	$Wd = Wa \& FF$

Example Files: FFT.c

Examples:

```
int find_parity(int data){

    int count;
    #asm
    MOV #0x08, W0
    MOV W0, count
    CLR W0
```

```

loop:
XOR.B data,W0
RRC data,W0
DEC count,F
BRA NZ, loop
MOV #0x01,W0
ADD count,F
MOV count, W0
MOV W0, _RETURN_
#endasm
}

```

#bank_dma

Syntax:

#bank_dma

Elements:

None

Description:

Informs the compiler to assign the data for the next variable, array or structure into DMA bank.

Examples:

```

#bank_dma
struct {
int r_w;
int c_w;
long unused :2;
long data: 4;
}a_port;           //the data for a_port will be forced into memory
bank DMA

```

#bankx

Syntax:

#bankx

None

Description:

Informs the compiler to assign the data for the next variable, array or structure into BankX.

Examples:

```
#bankx
struct {
    int r_w;
    int c_d;
    long unused : 2;
    long data : 4;
} a_port;

// The data for a_port will be forced into memory bank
x
```

#banky**Syntax:**

```
#banky
```

None

Description:

Informs the compiler to assign the data for the next variable, array or structure into BankY.

Examples:

```
#banky
struct {
    int r_w;
    int c_d;
    long unused : 2;
    long data : 4;
} a_port;

// The data for a_port will be forced into memory bank
y
```

#bit**Syntax:**

```
#BIT id = x.y
```

Elements:

id is a valid C identifier,

x is a constant or a C variable,

y is a constant 0-7 (for 8-bit PICs)

[PCD] *y* is a constant 0-15

Description:

A new C variable (one bit) is created and is placed in memory at byte x and bit y. This is useful to gain access in C directly to a bit in the processors special function register map. It may also be used to easily access a bit of a standard C variable.

Example Files:

ex_glint.c

Examples:

```
#bit T0IF = 0x b.2
...
T1IF = 0; // Clear Timer 0 interrupt flag

int result;
#bit result_odd = result.0
...
if (result_odd)
```

[PCD]

```
#bit T1IF = 0x84.3
...
T1IF = 0; // Clear Timer 0 interrupt flag

int result;
#bit result_odd = result.0
...
if (result_odd)
```

See Also:

#BYTE, #RESERVE, #LOCATE, #WORD

buildcount

Description:

Only defined if Options>Project Options>Global Defines has global defines enabled.

This id resolves to a number representing the number of successful builds of the project.

#build

Syntax:

```
#BUILD(segment = address)
#BUILD(segment = address, segment = address)
#BUILD(segment = start:end)
#BUILD(segment = start: end, segment = start: end)
#BUILD(nosleep)
[PCD] #BUILD(segment = size) : For STACK use only
```

[PCD] #BUILD(ALT_INTERRUPT)

[PCD] #BUILD(AUX_MEMORY)

Elements:

segment - is one of the following memory segments which may be assigned a location: MEMORY, RESET, or INTERRUPT.

[PCD] **segment** - is one of the following memory segments which may be assigned a location: RESET, INTERRUPT, or STACK.

address - is a ROM location memory address. **Start** and **end** are used to specify a range in memory to be used.

start - is the first ROM location and **end** is the last ROM location to be used.

[PCD] **address** - is a ROM location memory address. Start and end are used to specify a range in memory to be used. Start is the first ROM location and end is the last ROM location to be used.

[PCD] **RESET** - will move the compiler's reset vector to the specified location. **INTERRUPT** will move the compiler's interrupt service routine to the specified location. This just changes the location the compiler puts its reset and ISR, it doesn't change the actual vector of the PIC. If you specify a range that is larger than actually needed, the extra space will not be used and prevented from use by the compiler.

[PCD] **STACK** - configures the range (start and end locations) used for the stack, if not specified the compiler uses the last 256 bytes. The STACK can be specified by only using the size parameters. In this case, the compiler uses the last RAM locations on the chip and builds the stack below it.

[PCD] **ALT_INTERRUPT** - will move the compiler's interrupt service routine to the alternate location, and configure the PIC to use the alternate location.

nosleep - is used to prevent the compiler from inserting a sleep at the end of main()

Bootload - produces a bootloader-friendly hex file (in order, full block size).

NOSLEEP_LOCK - is used instead of A sleep at the end of a main A infinite loop.

[PCD] **AUX_MEMORY** - Only available on devices with an auxiliary memory segment. Causes compiler to build code for the auxiliary memory segment, including the auxiliary reset and interrupt vectors. Also enables the keyword **INT_AUX** which is used to create the auxiliary interrupt service routine.

Description:

PIC18XXX devices with external ROM or PIC18XXX devices with no internal ROM can direct the compiler to utilize the ROM. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

[PCD] These directives are commonly used in bootloaders, where the reset and interrupt needs to be moved to make space for the bootloading application.

Example Files:

ex_glint.c

Examples:

```
#build(memory=0x20000:0x2FFFF)           //Assigns memory
space
#build(reset=0x200,interrupt=0x208)        //Assigns start
location                                  //of reset and
                                         //vectors
interrupt
#build(reset=0x200:0x207, interrupt=0x208:0x2ff) //Assign limited
space                                    //for reset and
                                         //vectors.
interrupt                                //Assigns memory space
#build(memory=0x20000:0x2FFFF)
```

[PCD]

```
/* assign the location where the compiler will place the reset
and interrupt vectors */
#build(reset=0x200,interrupt=0x208)

/* assign the location and fix the size of the segments
used by the compiler for the reset and interrupt vectors */
#build(reset=0x200:0x207, interrupt=0x208:0x2ff)

/* assign stack space of 512 bytes */
#build(stack=0x1E00:0x1FFF)

#build(stack= 0x300)                      // When Start and End
locations are                             //not specified, the
                                         //the last RAM locations
compiler uses                             //on the chip.
available
```

See Also:

#LOCATE, #RESERVE, #ROM, #ORG

#byte

Syntax:

#byte *id* = *x*

Elements:

id is a valid C identifier,

x is a C variable or a constant

Description:

If the *id* is already known as a C variable then this will locate the variable at address *x*. In this case the variable type does not change from the original definition. If the *id* is not known a new C variable is created and placed at address *x* with the type int (8 bit)

Warning: In both cases memory at *x* is not exclusive to this variable. Other variables may be located at the same location. In fact when *x* is a variable, then *id* and *x* share the same memory location.

Example Files:

ex_glint.c

Examples:

```
#byte status = 3
#byte b_port = 6

struct {
    short int r_w;
    short int c_d;
    int unused : 2;
    int data : 4; } a_port;
#byte a_port = 5
...
a_port.c_d = 1;
```

[PCD]

```
#byte status_register = 0x42
#byte b_port = 0x02C8

struct {
    short int r_w;
    short int c_d;
    int data : 6 ; } E_port;
#byte a_port = 0x2DA
...
a_port.c_d = 1;
```

See Also:

[#bit](#), [#locate](#), [#reserve](#), [#word](#), [Named Registers](#), [Type Specifiers](#), [Type Qualifiers](#), [Enumerated Types](#), [Structures & Unions](#), [Typedef](#)

#case**Syntax:**

#case

Elements:

None

Description:

Will cause the compiler to be case sensitive. By default the compiler is case insensitive. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

Warning: Not all the CCS example programs, headers and drivers have been tested with case sensitivity turned on.

Example Files:

[ex_cust.c](#)

Examples:

```
#case

int STATUS;

void func() {
int status;
...
STATUS = status; // Copy local status to
                //global
}
```

date**Syntax:**

__date__

Elements:

None

Description:

This pre-processor identifier is replaced at compile time with the date of the compile in the form: "31-jan-03".

Example Files:

ex_glint.c

Examples:

```
printf("Software was compiled on ");  
printf(__DATE__)
```

#define**Syntax:**

#define *id* text

or

#define *id*(*x,y...*) text

Elements:

id is a preprocessor identifier, text is any text, *x,y* is a list of local preprocessor identifiers, and in this form there may be one or more identifiers separated by commas.

Description:

Used to provide a simple string replacement of the ID with the given text from this point of the program and on.

In the second form (a C macro) the local identifiers are matched up with similar identifiers in the text and they are replaced with text passed to the macro where it is used.

If the text contains a string of the form #*idx* then the result upon evaluation will be the parameter *id* concatenated with the string *x*.

If the text contains a string of the form #*idx*#*idy* then parameter *idx* is concatenated with parameter *idy* forming a new identifier.

Within the define text two special operators are supported:

#*x* is the stringize operator resulting in "*x*"

x##y is the concatenation operator resulting in *xy*

The varadic macro syntax is supported where the last parameter is specified as ... and the local identifier used is __va_args__. In this case, all remaining arguments are combined with the commas.

Example Files:ex stwt.c, ex macro.c**Examples:**

```

#define BITS 8
a=a+BITS;                                //same as    a=a+8;

#define hi(x)  (x<<4)
a=hi(a);                                //same as    a=(a<<4);

#define isequal(a,b)  (primary_##a[b]==backup_##a[b])
                        // usage isequal(names,5)  is the
same as
                        //
(primary_names[5]==backup_names[5])

#define str(s)  #s
#define part(device)  #include str(device##.h)
                        // usage part(16F887) is the same as
                        // #include "16F887.h"

#define DBG(...)  fprintf(debug, __VA_ARGS__)

```

See Also:#UNDEF, #IFDEF, #IFDEF**#definedinc****Syntax:**value = definedinc(*variable*);**Parameters:****variable** - is the name of the variable, function, or type to be checked.**Returns:**A C status for the type of *id* entered as follows:

- 0 – not known
- 1 – typedef or enum
- 2 – struct or union type
- 3 – typemod qualifier
- 4 – defined function
- 5 – function prototype
- 6 – compiler built-in function
- 7 – local variable
- 8 – global variable

Function:

This function checks the type of the variable or function being passed in and returns a specific C status based on the type.

Availability:

All Device

Examples:

```
int x, y = 0;
y = definedinc( x );      // y will return 7 - x is a local variable
```

#device**Syntax:**

#DEVICE *chip options*

#DEVICE *Compilation mode selection*

Elements:***Chip Options:***

chip is the name of a specific processor (like: PIC16C74 or dsPIC33FJ64GP306), To get a current list of supported devices: START | RUN | CCSC +Q

Options are qualifiers to the standard operation of the device. Valid options are:

*=5	Use 5 bit pointers (for all parts)
*=8	Use 8 bit pointers (14 and 16 bit parts)
*=16	Use 16 bit pointers (for 14 bit parts)
ADC=x	Where x is the number of bits read_adc() should return
[PCD] ADC=SIGNED	Result returned from read_adc() is signed.(Default is unsigned)
[PCD] ADC=UNSIGNED	Return result from read_adc() is unsigned.(default is UNSIGNED)
ICD=TRUE	Generates code compatible with Microchips ICD debugging hardware.
ICD=n	For chips with multiple ICSP ports specify the port number being used. The default is 1.
WRITE_EEPROM=ASYNC	Prevents WRITE_EEPROM from hanging while writing is taking place. When used, do not write to EEPROM from both ISR and outside ISR.
WRITE_EEPROM = NOINT	Allows interrupts to occur while the write_eeprom() operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.
HIGH_INTS=TRUE	Use this option for high/low priority interrupts on the PIC® 18.
%f=.	No 0 before a decimal pint on %f numbers less than 1.
OVERLOAD=KEYWORD	Overloading of functions is now supported. Requires the

	use of the keyword for overloading.
OVERLOAD=AUTO	Default mode for overloading.
PASS_STRINGS=IN_RAM	A new way to pass constant strings to a function by first copying the string to RAM and then passing a pointer to RAM to the function.
CONST=READ_ONLY	Uses the ANSI keyword CONST definition, making CONST variables read only, rather than located in program memory.
CONST=ROM	Uses the CCS compiler traditional keyword CONST definition, making CONST variables located in program memory.
NESTED_INTERRUPTS=TRUE	Enables interrupt nesting for PIC24, dsPIC30, and dsPIC33 devices. Allows higher priority interrupts to interrupt lower priority interrupts.
NORETFIE	ISR functions (preceded by a #int_xxx) will use a RETURN opcode instead of the RETFIE opcode. This is not a commonly used option; used rarely in cases where the user is writing their own ISR handler.
NO_DIGITAL_INIT	Normally the compiler sets all I/O pins to digital and turns off the comparator. This option prevents that action.
VECTOR_INTS	For devices with both single and multiple vector interrupts. This selects multiple vectors.
[PCD] DUAL_PARTITION	For devices with Dual Partition Flash Modes, this enables Dual Partition Flash mode by setting the FBOOT configuration register to the appropriate value. It cuts the available program memory in half, and moves the configuration register addresses to the Dual Partition locations.
[PCD] DUAL_PARTITION_PROTECTED	For devices with Dual Partition Flash Modes this enabled Protected Dual Partition Flash mode, Partition 1 is write-protected when inactive, by setting the FBOOT configuration register to the appropriate value. It cuts the available program memory in half and moves the configuration register addresses to the Dual Partition locations.
[PCD] PARTITION_SEQUENCE=x	A value from 0 to 4095 to set the FBTSEQ configuration register. Only used when either DUAL_PARTITION or DUAL_PARTITION_PROTECTED is used. The value is used to determine which partition is active on power-up. The Partition with the lowest value will be the active partition. If the value is the same for both partitions, then Partition 1 will be the active partition on power-up.

Both chip and options are optional, so multiple #DEVICE lines may be used to fully define the device. Be warned that a #DEVICE with a chip identifier, will clear all previous #DEVICE and #FUSE settings.

Compilation mode selection:

The #DEVICE directive supports compilation mode selection. The valid keywords are CCS2, CCS3, CCS4 and ANSI. The default mode is CCS4. For the CCS4 and ANSI mode, the compiler uses the default fuse settings NOLVP, PUT for chips with these fuses. The NOWDT fuse is default if no call is made to restart_wdt().

CCS4	This is the default compilation mode. The pointer size in this mode for PCM and PCH is set to *=16 if the part has RAM over 0FF.
ANSI	Default data type is SIGNED all other modes default is UNSIGNED. Compilation is case sensitive, all other modes are case insensitive. Pointer size is set to *=16 if the part has RAM over 0FF.
CCS2 CCS3	var16 = NegConst8 is compiled as: var16 = NegConst8 & 0xff (no sign extension) Pointer size is set to *=8 for PCM and PCH and *=5 for PCB . The overload keyword is required.
CCS2 only	The default #DEVICE ADC is set to the resolution of the part, all other modes default to 8. onebit = eightbits is compiled as onebit = (eightbits != 0) All other modes compile as: onebit = (eightbits & 1)

Description:

To alter some specifics as to how the compiler operates

Example Files:

ex_mxram.c , ex_icd.c , 16c74.h

Examples:

Chip Options:

```
#device PIC16C74
#device PIC16C67 *=16
#device *=16 ICD=TRUE
#device PIC16F877 *=16 ADC=10
#device %f=.
printf("%f",.5); //will print .5, without the directive it will print 0.5
[PCD] #device DSPIC33FJ64GP306
[PCD] #device PIC24FJ64GA002 ICD=TRUE
[PCD] #device ADC=10
[PCD] #device ICD=TRUE ADC=10
```

[PCD] Float Options-

```
[PCD] #device %f=.
[PCD] printf("%f",.5); //will print .5, without the directive it will print 0.5
```

Compilation mode selection:

```
#device CCS2 // This will set the ADC to the resolution of the part
```

See Also:

read_adc()

device**Syntax:**

__device__

Elements:

None

Description:

This preprocessor identifier is defined by the compiler with the base number of the current device (from a #DEVICE). The base number is usually the number after the C in the part number. For example, the PIC16C622 has a base number of 622.

Examples:

```
#if __device__ == 71
    SETUP_ADC_PORTS (All_DIGITAL) ;
#endif
```

See Also:

#DEVICE

#if #else #elif #endif**Syntax:**

```
#if expr
    code
#elif expr //Optional, any number may be used
    code
#else //Optional
    code
#endif
```

Elements:

expr is an expression with constants, standard operators and/or preprocessor identifiers. **Code** is any standard c source code.

Description:

The pre-processor evaluates the constant expression and if it is non-zero will process the lines up to the optional **#ELSE** or the **#ENDIF**.

Note: you may NOT use C variables in the **#IF**. Only preprocessor identifiers created via **#define** can be used.

The preprocessor expression **DEFINED(id)** may be used to return 1 if the id is defined and 0 if it is not.

== and **!=** operators now accept a constant string as both operands. This allows for compile time comparisons and can be used with **GETENV()** when it returns a string result.

Example Files:

ex_extee.c

Examples:

```
#if MAX_VALUE > 255
    long value;
#else
    int value;
#endif
#if getenv("DEVICE")== "PIC16F877"
    //do something special for the PIC16F877
#endif
```

See Also:

#IFDEF, **#IFNDEF**, **getenv()**

#error**Syntax:**

#ERROR *text*

#ERROR / warning *text*

#ERROR / information *text*

Elements:

text - is optional and may be any text

Description:

Forces the compiler to generate an error at the location this directive appears in the file. The text may include macros that will be expanded for the display. This may be used to see the macro expansion. The command may also be used to alert the user to an invalid compile time situation.

Example Files:

ex_psp.

Examples:

```
#if BUFFER_SIZE>16
#error Buffer size is too large
#endif
#error Macro test: min(x,y)
```

See Also:**#WARNING****#export (options)****Syntax:**

#export(options)

Elements:

FILE=filename - The filename which will be generated upon compile. If not given, the filename will be the name of the file you are compiling, with a .o or .hex extension (depending on output format).

Output Formats:

C - Indicates the file format is C source code. In this case the object is not exported but rather a definition that allows another C program in the same memory space to call the exported functions. It may be used by a bootloader that needs the loaded application to call bootloader functions.

RELOCATABLE - CCS relocatable object file format. Must be imported or linked before loading into a PIC. This is the default format when the #EXPORT is used.

HEX - Intel HEX file format. Ready to be loaded into a PIC. This is the default format when no #EXPORT is used.

Exported Symbols:

ONLY=symbol+symbol+.....+symbol - Only the listed symbols will be visible to modules that import or link this relocatable object file. If neither ONLY or EXCEPT is used, all symbols are exported.

EXCEPT=symbol+symbol+.....+symbol - All symbols except the listed symbols will be visible to modules that import or link this relocatable object file. If neither ONLY or EXCEPT is used, all symbols are exported.

Exported Addresses:

RANGE=start:stop - Only addresses in this range are included in the hex file.

OFFSET=address - Hex file address starts at this address (0 by default)

ODD - Only odd bytes place in hex file.

EVEN - Only even bytes placed in hex file.

Description:

This directive will tell the compiler to either generate a relocatable object file or a stand-alone HEX binary. A relocatable object file must be linked into your application, while a stand-alone HEX binary can be programmed directly into the device. The command line compiler and the PCW IDE Project Manager can also be used to compile/link/build modules and/or projects. Multiple #EXPORT directives may be used to generate multiple hex files. This may be used for 18F8722 like devices with external memory.

Examples:

```
#EXPORT(RELOCATABLE, ONLY=TimerTask)
void TimerFunc1(void) { /* some code */ }
void TimerFunc2(void) { /* some code */ }
void TimerFunc3(void) { /* some code */ }
void TimerTask(void)
{
    TimerFunc1();
    TimerFunc2();
    TimerFunc3();
}
/*
This source will be compiled into a relocatable object, but the object
this is being linked to can only see TimerTask()
*/
```

See Also:

#IMPORT, #MODULE, Invoking the Command Line Compiler, Multiple Compilation Unit

file**Syntax:**

__file__

Elements:

None

Description:

The pre-processor identifier is replaced at compile time with the file path and the filename of the file being compiled.

Example Files:

assert.h

Examples:

```
if(index>MAX_ENTRIES)
    printf("Too many entries, source file: "
        __FILE__ " at line " __LINE__ "\r\n");
```

See Also:

line

filename**Syntax:**

__filename__

Elements:

None

Description:

The pre-processor identifier is replaced at compile time with the file path and the filename of the file being compiled.

Examples:

```
if(index>MAX_ENTRIES)
    printf("Too many entries, source file: "
        __FILENAME__ " at line " __LINE__ "\r\n");
```

See Also:

line

#fill_rom**Syntax:**

#fill_rom *value*

Elements:

value - is a constant 16-bit value

Description:

This directive specifies the data to be used to fill unused ROM locations. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

Example Files:

ex_glint.c

Examples:

```
#fill_rom 0x36
```

See Also:

#ROM

#fuses**Syntax:**

#fuses *options*

Elements:

options vary depending on the device. A list of all valid options has been put at the top of each devices .h file in a comment for reference. The PCW device edit utility can modify a particular devices fuses. The PCW pull down menu VIEW | Valid fuses will show all fuses with their descriptions. Some common options are:

- LP, XT, HS, RC
- WDT, NOWDT
- PROTECT, NOPROTECT
- PUT, NOPUT (Power Up Timer)
- BROWNOUT, NOBROWNOUT

Description:

This directive defines what fuses should be set in the part when it is programmed. This directive does not affect the compilation; however, the information is put in the output files. If the fuses need to be in Parallax format, add a PAR option. SWAP has the special function of swapping (from the Microchip standard) the high and low BYTES of non-program data in the Hex file. This is required for some device programmers.

Some fuses are set by the compiler based on other compiler directives. For example, the oscillator fuses are set up by the #USE delay directive. The debug, No debug and ICSPN Fuses are set by the #DEVICE ICD=directive.

Some processors allow different levels for certain fuses. To access these levels, assign a value to the fuse. For example, on the 18F452, the fuse PROTECT=6 would place the value 6 into CONFIG5L, protecting code blocks 0 and 3.

When linking multiple compilation units be aware this directive applies to the final object file. Later files in the import list may reverse settings in previous files.

To eliminate all fuses in the output files use: **#FUSES none**

To manually set the fuses in the output files use: **#FUSES 1 = 0xC200 // sets config word 1 to 0xC200**

Example Files:

ex_sqw.c

Examples:

```
#fuses HS, NOWDT
```

#hexcomment

Syntax:

#HEXCOMMENT text comment for the top of the hex file

#HEXCOMMENT\ text comment for the end of the hex file

Elements:

None

Description:

Puts a comment in the hex file.

Some programmers (MPLAB in particular) do not like comments at the top of the hex file.

Examples:

```
#hexcommentVersion3.1 - requires 20Mhz crystal
```

#id

Syntax:

#ID *number 16*

 #ID *number 32*

#ID *number, number, number, number*

#ID *"filename"*

#ID *CHECKSUM*

Elements:

Number 16 is a 16 bit number, *number* is a 4 bit number. `[PCD]` Number 3 2 is a 32 bit number, *number* is a 8 bit number. Filename is any valid PC filename and *checksum* is a keyword.

Description:

This directive defines the ID word to be programmed into the part. This directive does not affect the compilation but the information is put in the output file.

The first syntax will take a 16 (`[PCD]` 32)-bit number and put one nibble (`[PCD]` byte) in each of the four ID words (`[PCD]` bytes) in the traditional manner. The second syntax specifies the exact value to be used in each of the four ID words (`[PCD]` bytes).

When a filename is specified the ID is read from the file. The format must be simple text with a CR/LF at the end. The keyword CHECKSUM indicates the device checksum should be saved as the ID.

Example Files:

ex_cust.c

Examples:

```
#id 0x1234
#id "serial.num"
#id CHECKSUM

([PCD])
#id 0x12345678
#id 0x12, 0x34, 0x45, 0x67
#id "serial.num"
#id CHECKSUM
```

#ifdef #ifndef #else #endif**Syntax:**

```
#ifdef id
  code
#elif
  code
#else //optional
  code
#endif
```

```
#ifndef id
  code
#elif
  code
```

```
#else //optional
    code
#endif
```

Elements:

id is a preprocessor identifier, code is valid C source code.

Description:

This directive acts much like the #IF except that the preprocessor simply checks to see if the specified ID is known to the preprocessor (created with a #DEFINE). #IFDEF checks to see if defined and #IFNDEF checks to see if it is not defined.

Example Files:

ex_sqw.c

Examples:

```
#define debug        // Comment line out for no debug
...
#ifdef DEBUG
printf("debug point a");
#endif
```

See Also:

#IF

#ignore_warnings**Syntax:**

```
#ignore_warnings ALL
#IGNORE_WARNINGS NONE
#IGNORE_WARNINGS warnings
```

Elements:

warnings is one or more warning numbers separated by commas.

Description:

This function will suppress warning messages from the compiler. ALL indicates no warning will be generated. NONE indicates all warnings will be generated. If numbers are listed then those warnings are suppressed

Example Files:

ex_glint.c

Examples:

```
#ignore_warnings 203
while(TRUE) {
#ignore_warnings NONE
```

See Also:

Warning messages

#import(options)**Syntax:**

```
#import(options)
```

Elements:

FILE=filename - The filename of the object you want to link with this compilation.

ONLY=symbol+symbol+.....+symbol - Only the listed symbols will imported from the specified relocatable object file. If neither ONLY or EXCEPT is used, all symbols are imported.

EXCEPT=symbol+symbol+.....+symbol - The listed symbols will not be imported from the specified relocatable object file. If neither ONLY or EXCEPT is used, all symbols are imported.

RELOCATABLE - CCS relocatable object file format. This is the default format when the #IMPORT is used.

COFF - COFF file format from MPASM, C18 or C30.

HEX - Imported data is straight hex data.

RANGE=start:stop - Only addresses in this range are read from the hex file.

LOCATION=id - The identifier is made a constant with the start address of the imported data.

SIZE=id - The identifier is made a constant with the size of the imported data.

Description:

This directive will tell the compiler to include (link) a relocatable object with this unit during compilation. Normally all global symbols from the specified file will be linked, but the EXCEPT and ONLY options can prevent certain symbols from being linked. The command line compiler and the PCW IDE Project Manager can also be used to compile/link/build modules and/or projects.

Example Files:ex_glint.c**Examples:**

```
#IMPORT(FILE=timer.o, ONLY=TimerTask)
void main(void)
{
    while(TRUE)
        TimerTask();
}
/*timer.o is linked with this compilation, but only TimerTask() is
visible
in scope from this object.*/
```

See Also:#EXPORT, #MODULE, Invoking the Command Line Compiler, Multiple Compilation Unit**#include****Syntax:**

```
#include <filename>
#include <"filename">
```

Elements:

filename - is a valid PC filename. It may include normal drive and path information. A file with the extension ".encrypted" is a valid PC file. The standard compiler **#include** directive will accept files with this extension and decrypt them as they are read. This allows include files to be distributed without releasing the source code.

Description:

Text from the specified file is used at this point of the compilation. If a full path is not specified the compiler will use the list of directories specified for the project to search for the file. If the filename is in "" then the directory with the main source file is searched first. If the filename is in <> then the directory with the main source file is searched last.

Example Files:ex_sqw.c**Examples:**

```
#include <16C54.H>

#include <C:\INCLUDES\COMLIB\MYRS232.C>
```

#inline

Syntax:

#inline

Elements:

None

Description:

Tells the compiler that the function immediately following the directive is to be implemented INLINE. This will cause a duplicate copy of the code to be placed everywhere the function is called. This is useful to save stack space and to increase speed. Without this directive the compiler will decide when it is best to make procedures INLINE.

Example Files:

ex_cust.c

Examples:

```
#inline
swapbyte(int &a, int &b){
    int t;
    t=a;
    a=b;
    b=t;
}
```

See Also:

#SEPARATE

#int xxxx

Syntax:

PCB, PCM, PCH

#INT_AD	Analog to digital conversion complete
#INT_ADOF	Analog to digital conversion timeout
#INT_BUSCOL	Bus collision
#INT_BUSCOL2	Bus collision 2 detected
#INT_BUTTON	Pushbutton
#INT_CANERR	An error has occurred in the CAN module
#INT_CANIRX	An invalid message has occurred on the CAN bus
#INT_CANRX0	CAN Receive buffer 0 has received a new message

#INT_CANRX1	CAN Receive buffer 1 has received a new message
#INT_CANTX0	CAN Transmit buffer 0 has completed transmission
#INT_CANTX1	CAN Transmit buffer 0 has completed transmission
#INT_CANTX2	CAN Transmit buffer 0 has completed transmission
#INT_CANWAKE	Bus Activity wake-up has occurred on the CAN bus
#INT_CCP1	Capture or Compare on unit 1
#INT_CCP2	Capture or Compare on unit 2
#INT_CCP3	Capture or Compare on unit 3
#INT_CCP4	Capture or Compare on unit 4
#INT_CCP5	Capture or Compare on unit 5
#INT_COMP	Comparator detect
#INT_COMP0	Comparator 0 detect
#INT_COMP1	Comparator 1 detect
#INT_COMP2	Comparator 2 detect
#INT_CR	Cryptographic activity complete
#INT_EEPROM	Write complete
#INT_ETH	Ethernet module interrupt
#INT_EXT	External interrupt
#INT_EXT1	External interrupt #1
#INT_EXT2	External interrupt #2
#INT_EXT3	External interrupt #3
#INT_I2C	I2C interrupt (only on 14000)
#INT_IC1	Input Capture #1
#INT_IC2QEI	Input Capture 2 / QEI Interrupt
#IC3DR	Input Capture 3 / Direction Change Interrupt
#INT_LCD	LCD activity
#INT_LOWVOLT	Low voltage detected
#INT_LVD	Low voltage detected
#INT_OSC_FAIL	System oscillator failed
#INT_OSCF	System oscillator failed

#INT_PMP	Parallel Master Port interrupt
#INT_PSP	Parallel Slave Port data in
#INT_PWMTB	PWM Time Base
#INT_RA	Port A any change on A0_A5
#INT_RB	Port B any change on B4-B7
#INT_RC	Port C any change on C4-C7
#INT_RDA	RS232 receive data available
#INT_RDA0	RS232 receive data available in buffer 0
#INT_RDA1	RS232 receive data available in buffer 1
#INT_RDA2	RS232 receive data available in buffer 2
#INT_RTCC	Timer 0 (RTCC) overflow
#INT_SPP	Streaming Parallel Port Read/Write
#INT_SSP	SPI or I2C activity
#INT_SSP2	SPI or I2C activity for Port 2
#INT_TBE	RS232 transmit buffer empty
#INT_TBE0	RS232 transmit buffer 0 empty
#INT_TBE1	RS232 transmit buffer 1 empty
#INT_TBE2	RS232 transmit buffer 2 empty
#INT_TIMER0	Timer 0 (RTCC) overflow
#INT_TIMER1	Timer 1 overflow
#INT_TIMER2	Timer 2 overflow
#INT_TIMER3	Timer 3 overflow
#INT_TIMER4	Timer 4 overflow
#INT_TIMER5	Timer 5 overflow
#INT_ULPWU	Ultra-low power wake up interrupt
#INT_USB	Universal Serial Bus activity

Note many more #INT_ options are available on specific devices.
Check the devices .h file for a full list for a given device.

[PCD] PCD (PIC24/dsPIC devices)

#INT_AC1	Analog comparator 1 output change
#INT_AC2	Analog comparator 2 output change

#INT_AC3	Analog comparator 3 output change
#INT_AC4	Analog comparator 4 output change
#INT_ADC1	ADC1 conversion complete
#INT_ADC2	Analog to digital conversion complete
#INT_ADCP0	ADC pair 0 conversion complete
#INT_ADCP1	ADC pair 1 conversion complete
#INT_ADCP2	ADC pair 2 conversion complete
#INT_ADCP3	ADC pair 3 conversion complete
#INT_ADCP4	ADC pair 4 conversion complete
#INT_ADCP5	ADC pair 5 conversion complete
#INT_ADDRERR	Address error trap
#INT_C1RX	ECAN1 Receive Data Ready
#INT_C1TX	ECAN1 Transmit Data Request
#INT_C2RX	ECAN2 Receive Data Ready
#INT_C2TX	ECAN2 Transmit Data Request
#INT_CAN1	CAN 1 Combined Interrupt Request
#INT_CAN2	CAN 2 Combined Interrupt Request
#INT_CNI	Input change notification interrupt
#INT_COMP	Comparator event
#INT_CRC	Cyclic redundancy check generator
#INT_DCI	DCI transfer done
#INT_DCIE	DCE error
#INT_DMA0	DMA channel 0 transfer complete
#INT_DMA1	DMA channel 1 transfer complete
#INT_DMA2	DMA channel 2 transfer complete
#INT_DMA3	DMA channel 3 transfer complete
#INT_DMA4	DMA channel 4 transfer complete
#INT_DMA5	DMA channel 5 transfer complete
#INT_DMA6	DMA channel 6 transfer complete
#INT_DMA7	DMA channel 7 transfer complete
#INT_DMAERR	DMAC error trap
#INT_EEPROM	Write complete
#INT_EX1	External Interrupt 1
#INT_EX4	External Interrupt 4
#INT_EXT0	External Interrupt 0
#INT_EXT1	External interrupt #1
#INT_EXT2	External interrupt #2

#INT_EXT3	External interrupt #3
#INT_EXT4	External interrupt #4
#INT_FAULTA	PWM Fault A
#INT_FAULTA2	PWM Fault A 2
#INT_FAULTB	PWM Fault B
#INT_IC1	Input Capture #1
#INT_IC2	Input Capture #2
#INT_IC3	Input Capture #3
#INT_IC4	Input Capture #4
#INT_IC5	Input Capture #5
#INT_IC6	Input Capture #6
#INT_IC7	Input Capture #7
#INT_IC8	Input Capture #8
#INT_LOWVOLT	Low voltage detected
#INT_LVD	Low voltage detected
#INT_MATHERR	Arithmetic error trap
#INT_MI2C	Master I2C activity
#INT_MI2C2	Master2 I2C activity
#INT_OC1	Output Compare #1
#INT_OC2	Output Compare #2
#INT_OC3	Output Compare #3
#INT_OC4	Output Compare #4
#INT_OC5	Output Compare #5
#INT_OC6	Output Compare #6
#INT_OC7	Output Compare #7
#INT_OC8	Output Compare #8
#INT_OSC_FAIL	System oscillator failed
#INT_PMP	Parallel master port
#INT_PMP2	Parallel master port 2
#INT_PWM1	PWM generator 1 time based interrupt
#INT_PWM2	PWM generator 2 time based interrupt
#INT_PWM3	PWM generator 3 time based interrupt
#INT_PWM4	PWM generator 4 time based interrupt
#INT_PWMSEM	PWM special event trigger
#INT_QEI	QEI position counter compare
#INT_RDA	RS232 receive data available
#INT_RDA2	RS232 receive data available in buffer 2

#INT_RTC	Real - Time Clock/Calendar
#INT_SI2C	Slave I2C activity
#INT_SI2C2	Slave2 I2C activity
#INT_SPI1	SPI1 Transfer Done
#INT_SPI1E	SPI1E Transfer Done
#INT_SPI2	SPI2 Transfer Done
#INT_SPI2E	SPI2 Error
#INT_SPIE	SPI Error
#INT_STACKERR	Stack Error
#INT_TBE	RS232 transmit buffer empty
#INT_TBE2	RS232 transmit buffer 2 empty
#INT_TIMER1	Timer 1 overflow
#INT_TIMER2	Timer 2 overflow
#INT_TIMER3	Timer 3 overflow
#INT_TIMER4	Timer 4 overflow
#INT_TIMER5	Timer 5 overflow
#INT_TIMER6	Timer 6 overflow
#INT_TIMER7	Timer 7 overflow
#INT_TIMER8	Timer 8 overflow
#INT_TIMER9	Timer 9 overflow
#INT_UART1E	UART1 error
#INT_UART2E	UART2 error
#INT_AUX	Auxiliary memory ISR

Elements:

[PCD] NOCLEAR, LEVEL=n, HIGH, FAST, ALT, CLR_FIRST

Description:

These directives specify the following function is an interrupt function. Interrupt functions may not have any parameters. Not all directives may be used with all parts. See the devices .h file for all valid interrupts for the part or in PCW use the pull down VIEW | Valid Ints

The compiler will generate code to jump to the function when the interrupt is detected. It will generate code to save and restore the machine state, and will clear the interrupt flag. To prevent the flag from being cleared add NOCLEAR after the #INT_xxxx. The application program must call ENABLE_INTERRUPTS(INT_xxxx) to initially activate the interrupt along with the ENABLE_INTERRUPTS(GLOBAL) to enable interrupts.

The keywords HIGH and FAST may be used with the PCH compiler to mark an interrupt as high priority. A high-priority interrupt can interrupt another interrupt handler. An interrupt marked FAST is performed without saving or restoring any registers. This should be used as little as possible and save any registers that need to be saved manually. Interrupts marked HIGH can be used normally. See #DEVICE for information on building with high-priority interrupts.

[PCD] An interrupt marked FAST uses the shadow feature to save registers. Only one interrupt may be marked fast. Any registers used in the FAST interrupt beyond the shadow registers is the responsibility of the user to save and restore.

Level=n - specifies the level of the interrupt. Higher numbers are a higher priority.

Enable_interrupts - specifies the levels that are enabled. The default is level 0 and level 7 is never disabled. High is the same as level = 7.

A summary of the different kinds of dsPIC/PIC24 interrupts:

#INT_xxxx Normal (low priority) interrupt - Compiler saves/restores key registers. This interrupt will not interrupt any interrupt in progress.

#INT_xxxx FAST - Compiler does a FAST save/restore of key registers. Only one is allowed in a program.

#INT_xxxxLevel=3 - Interrupt is enabled when levels 3 and below are enabled.

#INT_GLOBAL - Compiler generates no interrupt code. User function is located at address 8 for user interrupt handling.

#INT_xxxx ALT - Interrupt is placed in Alternate Interrupt Vector instead of Default Interrupt Vector.

A summary of the different kinds of PIC18 interrupts:

#INT_xxxx - Normal (low priority) interrupt. Compiler saves/restores key registers. This interrupt will not interrupt any interrupt in progress.

#INT_xxxx FAST - High priority interrupt. Compiler DOES NOT save/restore key registers. This interrupt will interrupt any normal interrupt in progress. Only one is allowed in a program.

#INT_xxxx HIGH - High priority interrupt. Compiler saves/restores key registers. This interrupt will interrupt any normal interrupt in progress.

#INT_xxxx NOCLEAR - The compiler will not clear the interrupt.

#INT_xxx CLEAR_FIRST - The compiler will clear the interrupt at the beginning of the ISR instead of the end. The user code in the function should call `clear_interrupt()` to clear the interrupt in this case.

#INT_GLOBAL - Compiler generates no interrupt code. User function is located at address 8 for user interrupt handling.

Some interrupts shown in the devices header file are only for the enable/disable interrupts. For example, **INT_RB3** may be used in enable/interrupts to enable pin B3. However, the interrupt handler is **#INT_RB**.

Similarly **INT_EXT_L2H** sets the interrupt edge to falling and the handler is **#INT_EXT**.

Example Files:

ex_sisr.c and ex_stwt.c

Examples:

```
#int_ad
adc_handler() {
    adc_active=FALSE;
}

#int_rtcc noclear
isr() {
    ...
}
[PCD]
#int_ad
adc_handler() {
    adc_active=FALSE;
}

#int_timer1 noclear
isr() {
    ...
}
```

See Also:

enable_interrupts(), disable_interrupts(), #INT_DEFAULT, #INT_GLOBAL, #PRIORITY

#int default

Syntax:

#int_default

Elements:

None

Description:

The following function will be called if the device triggers an interrupt and none of the interrupt flags are set. If an interrupt is flagged, but is not the one triggered, the #INT_DEFAULT function will get called.

[PCD] A #INT_xxx handler has not been defined for the interrupt.

Examples:

```
#int_default
default_isr() {
    printf("unexplained interrupt\r\n");
}
```

See Also:

#INT_xxxx, #INT_global

#int_global**Syntax:**

#int_global

Elements:

None

Description:

This directive causes the following function to replace the compiler interrupt dispatcher. The function is normally not required and should be used with great caution. When used, the compiler does not generate start-up code or clean-up code, and does not save the registers.

Example Files:

ex_glint.c

Examples:

```
#int_global
ISR() {                                //Will be located at location 4 for PIC16 devices
    #asm
    bsf isr_flag
    retfie
    #endasm
}
```

See Also:

#INT_xxxx

line

Syntax:

__line__

Elements:

None

Description:

The pre-processor identifier is replaced at compile time with the line number of the file being compiled.

Example Files:

assert.h

Examples:

```

if(index>MAX_ENTRIES)
    printf("Too many entries, source file: "__FILE__" at line"
        "__LINE__" "\r\n");

```

See Also:

file

#list

Syntax:

#list

Elements:

None

Description:

#list begins inserting or resumes inserting source lines into the .lst file after a #NOLIST.

Example Files:

16c74.h

Examples:

```

#NOLIST                                //Do not clutter up the list file
#include<cdriver.h>
#LIST

```

See Also:

#NOLIST

#line

Syntax:

#line number file name

Elements:

Number - is non-negative decimal integer. File name is optional.

Description:

The C pre-processor informs the C Compiler of the location in your source code. This code is simply used to change the value of `__LINE__` and `__FILE__` variable.

Examples:

```

void main(){
#line 10           //specifies the line number that should be reported
                  //for the following line of input

#line 7"hello.c" //line number in the source file hello.c and it sets
                  //the line 7 as current line and hello.c as current
file

```

#locate

Syntax:

#locate *id*=*x*

Elements:

id - is a C variable

x - is a constant memory address

Description:

#LOCATE allocates a C variable to a specified address. If the C variable was not previously defined, it will be defined as an INT8.

A special form of this directive may be used to locate all A functions local variables starting at a fixed location.

Use: #LOCATE Auto = address

This directive will place the indirected C variable at the requested address.

Example Files:

ex_glint.c

Examples:

```

//This will locate the float variable at 50-53
//and C will not use this memory for other
//variables automatically located.

float x:
#locate x=0x50
[PCD]
float x:
#locate x=0x800

```

See Also:

[#byte](#), [#bit](#), [#reserve](#), [#word](#), [Named Registers](#), [Type Specifiers](#), [Type Qualifiers](#), [Enumerated Types](#), [Structures & Unions](#), [Typedef](#)

#module**Syntax:**

```
#module
```

Elements:

None

Description:

All global symbols created from the #MODULE to the end of the file will only be visible within that same block of code (and files #INCLUDE within that block). This may be used to limit the scope of global variables and functions within include files. This directive also applies to pre-processor #defines.

Note: The extern and static data qualifiers can also be used to denote scope of variables and functions as in the standard C methodology. #MODULE does add some benefits in that pre-processor #DEFINE can be given scope, which cannot normally be done in standard C methodology.

Examples:

```

int GetCount(void);
void SetCount(int newCount);
#MODULE
int g_count;
#define G_COUNT_MAX 100
int GetCount(void) {return(g_count);}
void SetCount(int newCount) {
    if (newCount>G_COUNT_MAX)
        newCount=G_COUNT_MAX;
    g_count=newCount;
}
/*

```

```
the functions GetCount() and SetCount() have global scope, but the
variable g_count and the #define G_COUNT_MAX only has scope to this
file.
*/
```

See Also:

#EXPORT, **Invoking the Command Line Compiler**, **Multiple Compilation Unit**

#nolist**Syntax:**

#nolist

Elements:

None

Description:

Stops inserting source lines into the .lst file (until a #LST).

Example Files:

16c74.h

Examples:

```
#NOLIST          //Do not clutter up the list list
#include<cdriver.h>
#LIST
```

See Also:

#LIST

#OCS**Syntax:**

#osc x

Elements:

x - is the clock's speed and can be 1 Hz to 100 Mhz.

Description:

Used instead of the **#use delay(clock=x)**

Examples:

```
#include<18F4520.h>
#device ICD=TRUE
#OCS 20 Mhz
```

```
#use rs232(debugger)

void(){
    ---;
}
```

See Also:
[#USE DELAY](#)

#opt

Syntax:
#opt n

Elements:

All Devices: **n** is the optimization level 1-9 or by using the word "compress" for PIC18 and Enhanced PIC16 families.

[PCD] All Devices: **n** is the optimization level 0-9

Description:

The optimization level is set with this directive. This setting applies to the entire program and may appear anywhere in the file. The default is 9 for normal. When Compress is specified the optimization is set to an extreme level that causes a very tight ROM image, the code is optimized for space, not speed. Debugging with this level may be more difficult.

Examples:

```
#opt5
```

#org

Syntax:

#ORG *start, end*

or

#ORG *segment*

or

#ORG *start, end { }*

or

#ORG *start, end auto=0*

#ORG *start, end DEFAULT*

or

#ORG *DEFAULT*

Elements:

start - is the first ROM location (word address) to use.

end - is the last ROM location.

segment - is the start ROM location from a previous #ORG

Description:

This directive will fix the following function, constant or ROM declaration into a specific ROM area. End may be omitted if a segment was previously defined if you only want to add another function to the segment.

Follow the ORG with a { } to only reserve the area with nothing inserted by the compiler.

The RAM for a ORG'd function may be reset to low memory so the local variables and scratch variables are placed in low memory. This should only be used if the ORG'd function will not return to the caller. The RAM used will overlap the RAM of the main program. Add a AUTO=0 at the end of the #ORG line.

If the keyword DEFAULT is used then this address range is used for all functions user and compiler generated from this point in the file until a #ORG DEFAULT is encountered (no address range). If a compiler function is called from the generated code while DEFAULT is in effect the compiler generates a new version of the function within the specified address range.

#ORG may be used to locate data in ROM. Because CONSTANT are implemented as functions the #ORG should proceed the CONSTANT and needs a start and end address.

For a ROM declaration only the start address should be specified.

When linking multiple compilation units be aware this directive applies to the final object file. It is an error if any #ORG overlaps between files unless the #ORG matches exactly.

Example Files:

loader.c

Examples:

```
#ORG 0x1E00, 0x1FFF
MyFunc() {
    //This function located at 1E00
}

#ORG 0x1E00
Anotherfunc(){
    // This will be somewhere 1E00-1F00
}

#ORG 0x800, 0x820 {} //Nothing will be at 800-820

#ORG 0x1B80
ROM int32 seridl_N0=12345;

#ORG 0x1C00, 0x1C0F //This ID will be at 1C00
```

```
CHAR CONST ID[10]= {"123456789"}; //Note some extra code will
                                   //proceed the 123456789

#ORG 0x1F00, 0x1FF0
Void loader () {
...
}
```

See Also:

#ROM

#pin_select

Syntax:

#PIN_SELECT function=pin_xx

Elements:

function - is the Microchip defined pin function name, such as:

- U1RX(UART1 receive)
- INT1(external interrupt 1)
- T2CK (timer 2 clock)
- IC1 (input capture 1)
- OC1 (output capture 1)

PCB, PCM, PCH

INT1	External Interrupt 1
INT2	External Interrupt 2
INT3	External Interrupt 3
T0CK	Timer0 External Clock
T3CK	Timer3 External Clock
CCP1	Input Capture 1
CCP2	Input Capture 2
T1G	Timer1 Gate Input
T3G	Timer3 Gate Input
U2RX	EUSART2 Asynchronous Receive/Synchronous Receive (also named: RX2)
U2CK	EUSART2 Asynchronous Clock Input
SDI2	SPI2 Data Input
SCK2IN	SPI2 Clock Input
SS2IN	SPI2 Slave Select Input
FLT0	PWM Fault Input
T0CKI	Timer0 External Clock Input
T3CKI	Timer3 External Clock Input
RX2	EUSART2 Asynchronous Transmit/Asynchronous Clock Output (also named: TX2)
NULL	NULL

C1OUT	Comparator 1 Output
C2OUT	Comparator 2 Output
U2TX	EUSART2 Asynchronous Transmit/ Asynchronous Clock Output (also named: TX2)
U2DT	EUSART2 Synchronous Transmit (also named: DT2)
SDO2	SPI2 Data Output
SCK2OUT	SPIC2 Clock Output
SS2OUT	SPI2 Slave Select Output
ULPOUT	Ultra Low-Power Wake-Up Event
P1A	ECCP1 Compare or PWM Output Channel A
P1B	ECCP1 Enhanced PWM Output, Channel B
P1C	ECCP1 Enhanced PWM Output, Channel C
P1D	ECCP1 Enhanced PWM Output, Channel D
P2A	ECCP2 Compare or PWM Output Channel A
P2B	ECCP2 Enhanced PWM Output, Channel B
P2C	ECCP2 Enhanced PWM Output, Channel C
P2D	ECCP1 Enhanced PWM Output, Channel D
TX2	EUSART2 Asynchronous Transmit/Asynchronous Clock Output (also named: TX2)
DT2	EUSART2 Synchronous Transmit (also named: U2DT)
SCK2	SPI2 Clock Output
SSDMA	SPI DMA Slave Select

pin_xx is the CCS provided pin definition. For example: PIN_C7, PIN_B0, PIN_D3, etc.

PCD (PIC24/dsPIC devices)

NULL	NULL
C1OUT	Comparator 1 Output
C2OUT	Comparator 2 Output
C3OUT	Comparator 3 Output
C4OUT	Comparator 4 Output
U1TX	UART1 Transmit
U1RTS	UART1 Request to Send
U2TX	UART2 Transmit
U2RTS	UART2 Request to Send
U3TX	UART3 Transmit
U3RTS	UART3 Request to Send
U4TX	UART4 Transmit
U4RTS	UART4 Request to Send
SDO1	SPI1 Data Output
SCK1OUT	SPI1 Clock Output
SS1OUT	SPI1 Slave Select Output
SDO2	SPI2 Data Output
SCK2OUT	SPI2 Clock Output
SS2OUT	SPI2 Slave Select Output
SDO3	SPI3 Data Output

SCK3OUT	SPI3 Clock Output
SS3OUT	SPI3 Slave Select Output
SDO4	SPI4 Data Output
SCK4OUT	SPI4 Clock Output
SS4OUT	SPI4 Slave Select Output
OC1	Output Compare 1
OC2	Output Compare 2
OC3	Output Compare 3
OC4	Output Compare 4
OC5	Output Compare 5
OC6	Output Compare 6
OC7	Output Compare 7
OC8	Output Compare 8
OC9	Output Compare 9
OC10	Output Compare 10
OC11	Output Compare 11
OC12	Output Compare 12
OC13	Output Compare 13
OC14	Output Compare 14
OC15	Output Compare 15
OC16	Output Compare 16
C1TX	CAN1 Transmit
C2TX	CAN2 Transmit
CSDO	DCI Serial Data Output
CSCOUT	DCI Serial Clock Output
COFSOUT	DCI Frame Sync Output
UPDN1	QE11 Direction Status Output
UPDN2	QE12 Direction Status Output
CTPLS	CTMU Output Pulse
SYNCO1	PWM Synchronization Output Signal
SYNCO2	PWM Secondary Synchronization Output Signal
REFCLKO	REFCLK Output Signal
CMP1	Analog Comparator Output 1
CMP2	Analog Comparator Output 2
CMP3	Analog Comparator Output 3
CMP4	Analog Comparator Output 4
PWM4H	PWM4 High Output
PWM4L	PWM4 Low Output
QE1CCMP	QE11 Counter Comparator Output
QE2CCMP	QE12 Counter Comparator Output
MDOUT	DSM Modulator Output
DCIDO	DCI Serial Data Output
DCISCKOUT	DCI Serial Clock Output
DCIFSOUT	DCI Frame Sync Output
INT1	External Interrupt 1 Input

INT2	External Interrupt 2 Input
INT3	External Interrupt 3 Input
INT4	External Interrupt 4 Input
T1CK	Timer 1 External Clock Input
T2CK	Timer 2 External Clock Input
T3CK	Timer 3 External Clock Input
T4CK	Timer 4 External Clock Input
T5CK	Timer 5 External Clock Input
T6CK	Timer 6 External Clock Input
T7CK	Timer 7 External Clock Input
T8CK	Timer 8 External Clock Input
T9CK	Timer 9 External Clock Input
IC1	Input Capture 1
IC2	Input Capture 2
IC3	Input Capture 3
IC4	Input Capture 4
IC5	Input Capture 5
IC6	Input Capture 6
IC7	Input Capture 7
IC8	Input Capture 8
IC9	Input Capture 9
IC10	Input Capture 10
IC11	Input Capture 11
IC12	Input Capture 12
IC13	Input Capture 13
IC14	Input Capture 14
IC15	Input Capture 15
IC16	Input Capture 16
C1RX	CAN1 Receive
C2RX	CAN2 Receive
OCFA	Output Compare Fault A Input
OCFB	Output Compare Fault B Input
OCFC	Output Compare Fault C Input
U1RX	UART1 Receive
U1CTS	UART1 Clear to Send
U2RX	UART2 Receive
U2CTS	UART2 Clear to Send
U3RX	UART3 Receive
U3CTS	UART3 Clear to Send
U4RX	UART4 Receive
U4CTS	UART4 Clear to Send
SDI1	SPI1 Data Input
SCK1IN	SPI1 Clock Input
SS1IN	SPI1 Slave Select Input
SDI2	SPI2 Data Input

SCK2IN	SPI2 Clock Input
SS2IN	SPI2 Slave Select Input
SDI3	SPI3 Data Input
SCK3IN	SPI3 Clock Input
SS3IN	SPI3 Slave Select Input
SDI4	SPI4 Data Input
SCK4IN	SPI4 Clock Input
SS4IN	SPI4 Slave Select Input
CSDI	DCI Serial Data Input
CSCK	DCI Serial Clock Input
COFS	DCI Frame Sync Input
FLTA1	PWM1 Fault Input
FLTA2	PWM2 Fault Input
QEA1	QEI1 Phase A Input
QEA2	QEI2 Phase A Input
QEB1	QEI1 Phase B Input
QEB2	QEI2 Phase B Input
INDX1	QEI1 Index Input
INDX2	QEI2 Index Input
HOME1	QEI1 Home Input
HOME2	QEI2 Home Input
FLT1	PWM1 Fault Input
FLT2	PWM2 Fault Input
FLT3	PWM3 Fault Input
FLT4	PWM4 Fault Input
FLT5	PWM5 Fault Input
FLT6	PWM6 Fault Input
FLT7	PWM7 Fault Input
FLT8	PWM8 Fault Input
SYNCI1	PWM Synchronization Input 1
SYNCI2	PWM Synchronization Input 2
DCIDI	DCI Serial Data Input
DCISCKIN	DCI Serial Clock Input
DCIFSIN	DCI Frame Sync Input
DTCMP1	PWM Dead Time Compensation 1 Input
DTCMP2	PWM Dead Time Compensation 2 Input
DTCMP3	PWM Dead Time Compensation 3 Input
DTCMP4	PWM Dead Time Compensation 4 Input
DTCMP5	PWM Dead Time Compensation 5 Input
DTCMP6	PWM Dead Time Compensation 6 Input
DTCMP7	PWM Dead Time Compensation 7 Input

Description:

When using PPS chips a #PIN_SELECT must be appear before these peripherals can be used or referenced.

[PCD] On devices that contain Peripheral Pin Select (PPS), this allows the programmer to define which pin a peripheral is mapped to.

Examples:

```
#pin_select U1TX=PIN_C6
#pin_select U1RX=PIN_C7
#pin_select INT1=PIN_B0
```

See Also:

pin_select()

pcb

Syntax:

__pcb__

Elements:

None

Description:

The PCB compiler defines this pre-processor identifier. It may be used to determine if the PCB is doing the compilation.

Example Files:

ex_sqw.c

Examples:

```
#ifdef __pcb__
#device PIC16C54
#endif
```

See Also:

PCM, PCH, PCD

pcd

Syntax:

__pcd__

Elements:

None

Description:

The PCD compiler defines this pre-processor identifier. It may be used to determine if the PCD is doing the compilation.

Example Files:

ex_sqw.c

Examples:

```
#ifdef __pcd__
#device dsPIC33FJ256MC710
#endif
```

See Also:

__PCB__, __PCM__, __PCH__

pcm**Syntax:**

__pcm__

Elements:

None

Description:

The PCM compiler defines this pre-processor identifier. It may be used to determine if the PCM is doing the compilation.

Example Files:

ex_sqw.c

Examples:

```
#ifdef __pcm__
#device PIC16C71
#endif
```

See Also:

__PCB__, __PCH__, __PCD__

pch**Syntax:**

__pch__

Elements:

None

Description:

The PCH compiler defines this pre-processor identifier. It may be used to determine if the PCH is doing the compilation.

Example Files:

ex_sqw.c

Examples:

```
#ifdef __pch__
#device PIC18F452
#endif
```

See Also:

__PCM__, __PCM__, __PCD__

#pragma**Syntax:**

#pragma cmd

Elements:

cmd - is any valid pre-processor directive.

Description:

This directive is used to maintain compatibility between C compilers. This compiler will accept this directive before any other pre-processor command. In no case does this compiler require this directive.

Example Files:

ex_cust.c

Examples:

```
#pragma device PIC16C54
```

See Also:**#priority****Syntax:**

#priority ints

Elements:

ints - is a list of one or more interrupts separated by commas.

exports - makes the functions generated from this directive available to other compilation units within the link.

Description:

The priority directive may be used to set the interrupt priority. The highest priority items are first in the list. If an interrupt is active it is never interrupted. If two interrupts occur at around the same time then the higher one in this list will be serviced first. When linking multiple compilation units be aware only the one in the last compilation unit is used.

Examples:

```
#priority rtc_c.rb
```

See Also:

[#INT xxxx](#)

#profile**Syntax:**

#profile options

Elements:

options - may be one of the following:

functions - Profiles the start/end of functions and all profileout() messages.

functions, parameters - Profiles the start/end of functions, parameters sent to functions, and all profileout() messages.

profileout - Only profile profileout() messages.

paths - Profiles every branch code.

off - Disable all code profiling.

on - Re-enables the code profiling that was previously disabled with a **#profile off** command. This will use the last options before disabled with the off command.

Description:

Large programs on the microcontroller may generate lots of profile data, which may make it difficult to debug or follow. By using **#profile** the user can dynamically control which points of the program are being profiled, and limit data to what is relevant to the user.

Example Files:

[ex_profile.c](#)

Examples:

```
#profile off
void BigFunction(void)
{
    //BigFunction code goes here since #profile off was called above.
    //No profiling will happen even for the functions called by
    BigFunction().
}
#profile on
```

See Also:

[#use profile\(\)](#), [profileout\(\)](#), [Code Profile overview](#)

#recursive**Syntax:**

#recursive

Elements:

None

Description:

Directs the compiler that the procedure immediately following the directive will be recursive.

Examples:

```
#recursive
int factorial(int num){
    if(num <=1)
        return 1;
    return num * factorial(num-1);
}
```

#reserve**Syntax:**

#reserve **address**

#reserve **address, address, address**

#reserve **start:end**

Elements:

address - is a RAM address.

start - is the first address.

end - is the last address.

Description:

This directive allows RAM locations to be reserved from use by the compiler. #RESERVE must appear after the #DEVICE otherwise it will have no effect. When linking multiple compilation units be aware this directive applies to the final object file.

Example Files:

ex_cust.c

Examples:

```
#device PIC16C74
#reserve 0x60:0X6f
```

```
[PCD]
#device dsPIC30F2010
#reserve 0x800:0x80B3
```

See Also:

#ORG

#rom

Syntax:

```
#rom address = {list}
```

Elements:

address - is the same address used in the device datasheet (Byte for PIC18 and Word for all others)

list - is a list of words separated by commas.

Description:

Allows the insertion of data into the .HEX file. For example, this may be used to program the '84 data EEPROM, as shown in the following example.

Note that if the #ROM address is inside the program memory space, the directive creates a segment for the data, resulting in an error if a #ORG is over the same area. The #ROM data will also be counted as used program memory space.

The type option indicates the type of each item, the default is 16 bits. Using char as the type treats each item as 7 bits packing 2 chars into every PCM 14-bit word.

When linking multiple compilation units be aware this directive applies to the final object file.

Some special forms of this directive may be used for verifying program memory:

#ROM address = checksum - This will put a value at address such that the entire program memory will sum to 0x1248.

#ROM address = crc16 - This will put a value at address that is a crc16 of all the program memory except the specified address.

#ROM address = crc16(start, end) - This will put a value at address that is a crc16 of all the program memory from start to end.

#ROM address = crc8 - This will put a value at address that is a crc16 of all the program memory except the specified address.

Example Files:

ex_glint.c

Examples:

```
#rom getenv("EEPROM_ADDRESS")={1,2,3,4,5,6,7,8}
#rom int8 0x1000={"(c) CCS, 2010"}
```

See Also:

#ORG

#separate

Syntax:

#separate

[PCD] #separate *options*

Elements:

[PCD] *options* - options include:

STDCALL - Use the standard Microchip calling method, as used in C30. W0-W7 is used for function parameters, rest of the working registers are not touched, remaining function parameters are pushed onto the stack.

ARG=Wx:Wy - Use the working registers Wx to Wy to hold function parameters. Any remaining function parameters are pushed onto the stack.

DND=Wx:Wy - Function will not change Wx to Wy working registers.

AVOID=Wx:Wy - Function will not use Wx to Wy working registers for function parameters.

NO RETURN - Prevents the compiler generated return at the end of a function.

Use STDCALL with the ARG, DND or AVOID parameters.

If one of these options is not specified, the compiler will determine the best configuration, and will usually not use the stack for function parameters (usually scratch space is allocated for parameters).

Description:

Directs the compiler that the procedure immediately following the directive is to be implemented separately. This is useful to prevent the compiler from automatically making a procedure inline. This will save ROM space, but it does use more stack space.

The compiler will make all procedures marked ***separate***, separated as requested, even if there is not enough stack space to execute.

Example Files:

ex_cust.c

Examples:

```
#separate
swapbyte (int*a, int*b){
  int t;
  t=*a;
  *a=*b;
  *b=t;
}
[PCD]
#separate ARG=W0:W7 AVOID=W8:W15 DND=W8:W15
swapbyte (int*a, int*b){
  int t;
  t=*a;
  *a=*b;
  *b=t;
}
```

See Also:

#INLINE

#serialize

Syntax:

#SERIALIZE(*id=xxx*, *next="x"* | *file="filename.txt"* | *listfile="filename.txt"*,
"*prompt="text"*, *log="filename.txt"*) -

#SERIALIZE(*dataee=x*, *binary=x*, *next="x"* | *file="filename.txt"* |
listfile="filename.txt",
prompt="text", *log="filename.txt"*)

Elements:

id=xxx - Specify a C CONST identifier, may be int8, int16, int32 or char array.

Use in place of **id** parameter, when storing serial number to EEPROM:

dataee=x - The address x is the start address in the data EEPROM.

binary=x - The integer x is the number of bytes to be written to address specified.

string=x - The integer x is the number of bytes to be written to address specified.

unicode=n - If n is a 0, the string format is normal unicode. For n>0 n indicates the string number in a USB descriptor.

Use only one of the next three options:

file="filename.txt" - The file x is used to read the initial serial number from, and this file is updated by the ICD programmer. It is assumed this is a one line file with the serial number. The programmer will increment the serial number.

listfile="filename.txt" - The file x is used to read the initial serial number from, and this file is updated by the ICD programmer. It is assumed this is a file one serial number per line. The programmer will read the first line then delete that line from the file.

next="x" - The serial number X is used for the first load, then the hex file is updated to increment x by one.

Other optional parameters:

prompt="text" - If specified the user will be prompted for a serial number on each load. If used with one of the above three options then the default value the user may use is picked according to the above rules.

log=xxx - A file may optionally be specified to keep a log of the date, time, hex file name and serial number each time the part is programmed. If no id=xxx is specified then this may be used as a simple log of all loads of the hex file.

Description:

Assists in making serial numbers easier to implement when working with CCS ICD units. Comments are inserted into the hex file that the ICD software interprets.

Examples:

```
//Prompt user for serial number to be placed
//at address of serialNumA
//Default serial number = 200int8int8 const serialNumA=100;
//#serialize(id=serialNumA,next="200",prompt="Enter the serial number")

//Adds serial number log in seriallog.txt
//#serialize(id=serialNumA,next="200",prompt="Enter the serial number",
```

```
//log="seriallog.txt")

//Retrieves serial number from serials.txt
//#serialize(id=serialNumA,listfile="serials.txt")

//Place serial number at EEPROM address 0, reserving 1 byte
//#serialize(dataee=0,binary=1,next="45",prompt="Put in Serial number")

//Place string serial number at EEPROM address 0, reserving 2 bytes
//#serialize(dataee=0, string=2,next="AB",prompt="Put in Serial
number")
```

#task

(The RTOS is only included with the PCW, PCWH, and PCWHD software packages.)

Each RTOS task is specified as a function that has no parameters and no return. The #TASK directive is needed just before each RTOS task to enable the compiler to tell which functions are RTOS tasks. An RTOS task cannot be called directly like a regular function can.

Syntax:

#task (*options*)

Elements:

options are separated by comma and may be:

rate=time - Where time is a number followed by s, ms, us, or ns. This specifies how often the task will execute.

max=time - Where time is a number followed by s, ms, us, or ns. This specifies the budgeted time for this task.

queue=bytes - Specifies how many bytes to allocate for this task's incoming messages. The default value is 0.

enabled=value - Specifies whether a task is enabled or disabled by rtos_run(). True for enabled, false for disabled. The default value is enabled.

Description:

This directive tells the compiler that the following function is an RTOS task.

The rate option is used to specify how often the task should execute. This must be a multiple of the minor_cycle option if one is specified in the #USE RTOS directive.

The max option is used to specify how much processor time a task will use in one execution of the task. The time specified in max must be equal to or less than the time

specified in the `minor_cycle` option of the `#USE RTOS` directive before the project will compile successfully. The compiler does not have a way to enforce this limit on processor time, so a programmer must be careful with how much processor time a task uses for execution. This option does not need to be specified.

The `queue` option is used to specify the number of bytes to be reserved for the task to receive messages from other tasks or functions. The default `queue` value is 0.

Examples:

```
#task(rate=1s, max=20ms, queue=5)
```

See Also:

`#USE RTOS`

time**Syntax:**

```
__time__
```

Elements:

None

Description:

This pre-processor identifier is replaced at compile time with the time of the compile in the form: **"hh:mm:ss"**

Examples:

```
printf("Software was compiled on");
printf(__TIME__);
```

#todo**Syntax:**

```
#todo text
```

Elements:

text is free text

Description:

This directive documents in the source code items that the developer needs to work on.

Example Files:

None

Examples:

```
#todo Verify the math works in convert_adc_values
```

See Also:

[PCW Overview](#)

#type**Syntax:**

#TYPE *standard-type*=*size*

#TYPE *default=area*

#TYPE **unsigned**

#TYPE **signed**

[PCD] #TYPE **char=signed**

[PCD] #TYPE **char=unsigned**

[PCD] #TYPE ARG=Wx:Wy

[PCD] #TYPE DND=Wx:Wy

[PCD] #TYPE AVOID=Wx:Wy

[PCD] #TYPE RECURSIVE

[PCD] #TYPE CLASSIC

Elements:

standard-type - is one of the C keywords short, int, long, or default

[PCD] ***standard-type*** - is one of the C keywords short, int, long, float, or double

size - is 1,8,16, or 32

[PCD] ***size*** - is 1,8,16, 48, or 64

area - is a memory region defined before the #TYPE using the addressmod directive

[PCD] ***Wx:Wy*** - is a range of working registers (example: W0, W1, W15, etc)

Description:

By default the compiler treats SHORT as one bit / [PCD] 8 bits , INT as 8 / [PCD] 16 bits, and LONG as 16 / [PCD] 32 bits. The traditional C convention is to have INT defined as the most efficient size for the target processor. This is why it is 8-bit on PIC devices or [PCD] 16-bits on dsPIC/PIC24 ® . In order to help with code compatibility a #TYPE directive may be used to allow these types to be changed. #TYPE can redefine these keywords.

Note that the commas are optional. Since #TYPE may render some sizes inaccessible (like a one bit int in the above) four keywords representing the four ints may always be used: INT1, INT8, INT16, and INT32.

Note: CCS example programs and include files may not work correctly when using #TYPE in the program.

[PCD] Classic will set the type sizes to be compatible with CCS PIC programs.

This directive may also be used to change the default RAM area used for variable storage. This is done by specifying default=area where area is a addressmod address space.

When linking multiple compilation units be aware this directive only applies to the current compilation unit.

The #TYPE directive allows the keywords UNSIGNED and SIGNED to set the default data type.

[PCD] The ARG parameter tells the compiler that all functions can use those working registers to receive parameters. The DND parameters tells the compiler that all functions should not change those working registers (not use them for scratch space). The AVOID parameter tells the compiler to not use those working registers for passing variables to functions. If you are using recursive functions, then it will use the stack for passing variables when there is not enough working registers to hold variables; if you are not using recursive functions, the compiler will allocate scratch space for holding variables if there is not enough working registers. #SEPARATE can be used to set these parameters on an individual basis.

[PCD] The RECURSIVE option tells the compiler that ALL functions can be recursive. #RECURSIVE can also be used to assign this status on an individual basis.

Example Files:

ex_cust.c

Examples:

```
#TYPE    SHORT= 8, INT= 16, LONG= 32

#TYPE default=area

addressmod (user_ram_block, 0x100, 0x1FF);

#type default=user_ram_block // all variable declarations
                             // in this area will be in
                             // 0x100-0x1FF

#type default=                // restores memory allocation
```

```

// back to normal

#TYPE SIGNED
...
void main()
{
int variable1;           // variable1 can only take values from -128 to
127
...
...
}

[PCD]
#TYPE    SHORT=1, INT=8, LONG=16, FLOAT=48

#TYPE default=area

addressmod (user_ram_block, 0x100, 0x1FF);

#type default=user_ram_block // all variable declarations
                             // in this area will be in
                             // 0x100-0x1FF

#type default=              // restores memory allocation
                             // back to normal

#TYPE SIGNED

#TYPE RECURSIVE
#TYPE ARG=W0:W7
#TYPE AVOID=W8:W15
#TYPE DND=W8:W15

...
void main()
{
int variable1;           // variable1 can only take values from -128 to
127
...
...
}

```

#undef

Syntax:

#undef *id*

Elements:

id - is a pre-processor *id* defined via **#DEFINE**

Description:

The specified pre-processor ID will no longer have meaning to the pre-processor.

Examples:

```
#if MAXSIZE<100
#undef MAXSIZE
#define MAXSIZE 100
#endif
```

See Also:

[#DEFINE](#)

unicode**Syntax:**

`__unicode(constant-string)`

Elements:

Unicode format string

Description:

This macro will convert a standard ASCII string to a Unicode format string by inserting a \000 after each character and removing the normal C string terminator. For example:

```
__unicode("ABCD")
will return: "A\00B\000C\000D" (8 bytes total with the terminator)
```

Since the normal C terminator is not used for these strings you need to do one of the following for variable length strings:

```
string = __unicode(KEYWORD)  "\000\000";

OR

string = __unicode(KEYWORD);
string_size = sizeof(__unicode(KEYWORD));
```

Example Files:

[usb_desc_hid.h](#)

Examples:

```
#define USB_DESC_STRING_TYPE 3

#define USB_STRING(x) (sizeof(__unicode(x))+2), USB_DESC_STRING_TYPE,
__unicode(x)
#define USB_ENGLISH_STRING 4,USB_DESC_STRING_TYPE,0x09,0x04
//Microsoft defined for US
English

char const USB_STRING_DESC[]={
```

```

    USB_ENGLISH_STRING;
    USB_STRING("CCS");
    USB_STRING("CCS HID DEMO")
};

```

#use capture

Syntax:

#use capture (*options*)

Elements:

ICx/CCPx - Which CCP/Input Capture module to us.

INPUT = PIN_xx - Specifies which pin to use. Useful for device with remappable pins, this will cause compiler to automatically assign pin to peripheral.

TIMER=x - Specifies the timer to use with capture unit. If not specified default to timer 1 for PCM and PCH compilers and timer 3 for PCD compiler.

TICK=x - The tick time to setup the timer to. If not specified it will be set to fastest as possible or if same timer was already setup by a previous stream it will be set to that tick time. If using same timer as previous stream and different tick time an error will be generated.

FASTEST - Use instead of TICK=x to set tick time to fastest as possible.

SLOWEST - Use instead of TICK=x to set tick time to slowest as possible.

CAPTURE_RISING - Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING.

CAPTURE_FALLING - Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING.

CAPTURE_BOTH - PCD only. Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING.

PRE=x - Specifies number of rising edges before capture event occurs. Valid options are 1, 4 and 16, default to 1 if not specified. Options 4 and 16 are only valid when using CAPTURE_RISING, will generate an error is used with CAPTURE_FALLING or CAPTURE_BOTH.

[PCD] ISR=x - Specifies the number of capture events to occur before generating capture interrupt. Valid options are 1, 2, 3 and 4, defaults to 1 is not specified. Option 1 is only valid option when using CAPTURE_BOTH, will generate an error if trying to use 2, 3 or 4 with it.

STREAM=id - Associates a stream identifier with the capture module. The identifier may be used in functions like `get_capture_time()`.

DEFINE=id - Creates a define named `id` which specifies the number of capture per second. Default define name if not specified is `CAPTURES_PER_SECOND`. Define name must start with an ASCII letter 'A' to 'Z', an ASCII letter 'a' to 'z' or an ASCII underscore ('_').

Description:

This directive tells the compiler to setup an input capture on the specified pin using the specified settings. The `#USE DELAY` directive must appear before this directive can be used. This directive enables use of built-in functions such as `get_capture_time()` and `get_capture_event()`.

Examples:

```
#USE CAPTURE (INPUT=PIN_C2, CAPTURE_RISING, TIMER=1, FASTEST)
```

See Also:

[get_capture_time\(\)](#), [get_capture_event\(\)](#)

#use_delay

Syntax:

`#use_delay (options)`

Elements:

Options - may be any of the following separated by commas:

clock=speed speed is a constant 1-100000000 (1 hz to 100 mhz).

This number can contains commas. This number also supports the following denominations: M, MHZ, K, KHZ. This specifies the clock the CPU runs at.

Depending on the PIC this is 2 or 4 times the instruction rate. This directive is not needed if the following `type=speed` is used and there is no frequency multiplication or division.

type=speed type defines what kind of clock you are using, and the following values are valid: oscillator, osc (same as oscillator), crystal, xtal (same as crystal), internal, int (same as internal) or rc. The compiler will automatically set the oscillator configuration bits based upon your defined type. If you specified internal, the compiler will also automatically set the internal oscillator to the defined speed. Configuration fuses are modified when this option is used. Speed is the input frequency.

restart_wdt will restart the watchdog timer on every `delay_us()` and `delay_ms()` use.

clock_out when used with the internal or oscillator types this enables the clockout pin to output the clock.

fast_start some chips allow the chip to begin execution using an internal clock until the primary clock is stable.

lock some chips can prevent the oscillator type from being changed at run time by the software.

USB or USB_FULL for devices with a built-in USB peripheral. When used with the **type=speed** option the compiler will set the correct configuration bits for the USB peripheral to operate at Full-Speed.

USB_LOW for devices with a built-in USB peripheral. When used with the **type=speed** option the compiler will set the correct configuration bits for the USB peripheral to operate at Low-Speed.

PLL_WAIT for devices with a PLL and a PLL Ready Status flag to test. When a PLL clock is specified it will cause the compiler to poll the ready PLL Ready Flag and only continue program execution when flag indicates that the PLL is ready.

ACT or ACT=type for device with Active Clock Tuning, type can be either USB or SOSC. If only using ACT type will default to USB. ACT=USB causes the compiler to enable the active clock tuning and to tune the internal oscillator to the USB clock. ACT=SOSC causes the compiler to enable the active clock tuning and to tune the internal oscillator to the secondary clock at 32.768 kHz. ACT can only be used when the system clock is set to run from the internal oscillator.

[PCD] AUX: type=speed Some chips have a second oscillator used by specific peripherals and when this is the case this option sets up that oscillator.

[PCD] PLL_WAIT when used with a PLL clock, it causes the compiler to poll PLL ready flag and to only continue program execution when flag indicates that the PLL is ready.

Description:

Tells the compiler the speed of the processor and enables the use of the built-in functions: `delay_ms()` and `delay_us()`. Will also set the proper configuration bits, and if needed configure the internal oscillator. Speed is in cycles per second. An optional `restart_wdt` may be used to cause the compiler to restart the WDT while delaying. When linking multiple compilation units, this directive must appear in any unit that needs timing configured (`delay_ms()`, `delay_us()`, UART, SPI).

In multiple clock speed applications, this directive may be used more than once. Any timing routines (`delay_ms()`, `delay_us()`, UART, SPI) that need timing information will use the last defined `#USE DELAY` (For initialization purposes, the compiler will initialize the configuration bits and internal oscillator based upon the first `#USE DELAY`).

Example Files:ex_sqw.c**Examples:**

```

// set timing config to 32KHz, User sets the fuses
// on delay_us() and delay_ms()
#include delay (clock=32000, RESTART_WDT)

//the following 4 examples all configure the timing
library
//to use a 20Mhz clock, where the source is a
crystal.
#include delay (crystal=20000000)
#include delay (xtal=20,000,000)
#include delay(crystal=20Mhz)
#include delay(clock=20M, crystal)

//application is using a 10Mhz oscillator, but using
the 4x PLL
//to upscale it to 40Mhz. Compiler will set config
bits.
#include delay(oscillator=10Mhz, clock=40Mhz)

//application will use the internal oscillator at
8Mhz.
//compiler will set config bits, and set the internal
//oscillator to 8Mhz.
#include delay(internal=8Mhz)

```

See Also:delay_ms(), delay_us()**#use dynamic memory****Syntax:**

#use dynamic_memory

Elements:

None

Description:

This pre-processor directive instructs the compiler to create the `_DYNAMIC_HEAD` object. `_DYNAMIC_HEA` is the location where the first free space is allocated.

Example Files:ex_malloc.c

Examples:

```
#USE DYNAMIC_MEMORY
void main(){
}
```

#use fast_io**Syntax:**

#use fast_io (port)

Elements:

port - is A, B, C, D, E, F, G, H, J or ALL

Description:

Affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another **#use xxxx_IO** directive is encountered. The fast method of doing I/O will cause the compiler to perform I/O without programming of the direction register. The compiler's default operation is the opposite of this command, the direction I/O will be set/cleared on each I/O operation. The user must ensure the direction register is set correctly via **set_tris_X()**. When linking multiple compilation units be aware this directive only applies to the current compilation unit.

Example Files:

ex_cust.c

Examples:

```
#use fast_io(A)
```

See Also:

#USE FIXED_IO, #USE STANDARD_IO, set_tris_X(), General Purpose I/O

#use fixed_io**Syntax:**

#use fixed_io (port_outputs=pin, pin?)

Elements:

value - is a constant 16-bit value

Description:

This directive affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another **#USE XXX_IO** directive is encountered. The fixed method of doing I/O will cause the compiler to generate code to make an I/O pin either input or output every time it is used. The pins are programmed

according to the information in this directive (not the operations actually performed). This saves a byte of RAM used in standard I/O. When linking multiple compilation units be aware this directive only applies to the current compilation unit.

Examples:

```
#use fixed_io(a_outputs=PIN_A2, PIN_A3)
```

See Also:

#USE FAST IO, #USE STANDARD IO, General Purpose I/O

#use i2c

Syntax:

#use i2c (options)

Elements:

options - are separated by commas and may include the following:

MASTER	Sets to the master mode
MULTI_MASTER	Set the multi_master mode
SLAVE	Set the slave mode
SCL=pin	Specifies the SCL pin (pin is a bit address)
SDA=pin	Specifies the SDA pin
ADDRESS=nn	Specifies the slave mode address
FAST	Use the fast I2C specification.
FAST=nnnnnn	Sets the speed to nnnnnn hz
SLOW	Use the slow I2C specification
RESTART_WDT	Restart the WDT while waiting in I2C_READ
FORCE_HW	Use hardware I2C functions.
FORCE_SW	Use software I2C functions.
NOFLOAT_HIGH	Does not allow signals to float high, signals are driven from low to high
SMBUS	Bus used is not I2C bus, but very similar
STREAM=id	Associates a stream identifier with this I2C port. The identifier may then be used in functions like <code>i2c_read</code> or <code>i2c_write</code> .
NO_STRETCH	Do not allow clock stretching
MASK=nn	Set an address mask for parts that support it

I2C1	Instead of SCL= and SDA= this sets the pins to the first module
I2C2	Instead of SCL= and SDA= this sets the pins to the second module
NOINIT	No initialization of the I2C peripheral is performed. Use I2C_INIT() to initialize peripheral at run time.

Only some chips allow the following:

DATA_HOLD	No ACK is sent until I2C_READ is called for data bytes (slave only)
ADDRESS_HOLD	No ACK is sent until I2C_read is called for the address byte (slave only)
SDA_HOLD	Min of 300ns holdtime on SDA a from SCL goes low

PIC18 devices that have a separate I2C peripheral instead of a combined SSP peripheral allow the following:

CLOCK_SOURCE=x	Used to specify the I2C peripheral's clock source. Options can be FOSC/4, FOSC, HFINTOSC or HFINT, MFINTOSC or MFINT, REFCLK or REF, TIMER0 or TMR0, TIMER2 or TMR2, TIMER4 or TMR4, TIMER6 or TMR6, or SMT1. If not specified, it defaults to FOSC/4. If a peripheral is selected as the clock, TMR2 for example, that peripheral must be setup to achieve the desired I2C clock rate.
CLOCK_DIVISOR=x	Used to specify the I2C clock divisor, can be 4 or 5.
ADDRESS_BITS=x	Used to specify the number of address bits, can be set to 7 or 10. Default is 7, if not specified.
ADDRESS1=x ADDRESS2=x ADDRESS3=x ADDRESS4=x	Used to specify the slave mode addresses the peripheral will respond to. Depending on the address bits and number of address masks, these devices can have 4, 2 or 1 addresses that they will respond to. These allow setting the individual addresses, ADDRESS1=x is the same as ADDRESS=xx. When set for 7 bit address mode, can have 4 or 2 addresses. 4 if no masks are specified. 2 if 1 or 2 masks are specified. When set for 10 bit address mode, can have 2 or 1 addresses. 2 if no masks are specified and 1 if 1 mask is specified. If using 1 or more addresses, always start with ADDRESS1, then ADDRESS2, etc., because any unspecified addresses will be assigned to the value of ADDRESS1.
MASK1=x MASK2=x	Used to specify the slave mode address masks, depending on the number of address bits it can have, 0, 1 or 2 address masks. When set for 7 bit address mode, it can have 0 or 2 address masks; simply assigning a value to MASK1 means I2C peripheral is set for 2 addresses and 2 address masks. When

	set for 10 bit address mode, it can have 0 or 1 address masks; simply assigning a value to MASK1 means the peripheral is set for 1 address and 1 address mask. If using 1 or more address mask, always set MASK1 because if 7 bit address mode is used and only MASK1 is specified, both address masks will be set to the value of MASK1. When using 7 bit address mode, MASK1 is the mask for ADDRESS1 and MASK2 is the mask for ADDRESS2.
SDA_HOLD=x	Used to set the hold time on SDA after falling edge of SCL, can be set to 30, 100 or 300ns. If only SDA_HOLD is specified, the hold time is set to 300ns and if not specified, the hold time is set to 100ns.

Description:

CCS offers support for the hardware-based I2C™ and a software-based master I2C™ device. (For more information on the hardware-based I2C module, please consult the datasheet for your target device; not all PICs support I2C™.

The I2C library contains functions to implement an I2C bus. The `#USE I2C` remains in effect for the `I2C_START`, `I2C_STOP`, `I2C_READ`, `I2C_WRITE` and `I2C_POLL` functions until another `USE I2C` is encountered. If hardware pins are specified for SDA and SCL, then hardware functions are generated unless the **force_sw** is specified; otherwise software functions are generated. The SLAVE mode should only be used with the built-in SSP. The functions created with this directive are exported when using multiple compilation units. To access the correct function use the stream identifier.

[PCD] Some devices have an alternate set of I2C pins that may be used with the hardware I2C peripherals instead of the default pins. If a device has alternative I2C pins, then they will have the following configuration fuses available for selecting which pair to use: `ALT_I2Cx` and `NOALT_I2Cx`. `x` being the I2C peripheral (1-3). Setting the `NOALT_I2Cx` configuration fuse causes the device to use the `ASCLx` and `ASDAx` pins for the peripheral. Additionally, these configuration fuses determine which pins `#use i2c()` determines the hardware I2C pins for each I2C peripheral. By default, the `NOALT_I2Cx` configuration fuses are set. In order to use the alternative I2C hardware pins, the `ALT_I2Cx` configuration fuse must be set for that I2C peripheral.

Example Files:

[ex_extee.c](#) with [16c74.h](#)

Examples:

```
#use i2c(master, sda=PIN_B0, sci=PIN_B1
```

```
#use i2c(slave, sda=PIN_C4, sci=PIN_C3
    address=0xa0, FORCE_HW
```

```
#use i2c(master, sci=PIN_B0, sda=PIN_B1, fast=450000)
//sets the target speed to 450 KBSP
```

See Also:

[i2c_poll](#), [i2c_speed](#), [i2c_start](#), [i2c_stop](#), [i2c_slaveaddr](#), [i2c_isr_state](#), [i2c_write](#), [i2c_read](#), [I2C Overview](#)

#use profile()**Syntax:**

#use profile (**options**)

Elements:

option - may be any of the following separated by a comma:

ICD - (Default) configures code profiler to use the ICD connection.

TIMER1 - (optional) if specified, the code profiler run-time on the microcontroller will use the Timer1 peripheral as a timestamp for all profile events. If not specified, the code profiler tool will use the PC clock, which may be accurate for fast events.

BAUD=x - (optional) if specified, will use a different baud rate between the microcontroller and the code profiler tool. This may be required on slow microcontrollers to attempt to use a slower baud rate.

Description:

This directs the compiler to add the code profiler run-time in the microcontroller and configure the link and clock.

Example Files:

[ex_profile.c](#)

Examples:

```
#profile(ICD, TIMER1, baud=9600)
```

See Also:

[#profile\(\)](#), [profileout\(\)](#), [Code Profile overview](#)

#use pwm()**Syntax:**

#use pwm (**options**)

Elements:

option - may be any of the following separated by a comma:

PWMx or CCPx - Selects the CCP to use, **x** being the module to use.

[PCD] PWMx or OCx - Selects the Output Compare module, **x** being the module number to use.

OUTPUT=PIN_xx - Selects the PWM pin to use, pin must be one of the CCP pins. If device has remappable pins compiler will assign specified pin to specified CCP module. If CCP module not specified it will assign remappable pin to first available module.

[PCD] OUTPUT=PIN_xx - Selects the PWM pin to use, pin must be one of the OC pins. If device has remappable pins compiler will assign specified pin to specified OC module. If OC module not specified it will assign remappable pin to first available module.

TIMER=x - Selects timer to use the PWM module, default if not specified is Timer2.

FREQUENCY=x - Sets the period of PWM based off specified value, should not be used if PERIOD is already specified. If frequency can't be achieved exactly compiler will generate a message specifying the exact frequency and period of PWM. If neither FREQUENCY or PERIOD is specified, the period defaults to maximum possible period with maximum resolution and compiler will generate a message specifying the frequency and period of PWM, or if using same timer as previous stream instead of setting to maximum possible it will be set to the same as previous stream. If using same timer as previous stream and frequency is different compiler will generate an error.

Period=x - Sets the period of PWM, should not be used if FREQUENCY is already specified. If period can't be achieved exactly compiler will generate a message specifying the exact period and frequency of PWM. If neither PERIOD or FREQUENCY is specified, the period defaults to maximum possible period with maximum resolution and compiler will generate a message specifying the frequency and period of PWM, or if using same timer as previous stream instead of setting to maximum possible it will be set to the same as previous stream. If using same timer as previous stream and period is different compiler will generate an error.

BITS=x - Sets the resolution of the the duty cycle, if period or frequency is specified will adjust the period to meet set resolution and will generate a message specifying the frequency and duty of PWM. If period or frequency not specified will set period to maximum possible for specified resolution and compiler will generate a message specifying the frequency and period of PWM, unless using same timer as previous then it will generate an error if resolution is different then previous stream. If not specified, then frequency, period or previous stream using same timer sets the resolution.

DUTY=x - Selects the duty percentage of PWM. Default, if not specified, is 50%.

PWM_ON - Initialize the PWM in the ON state. Default state, if not specified, is ***pwm_on*** or ***pwm_off***.

PWM_OFF - Initialize the PWM in the OFF state.

STEAM=id - Associates a stream identifier with the PWM signal. The identifier may be used in functions like ***pwm_set_duty_percent()***.

Description:

This directive tells the compiler to setup a PWM on the specified pin using the specified frequency, period, duty cycle and resolution. The **#USE DELAY** directive must appear before this directive can be used. This directive enables use of built-in functions such as ***pwm_set_duty_percent()***, ***pwm_set_frequency()***, ***pwm_set_duty()***, ***pwm_on()*** and ***pwm_off()***.

See Also:

pwm_on(), ***pwm_off()***, ***pwm_set_frequency()***, ***pwm_set_duty_percent()***, ***pwm_set_duty()***

#use rs232

Syntax:

#use rs232 (options)

Elements:

option - may be any of the following separated by a comma:

STREAM=id - Associates a stream identifier with this RS232 port. The identifier may then be used in functions like ***fputc()***.

BAUD=x - Set baud rate to x.

XMIT=pin - Set transmit pin.

RCV=pin - Set receive pin.

FORCE_SW - Generate software serial I/O routines even when UART pins are specified.

BRGH10K - Allow bad baud rates on devices that have baud rate problems.

ENABLE=pin - The specified pin will be high during transmit. This may be used to enable 485 transmit.

DEBUGGER - Indicates this stream is used to send/receive data through a CCS ICD unit. The default pin used is B3, use **XMIT=** and **RCV=** to change the pin used. Both should be the same pin.

RESTART_WDT - Causes ***GETC()*** to clear the WDT as it waits for a character.

INVERT - Invert the polarity of the serial pins (normally not needed when level converter, such as MAX232). May not be used with internal UART.

PARITY=x - Where x is N, E, or O.

BITS=x - Where **x** is 5-9 (5-7 may not be used with the SCI).

FLOAT_HIGH - The line is not driven high. This is used for open collector outputs.
Bit 6 in RS232_ERRORS is set if the pin is not high at the end of the bit time.

ERRORS - Used for the compiler to keep receive errors in the variable RS232_ERRORS and to reset errors when they occur, RS232_BUFFER_ERRORS when transmit, and RECEIVE_BUFFER are used.

SAMPLE_EARLY - A getc() normally samples data in the middle of a bit time. This option causes the sample to be at the start of a bit time. May not be used with UART.

RETURN=pin - The pin used to read signal back for **FLOAT_HIGH** and **MULTI_MASTER**. The default for **FLOAT_HIGH** is the **XMIT** pin, and for **MULTI_MASTER** the **RCV** pin.

MULTI_MASTER - Uses the RETURN pin to determine if another master on the bus is transmitting at the same time. If a collision is detected bit 6 is set in RS232_ERRORS and all future PUTC's are ignored until bit 6 is cleared. The signal is checked at the start and end of a bit time. May not be used with the UART.

LONG_DATA - Makes getc() return an int16 and putc() accept an int16. This is for 9 bit data formats.

DISABLE_INTS - Will cause interrupts to be disabled when the routines get or put a character. This prevents character distortion for software implemented I/O and prevents interaction between I/O in interrupt handlers and the main program when using the UART.

STOP=x - Used to set the number of stop bits (default is 1). This works for both UART and non-UART ports.

TIMEOUT=x - To set the time getc() waits for a byte in milliseconds. If no character comes in within this time the RS232_ERRORS is set to 0 as well as the return value from getc(). This works for both UART and non-UART ports.

SYNC_SLAVE - Makes the RS232 line a synchronous slave, making the receive pin a clock in, and the data pin the data in/out.

SYNC_MASTER - Makes the RS232 line a synchronous master, making the receive pin a clock out, and the data pin the data in/out.

SYNC_MASTER_CONT - Makes the RS232 line a synchronous master mode in continuous receive mode. The receive pin is set as a clock out, and the data pin is set as the data in/out.

UART1 - Sets the XMIT= and RCV= to the device's first hardware UART.

UART2 - Sets the XMIT= and RCV= to the chips second hardware UART.

UART3 - Sets the XMIT= and RCV= to the chips third hardware UART.

UART4 - Sets the XMIT= and RCV= to the chips fourth hardware UART.

[PCD] UART1A - Uses alternate UART pins.

[PCD] UART2A - Uses alternate UART pins.

NOINIT - No initialization of the UART peripheral is performed. Useful for dynamic control of the UART baud rate or initializing the peripheral manually at a later point in the program's run time. If this option is used, then `setup_uart()` needs to be used to initialize the peripheral. Using a serial routine (such as `getc()` or `putc()`) before the UART is initialized will cause undefined behavior.

ICD - Indicates this stream uses the ICD in a special pass through mode to send/receive serial data to/from the PC. The ICSP clock line is the device's receive pin (usually B6), and the ICSP data line is the transmit pin (usually B7). The default transmit pin is the device's ICSPDAT/PGD pin and the default receive pin is the device's ICSPCLK/PGC pin. Use XMIT= and RCV= to change the pins used.

MAX_ERROR=x - Specifies the max error percentage the compiler can set the RS232 baud rate from the specified baud before generating an error. Defaults to 3% if not specified.

serial buffer options:

RECEIVE_BUFFER=x - Size in bytes of UART circular receive buffer, default if not specified is zero. Uses an interrupt to receive data, supports RDA interrupt or external interrupts.

TRANSMIT_BUFFER=x - Size in bytes of UART circular transmit buffer, default if not specified is zero.

TXISR - If TRANSMIT_BUFFER is greater then zero specifies using TBE interrupt for transmitting data. Default is NOTXISR if TXISR or NOTXISR is not specified. TXISR option can only be used when using hardware UART.

NOTXISR - If TRANSMIT_BUFFER is greater then zero specifies to not use TBE interrupt for transmitting data. Default is NOTXISR if TXISR or NOTXISR is not specified and XMIT_BUFFER is greater then zero.

flow control options:

RTS=PIN_xx - Pin to use for RTS flow control. When using FLOW_CONTROL_MODE this pin is driven to the active level when it is ready to receive more data. In SIMPLEX_MODE the pin is driven to the

active level when it has data to transmit. FLOW_CONTROL_MODE can only be use when using RECEIVE_BUFFER.

RTS_LEVEL=x - Specifies the active level of the RTS pin, HIGH is active high and LOW is active low. Defaults to LOW if not specified.

CTS=PIN_xx - Pin to use for CTS flow control. In both FLOW_CONTROL_MODE and SIMPLEX_MODE this pin is sampled to see if it clear to send data. If pin is at active level and there is data to send it will send next data byte.

CTS_LEVEL=x - Specifies the active level of the CTS pin, HIGH is active high and LOW is active low. Default to LOW if not specified.

FLOW_CONTROL_MODE - Specifies how the RTS pin is used. For FLOW_CONTROL_MODE the RTS pin is driven to the active level when ready to receive data. Defaults to FLOW_CONTROL_MODE when neither FLOW_CONTROL_MODE or SIMPLEX_MODE is specified. If RTS pin is not specified then this option is not used.

SIMPLEX_MODE - Specifies how the RTS pin is used. For SIMPLEX_MODE the RTS pin is driven to the active level when it has data to send. Defaults to FLOW_CONTROL_MODE when neither FLOW_CONTROL_MODE or SIMPLEX_MODE is specified. If RTS pin is not specified then this option is not used.

Description:

This directive tells the compiler the baud rate and pins used for serial I/O. This directive takes effect until another RS232 directive is encountered. The #USE DELAY directive must appear before this directive can be used. This directive enables use of built-in functions such as GETC, PUTC, and PRINTF. The functions created with this directive are exported when using multiple compilation units. To access the correct function use the stream identifier.

When using parts with built-in SCI (*[PCD]* UART) and the SCI (*[PCD]* UART) pins are specified, the SCI will be used. If a baud rate cannot be achieved within 3% of the desired value using the current clock rate, an error will be generated. The definition of the RS232_ERRORS is as follows:

No UART:

- Bit 7 is 9th bit for 9 bit data mode (get and put).
- Bit 6 set to one indicates a put failed in float high mode.

With a UART:

- Used only by get:
- Copy of RSTA register except:
- Bit 0 is used to indicate a parity error.

Definition of the RS232_BUFFER_ERRORS variable is as follows:

- Bit 0 UART Receive overrun error occurred.
- Bit 1 Receive Buffer overflowed.
- Bit 2 Transmit Buffer overflowed.

Warning: The device UART will shut down on overflow (3 characters received by the hardware with a GETC() call). The "ERRORS" option prevents the shutdown by detecting the condition and resetting the UART.

Example Files:

[ex_cust.c](#)

Examples:

```
#use rs232 (baud=9600,xmit=PIN_A2,rcv=PIN_A3)
```

See Also:

[getc\(\)](#), [putc\(\)](#), [printf\(\)](#), [setup_uart\(\)](#), [RS232 I/O overview](#), [kbhit\(\)](#), [puts\(\)](#), [putc_send\(\)](#), [rcv_buffer_bytes\(\)](#), [tx_buffer_bytes\(\)](#), [rcv_buffer_full\(\)](#), [tx_buffer_full\(\)](#), [tx_buffer_available\(\)](#)

use rtos

(The RTOS is only included with the PCW and PCWH packages.)

The CCS Real Time Operating System (RTOS) allows a PIC micro controller to run regularly scheduled tasks without the need for interrupts. This is accomplished by a function (RTOS_RUN()) that acts as a dispatcher. When a task is scheduled to run, the dispatch function gives control of the processor to that task. When the task is done executing or does not need the processor anymore, control of the processor is returned to the dispatch function which then will give control of the processor to the next task that is scheduled to execute at the appropriate time. This process is called cooperative multi-tasking.

Syntax:

```
#use rtos (options)
```

Elements:

option - may be any of the following separated by a comma:

timer=X - Where x is 0-4 specifying the timer used by the RTOS.

minor_cycle=time - Where time is a number followed by s, ms, us, ns. This is the longest time any task will run. Each task's execution rate must be a multiple of this time. The compiler can calculate this if it is not specified.

statistics - Maintain min, max, and total time used by each task.

Description:

This directive tells the compiler which timer on the PIC to use for monitoring and when to grant control to a task. Changes to the specified timer's prescaler will effect the rate at which tasks are executed.

This directive can also be used to specify the longest time that a task will ever take to execute with the `minor_cycle` option. This simply forces all task execution rates to be a multiple of the `minor_cycle` before the project will compile successfully. If the this option is not specified the compiler will use a `minor_cycle` value that is the smallest possible factor of the execution rates of the RTOS tasks.

If the statistics option is specified then the compiler will keep track of the minimum processor time taken by one execution of each task, the maximum processor time taken by one execution of each task, and the total processor time used by each task.

When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

Examples:

```
#use rtos(timer=0,minor_cycle=20ms)
```

See Also:

[#TASK](#)

#use spi**Syntax:**

```
#use spi (options)
```

Elements:

option - may be any of the following separated by a comma:

MASTER - Set the device as the master. (default).

SLAVE - Set the device as the slave.

BAUD=n - Target bits per second, default is as fast as possible.

CLOCK_HIGH=n - High time of clock in us (not needed if BAUD= is used).
(default=0).

CLOCK_LOW=n - Low time of clock in us (not needed if BAUD= is used).
(default=0).

DI=pin - Optional pin for incoming data.

DO=pin - Optional pin for outgoing data.

CLK=pin - Clock pin.

MODE=n - The mode to put the SPI bus.

ENABLE=pin - Optional pin to be active during data transfer.

LOAD=pin - Optional pin to be pulsed active after data is transferred.

DIAGNOSTIC=pin - Optional pin to the set high when data is sampled.

SAMPLE_RISE - Sample on rising edge.

SAMPLE_FALL - Sample on falling edge (default).

BITS=n - Max number of bits in a transfer. (default=32)

SAMPLE_COUNT=n - Number of samples to take (uses majority vote). (default=1)

LOAD_ACTIVE=n - Active state for LOAD pin (0, 1).

ENABLE_ACTIVE=n - Active state for ENABLE pin (0, 1). (default=0)

IDLE=n - Inactive state for CLK pin (0, 1). (default=0)

ENABLE_DELAY=n - Time in us to delay after ENABLE is activated. (default=0)

DATA_HOLD=n - Time between data change and clock change.

LSB_FIRST - LSB is sent first.

MSB_FIRST - MSB is sent first. (default)

STREAM=id - Specify a stream name for this protocol.

SPI1 - Use the hardware pins for SPI Port 1.

SPI2 - Use the hardware pins for SPI Port 2.

[PCD] SPI3 - Use the hardware pins for SPI Port 3

[PCD] SPI4 - Use the hardware pins for SPI Port 4

FORCE_SW - Use a software implementation even when hardware pins are specified.

FORCE_HW - Use the pic hardware SPI.

NOINIT - Do not initialize the hardware SPI Port.

[PCD] XFER16 - Use 16-bit transfers instead of two 8-bit transfers.

Description:

The SPI library contains functions to implement an SPI bus. After setting all of the proper parameters in `#USE SPI`, the `spi_xfer()` function can be used to both transfer and receive data on the SPI bus.

The SPI1 and SPI2 options will use the SPI hardware onboard the PIC. The most common pins present on hardware SPI are: DI, DO, and CLK. These pins don't need to

be assigned values through the options; the compiler will automatically assign hardware-specific values to these pins. Consult your PIC's data sheet as to where the pins for hardware SPI are. If hardware SPI is not used, then software SPI will be used. Software SPI is much slower than hardware SPI, but software SPI can use any pins to transfer and receive data other than just the pins tied to the PIC's hardware SPI pins.

The MODE option is more or less a quick way to specify how the stream is going to sample data. MODE=0 sets IDLE=0 and SAMPLE_RISE. MODE=1 sets IDLE=0 and SAMPLE_FALL. MODE=2 sets IDLE=1 and SAMPLE_FALL. MODE=3 sets IDLE=1 and SAMPLE_RISE. There are only these 4 MODEs.

SPI cannot use the same pins for DI and DO. If needed, specify two streams: one to send data and another to receive data.

The pins must be specified with DI, DO, CLK or SPIx, all other options are defaulted as indicated above.

See Also:

[spi_xfer\(\)](#)

#use standard io**Syntax:**

#use standard_io (*port*)

Elements:

port - is A, B, C, D, E, F, G, H, J or ALL

Description:

This directive affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another #USE XXX_IO directive is encountered. The standard method of doing I/O will cause the compiler to generate code to make an I/O pin either input or output every time it is used. On the 5X processors this requires one byte of RAM for every port set to standard I/O.

Standard_io is the default I/O method for all ports.

When linking multiple compilation units be aware this directive only applies to the current compilation unit.

Example Files:

[ex_cust.c](#)

Examples:

```
#use standard_io(A)
```

See Also:

#USE FAST_IO, #USE FIXED_IO, General Purpose I/O

#use timer**Syntax:**

```
#use timer (options)
```

Elements:

TIMER=x - Sets the timer to use as the tick timer. x is a valid timer that the PIC has. Default value is 1 for Timer 1.

TICK=xx - Sets the desired time for 1 tick. xx can be used with ns(nanoseconds), us (microseconds), ms (milliseconds), or s (seconds). If the desired tick time can't be achieved it will set the time to closest achievable time and will generate a warning specifying the exact tick time. The default value is 1us.

BITS=x - Sets the variable size used by the get_ticks() and set_ticks() functions for returning and setting the tick time. x can be 8 for 8 bits, 16 for 16 bits or 32 for 32bits. The default is 32 for 32 bits.

[PCD] BITS=x - Sets the variable size used by the get_ticks() and set_ticks() functions for returning and setting the tick time. x can be 8 for 8 bits, 16 for 16 bits, 32 for 32bits or 64 for 64 bits. The default is 32 for 32 bits.

ISR - Uses the timer's interrupt to increment the upper bits of the tick timer. This mode requires the the global interrupt be enabled in the main program.

NOISR - The get_ticks() function increments the upper bits of the tick timer. This requires that the get_ticks() function be called more often then the timer's overflow rate. NOISR is the default mode of operation.

STREAM=id - Associates a stream identifier with the tick timer. The identifier may be used in functions like get_ticks().

DEFINE=id - Creates a define named id which specifies the number of ticks that will occur in one second. Default define name if not specified is TICKS_PER_SECOND. Define name must start with an ASCII letter 'A' to 'Z', an ASCII letter 'a' to 'z' or an ASCII underscore ('_').

COUNTER or COUNTER=x - Sets up specified timer as a counter instead of timer. x specifies the prescallar to setup counter with, default is1 if x is not specified specified. The function get_ticks() will return the current count and the function set_ticks() can be used to set count to a specific starting value or to clear counter.

Description:

This directive creates a tick timer using one of the PIC's timers. The tick timer is initialized to zero at program start. This directive also creates the define TICKS_PER_SECOND as a floating point number, which specifies that number of ticks that will occur in one second.

Examples:

```
#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)

unsigned int16 tick_difference(unsigned int16 current, unsigned int16
previous) {

    return(current - previous);
}

void main(void) {
    unsigned int16 current_tick, previous_tick;
    current_tick = previous_tick = get_ticks();
    while(TRUE) {
        current_tick = get_ticks();
        if(tick_difference(current_tick, previous_tick) > 1000) {
            output_toggle(PIN_B0);
            previous_tick = current_tick;
        }
    }
}
```

See Also:

get_ticks(), set_ticks()

#use touchpad**Syntax:**

#use touchpad (options)

Elements:

RANGE=x - Sets the oscillator charge/discharge current range. If x is L, current is nominally 0.1 microamps. If x is M, current is nominally 1.2 microamps. If x is H, current is nominally 18 microamps. Default value is H (18 microamps).

THRESHOLD=x - x is a number between 1-100 and represents the percent reduction in the nominal frequency that will generate a valid key press in software. Default value is 6%.

SCANTIME=xxMS - *xx is the number of milliseconds used by the microprocessor to scan for one key press. If utilizing multiple touch pads, each pad will use xx milliseconds to scan for one key press. Default is 32ms.*

PIN=char - *If a valid key press is determined on "PIN", the software will return the character "char" in the function touchpad_getc(). (Example: PIN_B0='A')*

SOURCETIME=xxus - (CTMU only) **xx** is the number of microseconds each pin is sampled for by ADC during each scan time period. Default is 10us.

Description:

This directive will tell the compiler to initialize and activate the Capacitive Sensing Module (CSM) or Charge Time Measurement Unit (CTMU) on the microcontroller. The compiler requires use of the TIMER0 and TIMER1 modules for CSM and Timer1 ADC modules for CTMU, and global interrupts must still be activated in the main program in order for the CSM or CTMU to begin normal operation. For most applications, a higher RANGE, lower THRESHOLD, and higher SCANTIME will result better key press detection. Multiple PIN's may be declared in "options", but they must be valid pins used by the CSM or CTMU. The user may also generate a TIMER0 ISR with TIMER0's interrupt occurring every SCANTIME milliseconds. In this case, the CSM's or CTMU's ISR will be executed first.

Examples:

```
#USE TOUCHPAD (THRESHOLD=5, PIN_D5='5', PIN_B0='C')
void main(void) {
    char c;
    enable_interrupts(GLOBAL);

    while(1) {
        c = TOUCHPAD_GETC(); //will wait until a pin is detected
    }                       //if PIN_B0 is pressed, c will have 'C'
                           //if PIN_D5 is pressed, c will have '5'
}
```

See Also:

[touchpad_state\(\)](#), [touchpad_getc\(\)](#), [touchpad_hit\(\)](#)

#warning

Syntax:

#warning *text*

Elements:

text - is optional and may be any text.

Description:

Forces the compiler to generate a warning at the location this directive appears in the file. The text may include macros that will be expanded for the display. This may be used to see the macro expansion. The command may also be used to alert the user to an invalid compile time situation.

To prevent the warning from being counted as a warning, use this syntax:

#warning/information text

Example Files:

ex_psp.c

Examples:

```
#if BUFFER_SIZE<32
#warning Buffer Overflow may occur
#endif
```

See Also:

#ERROR

#word**Syntax:**

#word **id**=x

Elements:

id - is a valid C identifier.

x - is a C variable or a constant

Description:

If the id is already known as a C variable then this will locate the variable at address x. In this case the variable type does not change from the original definition. If the id is not known a new C variable is created and placed at address x with the type int16

Warning: In both cases memory at x is not exclusive to this variable. Other variables may be located at the same location. In fact when x is a variable, then id and x share the same memory location.

Examples:

```
#word data = 0x0800

struct {
    int lowerByte : 8;
    int upperByte : 8;
```

```

} control_word;
#word control_word = 0x85
...
control_word.upperByte = 0x42;

[PCD]
#word data = 0x0860
struct {
    short C;
    short Z;
    short OV;
    short N;
    short RA;
    short IPL0;
    short IPL1;
    short IPL2;
    int upperByte : 8;
} status_register;
#word status_register = 0x42
...
short zero = status_register.Z;

```

See Also:

[#bit](#), [#byte](#), [#locate](#), [#reserve](#), [Named Registers](#), [Type Specifiers](#), [Type Qualifiers](#), [Enumerated Types](#), [Structures & Unions](#), [Typedef](#)

#zero local ram**Syntax:**

```
#zero_local_ram
```

Elements:

None

Description:

This directive causes the compiler to initialize all local variables with no initializer to zero every time the function is invoked. Local variables with an initializer (= after the declaration) are not affected.

Example Files:

None

Examples:

```

#zero_local_ram
void sample_adc(void {
    int raw_data[1-];           // both raw_data and

```

```
int sum;                                // sum zero'ed on each call
    . . .
}
```

See Also:

[#zero_ram](#), [#fill_rom](#), [static](#)

#zero_ram**Syntax:**

`#zero_ram`

Elements:

None

Description:

This directive zero's out all of the internal registers that may be used to hold variables before program execution begins.

Example Files:

[ex_cust.c](#)

Examples:

```
#zero_ram
void main() {
}
```

BUILT-IN FUNCTIONS

The CCS compiler provides a lot of built-in functions to access and use the PIC microcontroller's peripherals. This makes it very easy for the users to configure and use the peripherals without going into in depth details of the registers associated with the functionality. The functions categorized by the peripherals associated with them are listed on the next page. Click on the function name to get a complete description and parameter and return value descriptions.

abs()

Syntax:

value = abs(x)

Parameters:

x is a signed 8, 16, or 32 bit int or a float

[PCD] x is any integer or float type.

Returns:

Same type as the parameter.

Function:

Computes the absolute value of a number.

Availability:

All devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
signed int target, actual;
...
error = abs(target-actual);
```

See Also:

labs()

sin() cos() tan() asin() acos() atan() sinh() cosh() tanh() atan2()

Syntax:

```
val = sin (rad)
val = cos (rad)
val = tan (rad)
rad = asin (val)
rad1 = acos (val)
rad = atan (val)
rad2=atan2(val, val)
result=sinh(value)
result=cosh(value)
result=tanh(value)
```

Parameters:

rad is a float representing an angle in Radians -2pi to 2pi.

[PCD] ***rad*** is any float type representing an angle in Radians -2pi to 2pi.

val is a float with the range -1.0 to 1.0.

[PCD] ***val*** is any float type with the range -1.0 to 1.0.

Value is a float

[PCD] ***Value*** is any float type

Returns:

rad - is a float representing an angle in Radians -pi/2 to pi/2

val - is a float with the range -1.0 to 1.0.

rad1 - is a float representing an angle in Radians 0 to pi

rad2 - is a float representing an angle in Radians -pi to pi

Result is a float

[PCD] ***rad*** is a float with a precision equal to ***val*** representing an angle in Radians -pi/2 to pi/2

[PCD] ***val*** is a float with a precision equal to ***rad*** within the range -1.0 to 1.0.

[PCD] ***rad1*** is a float with a precision equal to ***val*** representing an angle in Radians 0 to pi

[PCD] ***rad2*** is a float with a precision equal to ***val*** representing an angle in Radians -pi to pi

[PCD] Result is a float with a precision equal to ***value***

Function:

These functions perform basic Trigonometric functions.

- sin** - returns the sine value of the parameter (measured in radians)
- cos** - returns the cosine value of the parameter (measured in radians)
- tan** - returns the tangent value of the parameter (measured in radians)
- asin** - returns the arc sine value in the range $[-\pi/2, +\pi/2]$ radians
- acos** - returns the arc cosine value in the range $[0, \pi]$ radians
- atan** - returns the arc tangent value in the range $[-\pi/2, +\pi/2]$ radians
- atan2** - returns the arc tangent value of y/x in the range $[-\pi, +\pi]$ radians
- sinh** - returns the hyperbolic sine of x
- cosh** - returns the hyperbolic cosine of x
- tanh** - returns the hyperbolic tangent of x

Note on error handling:

If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Domain error occurs in the following cases:

- asin**: when the argument not in the range $[-1, +1]$
- acos**: when the argument not in the range $[-1, +1]$
- atan2**: when both arguments are zero

Range error occur in the following cases:

- cosh**: when the argument is too large
- sinh**: when the argument is too large

Availability:

All devices

Requires:

#INCLUDE <math.h>

Examples:

```
float phase;
// Output one sine wave
for(phase=0; phase<2*3.141596; phase+=0.01)
    set_analog_voltage( sin(phase)+1 );;
```

Examples Files:

[ex_tank.c](#)

See Also:

[log\(\)](#), [log10\(\)](#), [exp\(\)](#), [pow\(\)](#), [sqrt\(\)](#)

act_status()**Syntax:**

```
status = act_status();
```

Parameters:

```
-----
```

Returns:

Returns the status of the ACT module. See the device's header file for defines that can be and'ed with result.

Function:

Used to get the status of the Active Clock Tuning (ACT) module.

Availability:

Devices with an ACT module. See the device's header file for availability.

Requires:

```
-----
```

Examples:

```
unsigned int8 Status;
int1 ClockLocked;
Status = act_status();
if((Status & ACT_CLOCK_LOCKED) == 0)
    ClockLoded = FALSE;
else
    ClockLocked = TRUE;
```

See Also:

setup_act()

adc_done() adc2_done() adc_done2()**Syntax:**

```
value = adc_done();
[PCD] value = adc_done2();
[PCD] value=adc_done([channel])
```

Parameters:

adc_done(); - Nothing required

[PCD] **adc_done2();** - **channel** is an optional parameter for specifying the channel to check if the conversion is done. If not specified will use channel specified in the last call to `set_adc_channel()`, `read_adc()` or `adc_done()`.

Returns:

A short int. TRUE if the A/D converter is done with conversion, FALSE if it is still busy.

Function:

Can be polled to determine if the A/D has valid data.

Availability:

Only available on devices with built in analog to digital converters

[PCD] Only available for dsPIC33EPxxGSxxx family.

Requires:

Examples:

```
int16 value;
setup_adc_ports(sAN0|sAN1, VSS_VDD);
setup_adc(ADC_CLOCK_DIV_4|ADC_TAD_MUL_8);
set_adc_channel(0);
read_adc(ADC_START_ONLY);

int1 done = adc_done();
while(!done) {
    done = adc_done();
}
value = read_adc(ADC_READ_ONLY);
printf("A/C value = %LX\n\r", value);
}
```

See Also:

[setup_adc\(\)](#), [set_adc_channel\(\)](#), [setup_adc_ports\(\)](#), [read_adc\(\)](#), [ADC Overview](#)

adc_read()**Syntax:**

result=adc_read(register)

Parameters:

Register - ADC register to read:

- `adc_result`
- `adc_accumulator`
- `adc_filter`

Returns:

int8 or in16 read from the specified register. Return size depends on which register is being read. For example, ADC_RESULT register is 16 bits and ADC_COUNT register is 8-bits.

Function:

Reads one of the Analog-to-Digital Converter with Computation (ADC2) Module registers.

Availability:

All devices with an ADC2 Module

Requires:

Constants defined in the device's .h file

Examples:

```
FilteredResult=adc_read(ADC_FILTER);
```

See Also:

[ADC Overview](#), [setup_adc\(\)](#), [setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#), [#DEVICE](#), [adc_write\(\)](#), [adc_status\(\)](#), [set_adc_trigger\(\)](#)

adc_status()**Syntax:**

```
status=adc_status()
```

Parameters:

Nothing required

Returns:

int8 value of the ADSTAT register

Function:

Read the current value of the ADSTAT register of the Analog-to-Digital Converter with Computation (ADC2) Module.

Availability:

All devices with an ADC2 Module

Requires:

Examples:

```
while ((adc_status() & ADC_UPDATING)==0);  
  
Average=adc_read(ADC_FILTER);
```

See Also:

[ADC Overview](#), [setup_adc\(\)](#), [setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#),
[#DEVICE](#), [adc_read\(\)](#), [adc_write\(\)](#), [set_adc_trigger\(\)](#)

adc_write()**Syntax:**

adc_write(**register**, **value**)

Parameters:

register - ADC register to write:

- ADC_REPEAT
- ADC_SET_POINT
- ADC_LOWER_THRESHOLD
- ADC_UPPER_THRESHOLD

Returns:

Undefined

Function:

Write one of the Analog-to-Digital Converter with Computation (ADC2) Module registers.

Availability:

All devices with an ADC2 Module

Requires:

Constants defined in the device's .h file

Examples:

```
adc_write(ADC_SET_POINT, 300);
```

See Also:

[ADC Overview](#), [setup_adc\(\)](#), [setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#),
[#DEVICE](#), [adc_read\(\)](#), [adc_status\(\)](#), [set_adc_trigger\(\)](#)

assert()**Syntax:**

assert (**condition**);

Parameters:

condition is any relational expression

Returns:

Function:

This function tests the condition and if FALSE will generate an error message on STDERR (by default the first USE RS232 in the program). The error message will include the file and line of the assert(). No code is generated for the assert() if you #define NDEBUG. In this way you may include asserts in your code for testing and quickly eliminate them from the final program.

Availability:

All Devices

Requires:

assert.h and #USE RS232

Examples:

```
    assert( number_of_entries<TABLE_SIZE );

// If number_of_entries is >= TABLE_SIZE then
// the following is output at the RS232:
// Assertion failed, file myfile.c, line 56
```

See Also:

[#USE RS232](#), [RS232 I/O Overview](#)

atof()**Syntax:**

atof(string);

Parameters:

string is a pointer to a null terminated string of characters.

Returns:

Result is a floating point number

Function:

Converts the string passed to the function into a floating point representation. If the result cannot be represented, the behavior is undefined. This function also handles E format numbers.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
char string [10];
float32 x;

strcpy (string, "12E3");
x = atoe(string);
// x is now 12000.00
```

See Also:

[atoi\(\)](#), [atol\(\)](#), [atoi32\(\)](#), [atof\(\)](#), [printf\(\)](#)

atof() atof48() atof64() strtof48()**Syntax:**

result = atof (*string*)

[PCD] Or

result = atof48(*string*)

or

result=atof64(*string*)

or

result=strtof48(*string*))

Parameters:

string is a pointer to a null terminated string of characters.

Returns:

Result is a floating point number

[PCD] Result is a floating point number in single, extended or double precision format

Function:

Converts the string passed to the function into a floating point representation. If the result cannot be represented, the behavior is undefined.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
char string [10];
float x;

strcpy (string, "123.456");
x = atof(string);
// x is now 123.456
```

Example Files:

ex_tank.c

See Also:

atoi(), atol(), atoi32(), printf()

atoi() atol() atoi32() atol32() atoi48() atoi64()

Syntax:

```
ivalue = atoi(string)
ivalue = atol(string)
i32value = atoi32(string)
i32value = atol32(string)
[PCD] i48value = atoi48(string);
[PCD] i64value = atoi64(string);
```

Parameters:

string - is a pointer to a null terminated string of characters.

Returns:

ivalue is an 8 bit int
 ivalue is a 16 bit int
 i32value is a 32 bit int
 [PCD] i48value is a 48 bit int
 [PCD] i64value is a 64 bit int

Function:

Converts the string passed to the function into an *int* representation. Accepts both decimal and hexadecimal argument. If the result cannot be represented, the behavior is undefined.

Availability:

All devices

Requires:

#INCLUDE<stdlib.h>

Examples:

```
char string[10];
int x;

strcpy(string, "123");
x = atoi(string);      // x is now 123
```

Example Files:

input.c

See Also:

printf()

at_clear_interrupts()**Syntax:**

at_clear_interrupts(interrupts);

Parameters:

interrupts - an 8-bit constant specifying which AT interrupts to disable. The constants are defined in the device's header file as:

- AT_PHASE_INTERRUPT
- AT_MISSING_PULSE_INTERRUPT
- AT_PERIOD_INTERRUPT
- AT_CC3_INTERRUPT
- AT_CC2_INTERRUPT
- AT_CC1_INTERRUPT

Returns:

Function:

To disable the Angular Timer interrupt flags. More than one interrupt can be cleared at a time by or'ing multiple constants together in a single call, or calling function multiple times for each interrupt to clear.

Availability:

All Devices with an AT module

Requires:

Constants defined in the device's header file

Examples:

```
#INT-AT1
void __ISR(void) {
    if (at_interrupt_active(AT_PERIOD_INTERRUPT))
    {
        handle_period_interrupt();
        at_clear_interrupts(AT_PERIOD_INTERRUPT);
    }
    if (at_interrupt_active(AT_PHASE_INTERRUPT);
    {
        handle_phase_interrupt();
        at_clear_interrupts(AT_PHASE_INTERRUPT);
    }
}
```

See Also:

at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(),
at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(),
at_set_set_point(), at_get_set_point(), at_get_set_point_error(),
at_enable_interrupts(), at_disable_interrupts(), at_interrupt_active(), at_setup_cc(),
at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_disable_interrupts()**Syntax:**

`at_disable_interrupts(interrupts);`

Parameters:

interrupts - an 8-bit constant specifying which AT interrupts to disable. The constants are defined in the device's header file as:

- AT_PHASE_INTERRUPT
- AT_MISSING_PULSE_INTERRUPT
- AT_PERIOD_INTERRUPT
- AT_CC3_INTERRUPT
- AT_CC2_INTERRUPT
- AT_CC1_INTERRUPT

Returns:

Function:

To disable the Angular Timer interrupts. More than one interrupt can be disabled at a time by or'ing multiple constants together in a single call, or calling function multiple times for each interrupt to be disabled.

Availability:

All Devices with an AT module

Requires:

Constants defined in the device's header file

Examples:

```
at_disable_interrupts(AT_PHASE_INTERRUPT);
at_disable_interrupts(AT_PERIOD_INTERRUPT|AT_CC1_INTERRUPT);
```

See Also:

at set resolution(), at get resolution(), at set missing pulse delay(),
at get missing pulse delay(), at get period(), at get phase counter(),
at set set point(), at get set point(), at get set point error(),
at enable interrupts(), at clear interrupts(), at interrupt active(), at setup cc(),
at set compare time(), at get capture(), at get status(), setup at()

at enable interrupts()

Syntax:

```
at_enable_interrupts(interrupts);
```

Parameters:

interrupts - an 8-bit constant specifying which AT interrupts to enable. The constants are defined in the device's header file as:

- AT_PHASE_INTERRUPT
- AT_MISSING_PULSE_INTERRUPT
- AT_PERIOD_INTERRUPT
- AT_CC3_INTERRUPT
- AT_CC2_INTERRUPT
- AT_CC1_INTERRUPT

Returns:

Function:

To enable the Angular Timer interrupts. More than one interrupt can be enabled at a time by or'ing multiple constants together in a single call, or calling function multiple times for each interrupt to be enabled.

Availability:

All Devices with an AT module

Requires:

Constants defined in the device's header file

Examples:

```
at_enable_interrupts(AT_PHASE_INTERRUPT);
at_enable_interrupts(AT_PERIOD_INTERRUPT|AT_CC1_INTERRUPT);
```

See Also:

```
setup_at(), at_set_resolution(), at_get_resolution(),
at_set_missing_pulse_delay(), at_get_missing_pulse_delay(),
at_get_phase_counter(), at_set_set_point(), at_get_set_point(),
at_get_set_point(), at_get_set_point_error(),
at_disable_interrupts(), at_clear_interrupts(),
at_interrupt_active(), at_setup_cc(), at_set_compare_time(),
at_get_capture(), at_get_status()
```

at_get_capture()**Syntax:**

```
result=at_get_capture(which);;
```

Parameters:

which - an 8-bit constant specifying which AT Capture/Compare module to get the capture time from, can be 1, 2 or 3.

Returns:

A 16-bit integer

Function:

To get one of the Angular Timer Capture/Compare modules capture time.

Availability:

All Devices with an AT module

Requires:

Examples:

```
result1=at_get_capture(1);
result2=at_get_capture(2);
```

See Also:

```
setup_at(), at_set_resolution(), at_get_resolution(),
at_set_missing_pulse_delay(), at_get_missing_pulse_delay(),
at_get_phase_counter(), at_set_set_point(), at_get_set_point(),
at_get_set_point(), at_get_set_point_error(),
at_enable_interrupts(), at_disable_interrupts(),
at_clear_interrupts(), at_interrupt_active(), at_setup_cc(),
at_set_compare_time(), at_get_status()
```

at_get_missing_pulse_delay()**Syntax:**

```
result=at_get_missing_pulse_delay();
```

Parameters:

```
-----
```

Returns:

A 16-bit integer

Function:

To setup the Angular Timer Missing Pulse Delay

Availability:

All Devices with an AT module

Requires:

```
-----
```

Examples:

```
result=at_get_missing_pulse_delay();
```

See Also:

at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_period(),
at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(),
at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(),
at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_get_period()**Syntax:**

```
result=at_get_period();
```

Parameters:

```
-----
```

Returns:

A 16-bit integer. The MSB of the returned value specifies whether the period counter rolled over one or more times. 1 - counter rolled over at least once, 0 - value returned is valid.

Function:

To get one of the Angular Timer Measure Period.

Availability:

All Devices with an AT module

Requires:

```
-----
```

Examples:

```
result=at_get_period();
```

See Also:

[at_set_resolution\(\)](#), [at_get_resolution\(\)](#), [at_set_missing_pulse_delay\(\)](#),
[at_get_missing_pulse_delay\(\)](#), [at_get_phase_counter\(\)](#), [at_set_set_point\(\)](#),
[at_get_set_point\(\)](#), [at_get_set_point_error\(\)](#), [at_enable_interrupts\(\)](#),
[at_disable_interrupts\(\)](#), [at_clear_interrupts\(\)](#), [at_interrupt_active\(\)](#), [at_setup_cc\(\)](#),
[at_set_compare_time\(\)](#), [at_get_capture\(\)](#), [at_get_status\(\)](#), [setup_at\(\)](#)

at_get_phase_counter()**Syntax:**

```
result=at_get_phase_counter();
```

Parameters:

```
-----
```

Returns:

A 16-bit integer.

Function:

To get one of the Angular Timer Phase Counter.

Availability:

All Devices with an AT module

Requires:

Examples:

```
result=at_get_phase_counter();
```

See Also:

[at set resolution\(\)](#), [at get resolution\(\)](#), [at set missing pulse delay\(\)](#),
[at get missing pulse delay\(\)](#), [at get period\(\)](#), [at set set point\(\)](#),
[at get set point\(\)](#), [at_get_set_point_error\(\)](#), [at enable interrupts\(\)](#),
[at disable interrupts\(\)](#), [at clear interrupts\(\)](#), [at interrupt active\(\)](#), [at setup cc\(\)](#),
[at set compare time\(\)](#), [at get capture\(\)](#), [at get status\(\)](#), [setup at\(\)](#)

at get resolution()**Syntax:**

```
result=at_get_resolution();
```

Parameters:

Returns:

A 16-bit integer.

Function:

To get one of the Angular Timer Resolution.

Availability:

All Devices with an AT module

Requires:

Examples:

```
result=at_get_resolution();
```

See Also:

at set resolution(), at set missing pulse delay(), at get missing pulse delay(),
at get period(), at get phase counter(), at set set point(), at get set point(),
at_get_set_point_error(), at enable interrupts(), at disable interrupts(),
at clear interrupts(), at interrupt active(), at setup cc(), at set compare time(),
at get capture(), at get status(), setup at()

at get set point()**Syntax:**

```
result=at_get_set_point();
```

Parameters:

Returns:

A 16-bit integer.

Function:

To get one of the Angular Timer Set Point.

Availability:

All Devices with an AT module

Requires:

Examples:

```
result=at_get_set_point();
```

See Also:

at set resolution(), at get resolution(), at set missing pulse delay(),
at get missing pulse delay(), at get period(), at get phase counter(),
at set set point(), at_get_set_point_error(), at enable interrupts(), at disable interrupts(),
at clear interrupts(), at interrupt active(), at setup cc(), at set compare time(),
at get capture(), at get status(), setup at()

at get set point error()**Syntax:**

```
result=at_get_set_point_error();
```

Parameters:

Returns:

A 16-bit integer.

Function:

To get one of the Angular Timer Set Point Error, the error of the measured period value compared to the threshold setting.

Availability:

All Devices with an AT module

Requires:

Examples:

```
result=at_get_set_point_error();
```

See Also:

at set resolution(), at get resolution(), at set missing pulse delay(),
at get missing pulse delay(), at get period(), at get phase counter(),
at set set point(), at get set point(), at enable interrupts(), at disable interrupts(),
at clear interrupts(), at interrupt active(), at setup cc(), at set compare time(),
at get capture(), at get status(), setup at()

at get status()**Syntax:**

```
result=at_get_status();
```

Parameters:

Returns:

An 8-bit integer. The possible results are defined in the device's header file as:

- AT_STATUS_PERIOD_AND_PHASE_VALID
- AT_STATUS_PERIOD_LESS_THEN_PREVIOUS

Function:

To get one of the Angular Timer module.

Availability:

All Devices with an AT module

Requires:

Examples:

```
if((at_get_status() & AT_STATUS_PERIOD_AND_PHASE_VALID) ==
    AT_STATUS_PERIOD_AND_PHASE_VALID
{
    Period=at_get_period();
    Phase=at_get_phase();
}
```

See Also:

[at set resolution\(\)](#), [at get resolution\(\)](#), [at set missing pulse delay\(\)](#),
[at get missing pulse delay\(\)](#), [at get period\(\)](#), [at get phase counter\(\)](#),
[at set set point\(\)](#), [at get set point\(\)](#), [at get set point error\(\)](#), [at enable interrupts\(\)](#),
[at disable interrupts\(\)](#), [at clear interrupts\(\)](#), [at interrupt active\(\)](#), [at setup cc\(\)](#),
[at set compare time\(\)](#), [at get capture\(\)](#), [setup at\(\)](#)

at interrupt active()

Syntax:

result=at_interrupt_active(**interrupt**);

Parameters:

interrupts - an 8-bit constant specifying which AT interrupts to check if its flag is set.

The constants are defined in the device's header file as:

- AT_PHASE_INTERRUPT
- AT_MISSING_PULSE_INTERRUPT
- AT_PERIOD_INTERRUPT
- AT_CC3_INTERRUPT
- AT_CC2_INTERRUPT
- AT_CC1_INTERRUPT

Returns:

TRUE if the specified AT interrupt's flag is set, interrupt is active, or FALSE if the flag is clear, interrupt is not active.

Function:

To check if the specified Angular Timer interrupt flag is set.

Availability:

All Devices with an AT module

Requires:

Examples:

```
#INT-AT1
voidl_isr(void)
{
    if(at_interrupt_active(AT_PERIOD_INTERRUPT))
    {
        handle_period_interrupt();
        at_clear_interrupts(AT_PERIOD_INTERRUPT);
    }
    if(at_interrupt_active(AT_PHASE_INTERRUPT);
    {
        handle_phase_interrupt();
        at_clear_interrupts(AT_PHASE_INTERRUPT);
    }
}
```

See Also:

at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(),
at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(),
at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(),
at_disable_interrupts(), at_clear_interrupts(), at_setup_cc(), at_set_compare_time(),
at_get_capture(), at_get_status(), setup_at()

at_set_compare_time()**Syntax:**

`at_set_compare_time(which, compare_time);`

Parameters:

which - an 8-bit constant specifying which AT Capture/Compare module to set the compare time for, can be 1, 2, or 3.

compare_time - a 16-bit constant or variable specifying the value to trigger an interrupt/output pulse.

Returns:

Function:

To set one of the Angular Timer Capture/Compare module's compare time.

Availability:

All Devices with an AT module

Requires:

Constants defined in the device's header file

Examples:

```
at_set_compare_time(1, 0x1FF);
at_set_compare_time(3, compare_time); }
```

See Also:

[at_set_resolution\(\)](#), [at_get_resolution\(\)](#), [at_set_missing_pulse_delay\(\)](#),
[at_get_missing_pulse_delay\(\)](#), [at_get_period\(\)](#), [at_get_phase_counter\(\)](#),
[at_set_set_point\(\)](#), [at_get_set_point\(\)](#), [at_get_set_point_error\(\)](#), [at_enable_interrupts\(\)](#),
[at_disable_interrupts\(\)](#), [at_clear_interrupts\(\)](#), [at_interrupt_active\(\)](#), [at_setup_cc\(\)](#),
[at_get_capture\(\)](#), [at_get_status\(\)](#), [setup_at\(\)](#)

at_set_missing_pulse_delay()**Syntax:**

```
at_set_missing_pulse_delay(pulse_delay);
```

Parameters:

pulse_delay - a signed 16-bit constant or variable to set the missing pulse delay.

Returns:

Function:

To setup the Angular Timer Missing Pulse Delay

Availability:

All Devices with an AT module

Requires:

Examples:

```
at_set_missing_pulse_delay(pulse_delay);
```

See Also:

at set resolution(), at get resolution(), at get missing pulse delay(), at get period(),
at get phase counter(), at set set point(), at get set point(), at get set point_error(),
at enable interrupts(), at disable interrupts(), at clear interrupts(), at interrupt active(),
at setup cc(), at set compare time(), at get capture(), at get status(), setup at()

at set resolution()**Syntax:**

```
at_set_resolution(resolution);
```

Parameters:

resolution - a 16-bit constant or variable to set the resolution.

Returns:

Function:

To setup the Angular Timer Resolution

Availability:

All Devices with an AT module

Requires:

Examples:

```
at_set_resolution(resolution);
```

See Also:

at get resolution(), at set missing pulse delay(), at get missing pulse delay(),
at get period(), at get phase counter(), at set set point(), at get set point(),
at get set point_error(), at enable interrupts(), at disable interrupts(),
at clear interrupts(), at interrupt active(), at setup cc(), at set compare time(),
at get capture(), at get status(), setup at()

at set set point()**Syntax:**

```
at_set_set_point(set_point);
```

Parameters:

resolution - a 16-bit constant or variable to set the resolution.

Returns:

Function:

To setup the Angular Timer Set Point

Availability:

All Devices with an AT module

Requires:

Examples:

```
at_set_set_point(set_point);
```

See Also:

[at set resolution\(\)](#), [at get resolution\(\)](#), [at set missing pulse delay\(\)](#),
[at get missing pulse delay\(\)](#), [at get period\(\)](#), [at get phase counter\(\)](#),
[at get set_point\(\)](#), [at_get_set_point_error\(\)](#), [at enable interrupts\(\)](#), [at disable interrupts\(\)](#),
[at clear interrupts\(\)](#), [at interrupt active\(\)](#), [at setup cc\(\)](#), [at set compare time\(\)](#),
[at get capture\(\)](#), [at get status\(\)](#), [setup at\(\)](#)

at setup cc()

Syntax:

```
at_setup_cc(which, settings);
```

Parameters:

which - an 8-bit constant specifying which AT Capture/Compare to setup, can be 1, 2 or 3.

settings - a 16-bit constant specifying how to setup the specified AT Capture/Compare module. See the device's header file for all options. Some of the typical options include:

- AT_CC_ENABLED
- AT_CC_DISABLED
- AT_CC_CAPTURE_MODE
- AT_CC_COMPARE_MODE
- AT_CAPTURE_FALLING_EDGE
- AT_CAPTURE_RISING_EDGE

Returns:

Function:

To setup one of the Angular Timer Capture/Compare modules to the specified settings.

Availability:

All Devices with an AT module

Requires:

Constants defined in the device's header file

Examples:

```
at_setup_cc(1,AT_CC_ENABLED|AT_CC_CAPTURE_MODE|
AT_CAPTURE_FALLING_EDGE|AT_CAPTURE_INPUT_ATCAP);

at_setup_cc(2,AT_CC_ENABLED|AT_CC_CAPTURE_MODE|
AT_CC_ACTIVE_HIGH);
```

See Also:

at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(),
at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(),
at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(),
at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(),
at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

bit_clear()

Syntax:

bit_clear(*var*, *bit*)

Parameters:

var may be a any bit variable (any lvalue)

bit is a number 0- 31 63 representing a bit number, 0 is the least significant bit.

Returns:

Undefined

Function:

Simply clears the specified bit (0-7, 0-15 or 0-31) in the given variable. The least significant bit is 0. This function is the similar to: `var &= ~(1<<bit);`

Availability:

All Devices

Requires:

Examples:

```
int x;  
x=5;  
bit_clear(x,2);      // x is now 1
```

Example Files:

ex_patg.c

See Also:

bit_set(), bit_test()

bit_first()**Syntax:**

N = bit_first (*value*, *var*)

Parameters:

value is a 0 to 1 to be shifted in

var is a 16 bit integer

Returns:

An 8-bit integer

Function:

This function sets N to the 0 based position of the first occurrence of value. The search starts from the right or least significant bit.

Availability:

24-bit Devices (PIC24, 30F/33F)

Requires:

Examples:

```
int16 var = 0x0033;  
Int8 N = 0;  
// N = 2  
N = bit_first (0, var);
```

See Also:

shift_right(), shift_left(), rotate_right(), rotate_left()

bit_last()

Syntax:

N = bit_last (*value*, *var*)

N = bit_last(*var*)

Parameters:

value is a 0 to 1 to search for

var is a 16 bit integer

Returns:

An 8-bit integer

Function:

The first function will find the first occurrence of value in the var starting with the most significant bit.

The second function will note the most significant bit of var and then search for the first different bit.

Both functions return a 0 based result.

Availability:

24-bit Devices (PIC24, 30F/33F)

Requires:

Examples:

```

//Bit pattern 11101110 11111111
Int16 var = 0xEEFF;
Int8 N = 0;           //N is assigned 12
N = bit_last (0, var); //N is assigned 12
N = bit_last(var)
```

See Also:

shift_right(), shift_left(), rotate_right(), rotate_left()

bit_set()

Syntax:

bit_set(*var*, *bit*)

Parameters:

var may be any variable (any lvalue)

bit is a number from 0 to the highest bit number in the type, 0 is the least significant bit

Returns:

Undefined

Function:

Sets the specified bit in the given variable. The least significant bit is 0.

This function is the similar to: `var |= (1<<bit);`

For example, for a 16-bit variable, the bit number may be 0-15,

Availability:

All Devices

Requires:

Examples:

```
int x;
x=5;
bit_set(x,3);           // x is now 13
```

Example Files:

[ex_patg.c](#)

See Also:

[bit_clear\(\)](#), [bit_test\(\)](#)

bit_test()**Syntax:**

value = bit_test (*var*, *bit*)

Parameters:

var may be any variable (any lvalue)

bit is a number from 0 to the highest bit number in the type, 0 is the least significant bit

Returns:

0 or 1

Function:

Tests the specified bit in the given variable. The least significant bit is 0.

This function is more efficient than, but otherwise similar to `((var & (1<<bit)) != 0)`

For example, for a 16-bit variable, the bit number may be 0-15,

Availability:

All Devices

Requires:

Examples:

```
if( bit_test(x,3) || !bit_test (x,1) ){    //either bit 3 is 1
                                           //or bit 1 is 0
}

if(data!=0)
    for(i=31;!bit_test(data, i);i-- ) ;    // i now has the most
                                           //significant bit in
data                                           // that is set to a 1
```

Example Files:

[ex_patg.c](#)

See Also:

[bit_clear\(\)](#), [bit_set\(\)](#)

brownout_enable()

Syntax:

brownout_enable (value)

Parameters:

value – TRUE or FALSE

Returns:

Undefined

Function:

Enable or disable the software controlled brownout. Brownout will cause the PIC to reset if the power voltage goes below a specific set-point.

Availability:

This function is only available on devices with a software controlled brownout. This may also require a specific configuration bit/fuse to be set for the brownout to be software controlled.

Requires:

Examples:

```
brownout_enable(TRUE);
```

See Also:

restart_cause()

bsearch()**Syntax:**

```
ip = bsearch (&key, base, num, width, compare)
```

Parameters:

key - Object to search for

base - Pointer to array of search data

num - Number of elements in search data

width - Width of elements in search data

compare - Function that compares two elements in search data

Returns:

bsearch returns a pointer to an occurrence of key in the array pointed to by base. If key is not found, the function returns NULL. If the array is not in order or contains duplicate records with identical keys, the result is unpredictable.

Function:

Performs a binary search of a sorted array.

Availability:

All Devices

Requires:

```
#INCLUDE <stdlib.h>
```

Examples:

```
int nums[5]={1,2,3,4,5};
int compar(const void *arg1,const void *arg2);

void main() {
    int *ip, key;
    key = 3;
    ip = bsearch(&key, nums, 5, sizeof(int), compar);
```

```

}
int compar(const void *arg1,const void *arg2) {
    if ( * (int *) arg1 < ( * (int *) arg2) return -1
    else if ( * (int *) arg1 == ( * (int *) arg2) return 0
    else return 1;
}

```

See Also:qsort()**calloc()****Syntax:**`ptr=calloc(nmem, size)`**Parameters:***nmem* is an integer representing the number of member objects*size* is the number of bytes to be allocated for each one of them.**Returns:**

A pointer to the allocated memory, if any. Returns null otherwise.

Function:The **calloc** function allocates space for an array of *nmem* objects whose size is specified by *size*.

The space is initialized to all bits zero.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```

int * iptr;
iptr=calloc(5,10);    // iptr will point to a block of memory of
                      // 50 bytes all initialized to 0

```

See Also:realloc(), free(), malloc()

ceil()

Syntax:

result = ceil (*value*)

Parameters:

value is a float

[PCD] **value** is any float type

Returns:

A float

[PCD] A float with precision equal to **value**

Function:

Computes the smallest integer value greater than the argument. CEIL(12,67) is 13,00.

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```

// Calculate cost based
/on weight rounded up to the
next pound
cost = ceil( weight ) * DollarsPerPound

```

See Also:

[floor\(\)](#)

clc1_setup_gate() clc2_setup_gate() clc3_setup_gate() clc4_setup_gate()

Syntax:

```

clc1_setup_gate(gate, mode);
clc2_setup_gate(gate, mode);
clc3_setup_gate(gate, mode);
clc4_setup_gate(gate, mode);

```

Parameters:

gate – selects which data gate of the Configurable Logic Cell (CLC) module to setup, value can be 1 to 4.

mode – the mode to setup the specified data gate of the CLC module into. The options are:

- clc_gate_and
- clc_gate_nand
- clc_gate_nor
- clc_gate_or
- clc_gate_clear
- clc_gate_set

Returns:

Undefined

[PCD] Undefined with precision equal to **value**

Function:

Sets the logic function performed on the inputs for the specified data gate.

Availability:

Devices with a CLC module

Requires:

Undefined

Examples:

```
clc1_setup_gate(1, CLC_GATE_AND);  
clc1_setup_gate(2, CLC_GATE_NAND);  
clc1_setup_gate(3, CLC_GATE_CLEAR);  
clc1_setup_gate(4, CLC_GATE_SET);
```

See Also:

setup_clcx(), clcx_setup_input()

clc1_setup_input() clc2_setup_input() clc3_setup_input() clc4_setup_input()

Syntax:

```
clc1_setup_input(input, selection);  
clc2_setup_input(input, selection);  
clc3_setup_input(input, selection);  
clc4_setup_input(input, selection);
```

Parameters:

input – selects which input of the Configurable Logic Cell (CLC) module to setup, value can be 1 to 4.

selection – the actual input for the specified input that is actually connected to the data gates of the CLC module. The options are:

- clc_input_0
- clc_input_1
- clc_input_2
- clc_input_3
- clc_input_4
- clc_input_5
- clc_input_6
- clc_input_7

Returns:

Undefined

Function:

Sets the input for the specified input number that is actually connected to all four data gates of the CLC module. Please refer to the table CLCx DATA INPUT SELECTION in the device's datasheet to determine which of the above selections corresponds to actual input pin or peripheral of the device.

Availability:

Devices with a CLC module

Requires:

Undefined

Examples:

```
clc1_setup_input(1, CLC_INPUT_0);  
clc1_setup_input(2, CLC_INPUT_1);  
clc1_setup_input(3, CLC_INPUT_2);  
clc1_setup_input(4, CLC_INPUT_3);
```

See Also:

setup_clcx(), clcx_setup_gate()

clear_dmt()

Syntax:

```
clear_dmt();
```

Parameters:

Returns:

Function:

Used to clear the Deadman Timer (DMT) peripheral.

Availability:

Only on devices that have the DMT peripheral.

Requires:

Examples:

```
if((dmt_status() & DMT_CLEAR_WINDOW_OPEN) == DMT_CLEAR_WINDOW_OPEN)
    clear_dmt();
```

See Also:

[read_dmt\(\)](#), [disable_dmt\(\)](#), [enable_dmt\(\)](#), [dmt_status\(\)](#), [setup_dmt\(\)](#)

clear_interrupt()**Syntax:**

clear_interrupt(*level*)

Parameters:

level - a constant defined in the devices.h file

Returns:

Undefined

Function:

Clears the interrupt flag for the given level. This function is designed for use with a specific interrupt, thus eliminating the GLOBAL level as a possible parameter. Some chips that have interrupt on change for individual pins allow the pin to be specified like INT_RA1.

Availability:

All Devices

Requires:

Examples:

```
clear_interrupt(int_timer1);
```


See Also:

[enable_interrupts\(\)](#) , [enable_interrupts](#) , [#INT](#) , [#INT](#) , [Interrupts Overview](#)
[disable_interrupts\(\)](#), [interrupt_active\(\)](#)

clear_pwm1_interrupt() **clear_pwm2_interrupt()**
clear_pwm3_interrupt() **clear_pwm4_interrupt()**
clear_pwm5_interrupt() **clear_pwm6_interrupt()**

Syntax:

```
clear_pwm1_interrupt (interrupt)
clear_pwm2_interrupt (interrupt)
clear_pwm3_interrupt (interrupt)
clear_pwm4_interrupt (interrupt)
clear_pwm5_interrupt (interrupt)
clear_pwm6_interrupt (interrupt)
```

Parameters:

interrupt - 8-bit constant or variable. Constants are defined in the device's header file as:

```
pwm_period_interrupt
pwm_duty_interrupt
pwm_phase_interrupt
pwm_offset_interrupt
```

Returns:

Undefined

Function:

Clears one of the above PWM interrupts, multiple interrupts can be cleared by or'ing multiple options together.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
clear_pwm1_interrupt (PWM_PERIOD_INTERRUPT);
clear_pwm1_interrupt (PWM_PERIOD_INTERRUPT | PWM_DUTY_INTERRUPT)
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(),
enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

cog_restart() cog2_restart() cog3_restart() cog4_restart()

Syntax:

```
cog_restart();
cog2_restart();
cog3_restart();
cog4_restart();
```

Parameters:

Returns:

Function:

To restart the Complementary Output Generator (COG) module after an auto-shutdown event occurs, when not using auto-restart option of module.

Availability:

Devices with a COG module

Requires:

Examples:

```
if (cog_status() == COG_AUTO_SHUTDOWN)
    cog_restart();
```

See Also:

setup_cog(), set_cog_dead_band(), set_cog_blanking(), set_cog_phase(), cog_status()

cog_status() cog2_status() cog3_status() cog4_status()

Syntax:

```
value=cog_status();
value=cog2_status();
value=cog3_status();
value=cog4_status();
```

Parameters:

Returns:

value - the status of the COG module

Function:

To determine if a shutdown event occurred on the Complementary Output Generator (COG) module.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
if (cog_status() == COG_AUTO_SHUTDOWN)
    cog_restart();
```

See Also:

setup_cog(), set_cog_dead_band(), set_cog_blanking(), set_cog_phase(), cog_restart()

crc_calc(mode)

Syntax:

```
Result = crc_calc (data,[width]);
Result = crc_calc(ptr,len,[width]);
Result = crc_calc8(data,[width]);
Result = crc_calc8(ptr,len,[width]);
Result = crc_calc16(data,[width]);           //same as crc_calc( )
Result = crc_calc16(ptr,len,[width]);        //same as crc_calc( )
[PCD] Result = crc_calc32(data,[width]);
[PCD] Result = crc_calc32(ptr,len,[width]);
```

Parameters:

data- This is one double word, word or byte that needs to be processed when using
 crc_calc16()
 crc_calc8()
 [PCD] crc_calc32()

ptr- is a pointer to one or more double words, words or bytes of data

len- number of double words, words or bytes to process for function calls

```
crc_calc16( )
crc_calc8( )
[PCD] crc_calc32( )
```

width- optional parameter used to specify the input data bit width to use with the functions

```
crc_calc16( )
crc_calc8( )
[PCD] crc_calc32( )
```

If not specified, it defaults to the width of the return value of the function

```
8-bit for crc_calc8( )
16-bit for crc_calc16( )
[PCD] 32-bit for crc_calc32( )
```

Returns:

Returns the result of the final CRC calculation.

Function:

Calculates the CRC of the passed data using the CRC engine. The function that should be used to do the calculation depends on the CRC polynomial used. For polynomials less than or equal 8 bits, `crc_calc8()` should be used. For polynomials greater than 8 bits, `crc_calc16()` should be used. Data widths less than or equal to 16 bits are supported.

[PCD] Calculates the CRC of the passed data using the CRC engine. The `crc_calc32()` function is only available for device with a 32 bit CRC peripheral. The function that should be used to do the calculation depends on the CRC polynomial used. For polynomials less than or equal to 8 bits, `crc_calc8()` should be used. For polynomials greater than 8 bits and less than or equal to 16 bits, `crc_calc16()` should be used. For polynomials greater than 16 bits, `crc_calc32()` should be used. For devices with a 32 bit CRC peripheral, data widths less than or equal to 32 bits are supported, and for device with a 16 bit CRC peripheral data widths less than or equal to 16 bits are supported.

Availability:

Only Devices with a built-in CRC module

Requires:

Examples:

```
int16 data[8];
Result = crc_calc(data,8);
```

Example Files:

ex_crc_hw.c

See Also:

setup_crc(); crc_init()

crc_init(mode)**Syntax:**

crc_init (*data*);

Parameters:

data- This will setup the initial value used by write CRC shift register. Most commonly, this register is set to 0x0000 for start of a new CRC calculation.

Returns:

Undefined

Function:

Configures the CRCWDAT register with the initial value used for CRC calculations.

Availability:

Only Devices with a built-in CRC module

Requires:

Examples:

```
crc_init ();           // Starts the CRC accumulator out at 0

crc_init(0xFEEE); // Starts the CRC accumulator out at 0xFEEE
```

See Also:

setup_crc(), crc_calc(), crc_calc8()

crc_read()**Syntax:**

value = read();

Parameters:

Returns:

A 16-bit integer.

Function:

Returns the current CRC Accumulator value.

Availability:

On devices with a Cyclic Redundancy Check (CRC) module.

Requires:

Examples:

```
int16 value;  
value = crc_read();
```

See Also:

setup_crc(), crc_init(), crc_calc(), crc_write()

crc_write()**Syntax:**

`crc_write(data, [data_width])`;

Parameters:

data is the 16 bit value to write

data_width is an optional parameter used to specify the width of the input data.

Returns:

Undefined

Function:

Used to write data into the CRC data registers.

Availability:

On devices with a Cyclic Redundancy Check (CRC) module.

Requires:

Examples:

```
crc_write(data);
```

See Also:

setup_crc(), crc_init(), crc_calc(), crc_read()

cwg_restart() cwg2_restart() cwg3_restart()**Syntax:**

```
cwg_restart();
cwg2_restart();
cwg3_restart();
```

Parameters:

Returns:

Function:

To restart the CWG module after an auto-shutdown event occurs, when not using auto-raster option of module.

Availability:

Devices with a CWG module

Requires:

Examples:

```
if(cwg_status() == CWG_AUTO_SHUTDOWN)
    cwg_restart();
```

See Also:

setup_cwg(), cwg_status()

cwg_status() cwg2_status() cwg3_status()**Syntax:**

```
value = cwg_status();
value = cwg2_status();
```

```
value = cwg3_status( );
```

Parameters:

Returns:

The status of the CWG module

Function:

To determine if a shutdown event occurred causing the module to auto-shutdown.

Availability:

Devices with a CWG module

Requires:

Examples:

```
if(cwg_status( ) == CWG_AUTO_SHUTDOWN)
    cwg_restart( );
```

See Also:

setup_cwg(), cwg_restart()

dac_write()

Syntax:

```
dac_write (value);
dac_write2 (value);
dac_write3(value);
dac_write4(value);
dac_write5(value);
dac_write6(value);
dac_write7(value);
dac_write8(value);
[PCD] dac_write (channel, value);
[PCD] dac_write (module, value);
[PCD] dac_write (module, value, [low_value]);
```

Parameters:

value - 8-bit or 16-bit integer value to be written to the DAC module

[PCD] channel - 16-bit integer value to be written to the DAC module channel: Channel to be written to. Constants are:

DAC_RIGHT
DAC_DEFAULT
DAC_LEFT

[PCD] module - DAC module to write value to.

[PCD] low_value - Optional 16-bit integer value for devices with an Analog Comparator with Slope Compensation DAC peripheral to set the DAC low data value. In Hysteric, Slope Generator and Triangle modes, this specifies the low data value and/or limit for the DAC module.

Returns:

Function:

This function will write a 8-bit or 16-bit integer to the specified DAC module.

Availability:

Devices with an analog-to-digital converter (DAC).

Requires:

Examples:

```
dac_write(20);

[PCD]
dac_write(DAC_RIGHT, 500);
dac_write(1, DacValue);
dac_write(1, DacValue, DacLowValue);
```

See Also:

[setup_dac\(\)](#), [DAC Overview](#), See header file for device selected

dci_data_received()

Syntax:

dci_data_received()

Parameters:

Returns:

An int1. Returns true if the DCI module has received data.

Function:

Use this function to poll the receive buffers. It acts as a kbhit() function for DCI.

Availability:

Devices with a DCI

Requires:

Examples:

```
while(1)
{
    if(dci_data_received())
    {
        //read data, load buffers, etc...
    }
}
```

See Also:

DCI Overview, setup_dci(), dci_start(), dci_write(), dci_read(), dci_transmit_ready()

dci_read()**Syntax:**

`dci_read(left_channel, right_channel);`

Parameters:

left_channel- A pointer to a signed int16 that will hold the incoming audio data for the left channel (on a stereo system). This data is received on the bus before the right channel data (for situations where left & right channel does have meaning)

right_channel- A pointer to a signed int16 that will hold the incoming audio data for the right channel (on a stereo system). This data is received on the bus after the data in *left channel*.

Returns:

Undefined

Function:

Use this function to read two data words. Do not use this function with DMA. This function is provided mainly for applications involving a stereo codec.

If your application does not use both channels but only receives on a slot (see `setup_dci`), use only the left channel.

Availability:

Devices with a DCI

Requires:

Examples:

```
while(1)
{
    dci_read(&left_channel, &right_channel);
    dci_write(&left_channel, &right_channel);
}
```

See Also:

`DCI Overview`, `setup_dci()`, `dci_start()`, `dci_write()`, `dci_transmit_ready()`, `dci_data_received()`

`dci_start()`**Syntax:**

`dci_start();`

Parameters:

Returns:

Undefined

Function:

Starts the DCI module's transmission. DCI operates in a continuous transmission mode (unlike other transmission protocols that transmit only when they have data). This function starts the transmission. This function is primarily provided to use DCI in conjunction with DMA

Availability:

Devices with a DCI

Requires:

Examples:

```

dci_initialize((I2S_MODE | DCI_MASTER |
DCI_CLOCK_OUTPUT | SAMPLE_RISING_EDGE |
UNDERFLOW_LAST |
MULTI_DEVICE_BUS),DCI_1WORD_FRAME |
DCI_16BIT_WORD | DCI_2WORD_INTERRUPT,
RECEIVE_SLOT0 | RECEIVE_SLOT1, TRANSMIT_SLOT0 |
TRANSMIT_SLOT1, 6000);
...
dci_start()

```

See Also:

DCI Overview, [setup_dci\(\)](#), [dci_write\(\)](#), [dci_read\(\)](#), [dci_transmit_ready\(\)](#), [dci_data_received\(\)](#)

dci_transmit_ready()

Syntax:

dci_transmit_ready()

Parameters:

Returns:

An int1. Returns true if the DCI module is ready to transmit (there is space open in the hardware buffer)

Function:

Use this function to poll the transmit buffers

Availability:

Devices with a DCI

Requires:

Examples:

```

while(1)
{
    if(dci_transmit_ready())
    {
        //transmit data, load
        buffers, etc...
    }
}

```

See Also:

[DCI Overview](#), [setup_dci\(\)](#), [dci_start\(\)](#), [dci_write\(\)](#), [dci_read\(\)](#), [dci_data_received\(\)](#)

dci_write()**Syntax:**

```
dci_write(left_channel, right_channel);
```

Parameters:

left_channel - A pointer to a signed int16 that holds the outgoing audio data for the left channel (on a stereo system). This data is transmitted on the bus before the right channel data (for situations where left & right channel does have meaning)

right_channel - A pointer to a signed int16 that holds the outgoing audio data for the right channel (on a stereo system). This data is transmitted on the bus after the data in *left channel*.

Returns:

Undefined

Function:

Use this function to transmit two data words. Do not use this function with DMA. This function is provided mainly for applications involving a stereo codec.

If the application does not use both channels but only transmits on a slot (see [setup_dci\(\)](#)), use only the left channel. If transmit more than two slots, call this function multiple times.

Availability:

Devices with a DCI

Requires:

Examples:

```
while(1)
{
    dci_read(&left_channel, &right_channel);
    dci_write(&left_channel, &right_channel)
}
```

See Also:

DCI Overview, setup_dci(), dci_start(), dci_read(), dci_transmit_ready(), dci_data_received()

delay_cycles()**Syntax:**

delay_cycles (*count*)

Parameters:

count - a constant 1-255

Returns:

Undefined

Function:

Creates code to perform a delay of the specified number of instruction clocks (1-255). An instruction clock is equal to four oscillator clocks.

The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.

Availability:

All Devices

Requires:

Examples:

```
delay_cycles( 1 ); // Same as a NOP
delay_cycles(25); // At 20 mhz a 5us delay
```

Example Files:

ex_cust.c

See Also:

delay_us(), delay_ms()

delay_ms()**Syntax:**

delay_ms (*time*)

Parameters:

time - a variable 0-65535(int16) or a constant 0-65535

Note: Previous compiler versions ignored the upper byte of an int16, now the upper byte affects the time.

Returns:

Undefined

Function:

This function will create code to perform a delay of the specified length. Time is specified in milliseconds. This function works by executing a precise number of instructions to cause the requested delay. It does not use any timers. If interrupts are enabled the time spent in an interrupt routine is not counted toward the time.

The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.

Availability:

All Devices

Requires:

#USE_DELAY

Examples:

```
#use delay (clock=20000000)
delay_ms( 2 );

void delay_seconds(int n) {
    for (;n!=0; n- -)
        delay_ms( 1000 );
}
```

Example Files:

ex_sqw.c

See Also:

delay_us(), delay_cycles(), #USE_DELAY

delay_us()

Syntax:

`delay_us(time)`

Parameters:

time - a variable 0-65535(int16) or a constant 0-65535

Note: Previous compiler versions ignored the upper byte of an int16, now the upper byte affects the time.

Returns:

Undefined

Function:

Creates code to perform a delay of the specified length. Time is specified in microseconds. Shorter delays will be INLINE code and longer delays and variable delays are calls to a function. This function works by executing a precise number of instructions to cause the requested delay. It does not use any timers. If interrupts are enabled the time spent in an interrupt routine is not counted toward the time.

The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.

Availability:

All Devices

Requires:

`#USE_DELAY`

Examples:

```
#use delay(clock=20000000)
```

```
do {
  output_high(PIN_B0);
  delay_us(duty);
  output_low(PIN_B0);
  delay_us(period-duty);
} while(TRUE);
```

Example Files:

[ex_sqw.c](#)

See Also:

[delay_ms\(\)](#), [delay_cycles\(\)](#), [#USE_DELAY](#)

disable_dmt()

Syntax:

```
disable_dmt();
```

Parameters:

Returns:

Function:

Disable the Deadman Timer (DMT). This function only works if the DMT_SW configuration fuses has been set. If the DMT configuration fuse is set, then the DMT is always enabled.

Availability:

Only on devices that have the DMT peripheral.

Requires:

Examples:

```
disabled_dmt();
```

See Also:

[clear_dmt\(\)](#), [read_dmt\(\)](#), [enable_dmt\(\)](#), [dmt_status\(\)](#), [setup_dmt\(\)](#)

disable_interrupts()

Syntax:

```
disable_interrupts (level)
```

```
[PCD] disable_interrupts (name)
```

```
[PCD] disable_interrupts (INTR_XX)
```

```
[PCD] disable_interrupts (expression)
```

Parameters:

level - a constant defined in the devices .h file

[PCD] ***name*** - a constant defined in the devices .h file

[PCD] **INTR_XX** – Allows user selectable interrupt options like **intr_normal**, **intr_alternate**, **intr_level**

[PCD] **expression** – A non-constant expression

Returns:

Undefined

[PCD] When **intr_levelx** is used as a parameter, this function will return the previous level.

Function:

Disables the interrupt at the given level. The GLOBAL level will not disable any of the specific interrupts but will prevent any of the specific interrupts, previously enabled to be active. Valid specific levels are the same as are used in #INT_xxx and are listed in the devices .h file. GLOBAL will also disable the peripheral interrupts on devices that have it.

Note that it is not necessary to disable interrupts inside an interrupt service routine since interrupts are automatically disabled. Some chips that have interrupt on change for individual pins allow the pin to be specified like INT_RA1.

[PCD]

Disables the interrupt for the given name. Valid specific names are the same as are used in #INT_xxx and are listed in the devices .h file. Note that it is not necessary to disable interrupts inside an interrupt service routine since interrupts are automatically disabled.

intr_glogal – Disables all interrupts that can be disabled

intr_normal – Use normal vectors for the ISR

intr_alterate – Use alternate vectors for the ISR

intr_level0 / intr_level7 – Disables interrupts at this level and below, enables interrupts above this level

intr_cn_pin|pin_xx – Disables a CN pin interrupts

expression – Disables interrupts during evaluation of the expression.

Availability:

Some Devices (PCM and PCH) with interrupts and all 24-bit (PCD) devices.

Requires:

Should have a #INT_xxxx, constants are defined in the devices .h file.

Examples:

```
disable_interrupts(GLOBAL);      // all interrupts OFF
disable_interrupts(INT_RDA);     // RS232 OFF
```

```
enable_interrupts(ADC_DONE);
enable_interrupts(RB_CHANGE); // these enable the interrupts
                                // but since the GLOBAL is
disabled they                  // are not activated until the
                                // statement:
following                       //
enable_interrupts(GLOBAL);
```

Example Files:

[ex_sisr.c](#), [ex_stwt.c](#)

See Also:

[enable_interrupts\(\)](#), [clear_interrupt\(\)](#), [#INT xxxx](#), [Interrupts Overview](#), [interrupt_active\(\)](#)

disable_pwm1_interrupt() **disable_pwm2_interrupt()**
disable_pwm3_interrupt() **disable_pwm4_interrupt()**
disable_pwm5_interrupt() **disable_pwm6_interrupt()**

Syntax:

```
disable_pwm1_interrupt(interrupt)
disable_pwm2_interrupt(interrupt)
disable_pwm3_interrupt(interrupt)
disable_pwm4_interrupt(interrupt)
disable_pwm5_interrupt(interrupt)
disable_pwm6_interrupt(interrupt)
```

Parameters:

interrupt - 8-bit constant or variable. Constants are defined in the device's header file as:

```
pwm_period_interrupt
pwm_duty_interrupt
pwm_phase_interrupt
pwm_offset_interrupt
```

Returns:

Undefined

Function:

Disables one of the above PWM interrupts, multiple interrupts can be disabled by or'ing multiple options together.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
disable_interrupts(GLOBAL);    // all interrupts OFF
disable_interrupts(INT_RDA);   // RS232 OFF

enable_interrupts(ADC_DONE);
enable_interrupts(RB_CHANGE);  // these enable the interrupts
                                // but since the GLOBAL is
disabled they
                                // are not activated until the
following
                                // statement:
enable_interrupts(GLOBAL);
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(), enable_pwm_interrupt(), clear_pwm_interrupt(), pwm_interrupt_active()

div() ldiv()

Syntax:

idiv=div(*num*, *denom*)
ldiv =ldiv(*lnum*, *ldenom*)

Parameters:

num and *denom* are signed integers.

num is the numerator and *denom* is the denominator

lnum and *ldenom* are signed longs

[PCD] *lnum* and *ldenom* are signed int32, int48 or int64

lnum is the numerator and *ldenom* is the denominator

Returns:

idiv is a structure of type **div_t** and ldiv is a structure of type **ldiv_t**. The **div** function returns a structure of type **div_t**, comprising of both the quotient and the remainder. The **ldiv** function returns a structure of type **ldiv_t**, comprising of both the quotient and the remainder.

Function:

idiv is a structure of type **div_t** and **ldiv** is a structure of type **ldiv_t**. The **div** function returns a structure of type **div_t**, comprising of both the quotient and the remainder. The **ldiv** function returns a structure of type **ldiv_t**, comprising of both the quotient and the remainder.

Availability:

All Devices

Requires:

#INCLUDE <STDLIB.H>

Examples:

```
div_t idiv;
ldiv_t ldiv;
idiv=div(3,2);           //idiv will contain quot=1 and
rem=1

ldiv=ldiv(300,250);      //ldiv will contain ldiv.quot=1
and ldiv.rem=5
```

dma_start()

Syntax:

dma_start(channel, mode, destAddr, sourceAddr, destCount, sourceCount);

[PCD] dma_start(channel, mode, addressA, addressB, count);

[PCD] dma_start(channel, mode, destAddr, sourceAddr, count);

Parameters:

Channel - The DMA channel to use.

mode - The mode to use for the DMA transfers. Constants for setting the mode are defined in the device's header file. See the header file for all possible options.

destAddr - The start RAM address of the destination address to use, can be anywhere in the GPR or SFR memory areas.

sourceAddr - The start address of the source address to use, can be anywhere in RAM, EEPROM or Flash program memory areas. The memory area of the address reads from is determined by one of the settings that can be made with the mode parameter.

destCount - The number of bytes to transfer to the destination address.

sourceCount - The number of bytes to transfer from the source address for each DMA trigger.

[PCD] addressA - The start RAM address of the buffer to use located within the DMA RAM bank.

[PCD] addressB - If using DMA_PING_PONG mode the start RAM address of the second buffer to use located within the DMA RAM bank.

[PCD] destAddr - The start RAM address of the destination address to use, located within the DMA RAM bank. Address data is moved from.

[PCD] sourceAddr - The start RAM address of the source address to use, located within the DMA RAM bank. Address data is moved to.

[PCD] count - The number of DMA transfers to do. For devices with Type 1 DMA peripheral, this should be one less the actual number of transfers to do. For devices with Type 2 DMA peripheral, this should be equal to the actual number of transfers to do.

Returns:

Void

Function:

Starts the DMA transfer for the specified channel in the specified mode of operation and assigns the RAM addresses to use the DMA transfer.

Availability:

Devices that have the DMA peripheral. The version of the function used depends on the type of DMA peripheral it has. Use **getenv("DMA")** to determine the type the device has.

[PCD] It will return 0 for no DMA peripheral, 1 for Type 1 and 2 for Type 2. For devices with Type 1 uses first version of the function and for devices with Type 2 uses second version of the function.

Requires:

Examples:

```
dma_start(1, DMA_SOURCE_ADDR_IS_SFR_GPR |
DMA_SOURCE_ADDR_UNCHANGED |
DMA_INC_DEST_ADDR | DMA_HW_TRIGGER_STARTS_XFER | DMA_CONTINUOUS,
RxBuffer, getenv("SFR:U1RXB"), DMA_BUFFER_SIZE, 1);
```

```
[PCD]
dma_start(0,DMA_PING_PONG|DMA_CONTINUOUS, RxBuffer[0],
RxBuffer[1], (DMA_BUFFER_SIZE-1)); // Type
```

1

```
dma_start(0,DMA_SOURCE_ADDR_UNCHANGED|DMA_INC_DEST_ADDR|
DMA_REPEATED|DMA_ONE_SHOT,RxBuffer,getenv("SFR:U1RXREG"),
DMA_BUFFER_SIZE); // Type
2
```

Example Files:

ex_dma_uart_rx.c

See Also:

setup_dma(), dma_status()

dma_status()

Syntax:

Value = dma_status(*channel*);

Parameters:

Channel – The channel in which the status is to be queried.

Returns:

The DMA channel's status. See the device header file for mask values that can be AND'ed with return value.

Function:

This function will return the status of the specified channel in the DMA module.

Availability:

Devices that have the DMA module

Requires:

Examples:

```
Int8 value;
value = dma_status(3); // This will return the status of
channel 1 of the DMA module
```

See Also:

setup_dma(), dma_start()

dmt_status()

Syntax:

```
Status = dmt_status();
```

Parameters:

Returns:

An int8 value indicating the status of the DT peripheral. See the device's header file for constants that can be and'ed with the return value to determine the state of the individual status bits.

Function:

Used to determine the status of the Deadman Timer (DMT) peripheral.

Availability:

Only on devices that have the DMT peripheral.

Requires:

Examples:

```
if((dmt_status() & DMT_CLEAR_WINDOW_OPEN) == DMT_CLEAR_WINDOW_OPEN)
    clear_dmt();
```

See Also:

[clear_dmt\(\)](#), [read_dmt\(\)](#), [disable_dmt\(\)](#), [enable_dmt\(\)](#), [setup_dmt\(\)](#)

enable_dmt()

Syntax:

```
enable_dmt();
```

Parameters:

Returns:

Function:

Enable the Deadman Timer (DMT). This function only works if the DMT_SW configuration fuses has been set. If the DMT configuration fuse is set, then the DMT is always enabled.

Availability:

Only on devices that have the DMT peripheral.

Requires:

Examples:

```
enabled_dmt();
```

See Also:

clear_dmt(), read_dmt(), disable_dmt(), dmt_status(), setup_dmt()

enable_interrupts()

Syntax:

enable_interrupts (*level*)

[PCD] enable_interrupts (*name*)

[PCD] enable_interrupts (*INTR_XX*)

Parameters:

level - is a constant defined in the devices *.h file

[PCD] **name**- a constant defined in the devices .h file

[PCD] **INTR_XX** – Allows user selectable interrupt options like **intr_normal**, **intr_alterate**, **intr_level**

Returns:

Undefined

Function:

This function enables the interrupt at the given level. An interrupt procedure should have been defined for the indicated interrupt.

The GLOBAL level will not enable any of the specific interrupts, but will allow any of the specified interrupts previously enabled to become active. Some chips that have an interrupt on change for individual pins all the pin to be specified, such as INT_RA1. For interrupts that use edge detection to trigger, it can be setup in the enable_interrupts() function without making a separate call to the set_int_edge() function.

Enabling interrupts does not clear the interrupt flag if there was a pending interrupt prior to the call. Use the `clear_interrupt()` function to clear pending interrupts before the call to `enable_interrupts()` to discard the prior interrupts.

[PCD]

name -Enables the interrupt for the given name. Valid specific names are the same as are used in `#INT_xxx` and are listed in the devices .h file.

intr_global – Enables all interrupt levels (same as `INTR_LEVEL0`)

intr_normal – Use normal vectors for the ISR

intr_alterate – Use alternate vectors for the ISR

intr_level0.... intr_level7 – Enables interrupts at this level and above, interrupts at lower levels are disabled

intr_cn_pin | pin_xx – Enables a CN pin interrupts

Availability:

Devices that have interrupts and all 24-bit devices.

Requires:

Should have a `#INT_XXXX` to define the ISR, and constants are defined in the devices *.h file.

Examples:

```
enable_interrupts(GLOBAL);
enable_interrupts(INT_TIMER0);
enable_interrupts( INT_EXT_H2L )
```

[PCD]

```
enable_interrupts(INT_TIMER0);
enable_interrupts(INT_TIMER1);
enable_interrupts(INTR_CN_PIN|Pin_B0);
```

Example Files:

[ex_sisr.c](#), [ex_stwt.c](#)

See Also:

[disable_interrupts\(\)](#), [clear_interrupt\(\)](#), [ext_int_edge\(\)](#), [#INT_xxxx](#), [Interrupts Overview](#), [interrupt_active\(\)](#)

erase_program_memory()

Syntax:

`erase_program_memory (address);`

Parameters:

address - is 32 bits. The least significant bits may be ignored.

Returns:

Undefined

Function:

Erases FLASH_ERASE_SIZE bytes to 0xFFFF in program memory.

FLASH_ERASE_SIZE varies depending on the part.

<u>Family</u>	<u>FLASH_ERASE_SIZE</u>
dsPIC30F	32 instructions (96 bytes)
dsPIC33FJ	512 instructions (1536 bytes)
PIC24FJ	512 instructions (1536 bytes)
PIC24HJ	512 instructions (1536 bytes)

NOTE: Each instruction on the PCD is 24 bits wide (3 bytes)

See `write_program_memory()` for more information on program memory access.

Availability:

All Devices

Requires:

Examples:

```
Int32 address = 0x2000;

erase_program_memory(address);           // erase block of memory
from 0x2000                               // to 0x2400 for a
PIC24HJ/FJ /33FJ                         //device, or erase 0x2000
to 0x2040                                 //for a dsPIC30F chip
```

See Also:

[write_program_eeprom\(\)](#), [write_program_memory\(\)](#), [Program Eeprom Overview](#)

enable_pwm1_interrupt() **enable_pwm2_interrupt()**
enable_pwm3_interrupt() **enable_pwm4_interrupt()**
enable_pwm5_interrupt() **enable_pwm6_interrupt()**

Syntax:

```
enable_pwm1_interrupt(interrupt)
enable_pwm2_interrupt(interrupt)
enable_pwm3_interrupt(interrupt)
enable_pwm4_interrupt(interrupt)
enable_pwm5_interrupt(interrupt)
enable_pwm6_interrupt(interrupt)
```

Parameters:

interrupt - 8-bit constant or variable. Constants are defined in the device's header file as:

```
PWM_PERIOD_INTERRUPT
PWM_DUTY_INTERRUPT
PWM_PHASE_INTERRUPT
PWM_OFFSET_INTERRUPT
```

Returns:

Function:

Enables one of the above PWM interrupts, multiple interrupts can be enabled by or'ing multiple options together. For the interrupt to occur, the overall PWMx interrupt still needs to be enabled and an interrupt service routine still needs to be created.

Availability:

Devices with a 16-bit PWM module.

Requires:

Examples:

```
enable_pwm1_interrupt(PWM_PERIOD_INTERRUPT);
enable_pwm1_interrupt(PWM_PERIOD_INTERRUPT |
PWM_DUTY_INTERRUPT);
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(),
disable_pwm_interrupt(), clear_pwm_interrupt(), pwm_interrupt_active()

erase_eeprom()

Syntax:

```
erase_eeprom (address);
```

Parameters:

address is 8 bits on PCB parts

Returns:

Undefined

Function:

This will erase a row of the EEPROM or Flash Data Memory.

Availability:

PCB devices with EEPROM like the 12F519

Requires:

Examples:

```
erase_eeprom(0);           // erase the first row of the EEPROM (8 bytes)
```

See Also:

[write_eeprom\(\)](#), [read_eeprom\(\)](#), [Data EEPROM Overview](#)

erase_program_memory()

Syntax:

```
erase_program_eeprom (address);
```

Parameters:

address - is 16 on PCM parts and 32 bits on PCH parts. The least significant bits may be ignored.

[PCD] **address** - is 32 bits. The least significant bits may be ignored.

Returns:

Function:

Erases FLASH_ERASE_SIZE bytes to 0xFFFF in program memory.

FLASH_ERASE_SIZE varies depending on the part. For example, if it is 64 bytes then the least significant 6 bits of address is ignored.

[PCD] For example, if it is 128 bytes then the least significant 7 bits of address is ignored.

See `write_program_memory()` **[PCD]** EEPROM Overview for more information on program memory access.

Availability:

Only devices that allow writes to program memory.

Requires:

Examples:

```
for (i=0x1000; i<=0x1fff; i+=getenv("FLASH_ERASE_SIZE"))
    erase_program_memory(i);
```

See Also:

[write_program_eeprom\(\)](#), [write program memory\(\)](#), [Program Eeprom Overview](#)

exp()

Syntax:

result = exp (*value*)

Parameters:

value is a float

[PCD] *value* is any float type

Returns:

A float

[PCD] A float with a precision equal to *value*

Function:

Computes the exponential function of the argument. This is e to the power of value where e is the base of natural logarithms. exp(1) is 2.7182818.

Note on error handling:

If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Range error occur in the following case: **exp** when the argument is too large

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```

// Calculate x to the power of y
x_power_y = exp( y * log(x) );
```

See Also:

[pow\(\)](#), [log\(\)](#), [log10\(\)](#)

ext_int_edge()

Syntax:

ext_int_edge (*source*, *edge*)

Parameters:

source is a constant 0,1 or 2 for the PIC18XXX and 0 otherwise.

[PCD] **source** is a constant from 0 to 4.

Source is optional and defaults to 0.

edge is a constant H_TO_L or L_TO_H representing "high to low" and "low to high"

Returns:

Undefined

Function:

Determines when the external interrupt is acted upon. The edge may be L_TO_H or H_TO_L to specify the rising or falling edge.

Availability:

Only devices with interrupts

Requires:

Constants are in the devices .h file

Examples:

```

ext_int_edge( 2, L_TO_H); // Set up PIC18 EXT2
ext_int_edge( 2, L_TO_H); // Set up external interrupt 2 to
interrupt
                                // on rising edge
ext_int_edge( H_TO_L ); // Sets up EXT
```

```
ext_int_edge( H_TO_L );      // Sets up external interrupt 0 to
interrupt                    // on falling edge
```

Example Files:ex_wakup.c**See Also:**

#INT_EXT , [enable_interrupts\(\)](#) , [disable_interrupts\(\)](#) , #INT_EXT , [enable_interrupts\(\)](#) , [disable_interrupts\(\)](#) , [Interrupts Overview](#)

fabs()**Syntax:**

result=fabs (*value*)

Parameters:

value is a float

[PCD] **value** is any float type

Returns:

result is a float

[PCD] result is a float with precision to **value**

Function:

The **fabs()** function computes the absolute value of a float

Availability:

All Devices

Requires:

Constants are in the devices .h file

Examples:

```
float result;
result=fabs(-40.0)           // result is 40.0
```

See Also:

[abs\(\)](#), [labs\(\)](#)

getc() getch() getchar() fgetc()**Syntax:**

value = getc()


```
value = fgetc(stream)
value=getch()
value=getchar()
```

Parameters:

stream is a stream identifier (a constant byte)

Returns:

An 8-bit character

Function:

This function waits for a character to come in over the RS232 RCV pin and returns the character.

In order to not hang forever waiting for an incoming character use **kbhit()** to test for a character available.

If a built-in USART is used the hardware can buffer 3 characters otherwise **getc()** must be active while the character is being received by the device.

If **fgetc()** is used then the specified stream is used where **getc()** defaults to STDIN (the last USE RS232).

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
printf("Continue (Y,N)?");
do {
    answer=getch();
}
while(answer!='Y' && answer!='N');

#use rs232(baud=9600,xmit=pin_c6,
          rcv=pin_c7,stream=HOSTPC)
#use rs232(baud=1200,xmit=pin_b1,
          rcv=pin_b0,stream=GPS)
#use rs232(baud=9600,xmit=pin_b3,
          stream=DEBUG)

...
while(TRUE) {
    c=fgetc(GPS);
    fputc(c,HOSTPC);
    if(c==13)
```

```
    fprintf(DEBUG, "Got a CR\r\n");
}
```

Example Files:

ex_stwt.c

See Also:

putc(), kbhit(), printf(), #USE RS232, input.c, RS232 I/O Overview

gets() fgets()

Syntax:

gets (*string*)

value = fgets (*string*, *stream*)

Parameters:

string is a pointer to an array of characters.

Stream is a stream identifier (a constant byte)

Returns:

Undefined

Function:

Reads characters (using **getc()**) into the string until a RETURN (value 13) is encountered. The string is terminated with a 0. Note that **INPUT.C** has a more versatile **get_string()** function.

If **fgets()** is used then the specified stream is used where gets() defaults to STDIN (the last USE RS232).

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
char string[30];

printf("Password: ");
gets(string);
if(strcmp(string, password))
    printf("OK");
```

See Also:

`getc()`, `get_string` in [input.c](#)

floor()

Syntax:

result = floor (*value*)

Parameters:

value is a float

[PCD] *value* is any float type

Returns:

Result is a float

[PCD] Result is a float with precision equal to *value*

Function:

Computes the greatest integer value not greater than the argument. Floor (12.67) is 12.00

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
                                // Find the fractional part of a value
frac = value - floor(value);
```

See Also:

[`ceil\(\)`](#)

fmod()

Syntax:

result= fmod (*val1*, *val2*)

Parameters:

val1 is a float

[PCD] *val1* is any float type

val2 is a float

[PCD] *val2* is any float type

Returns:

Result is a float

[PCD] Result is a float with precision equal to input parameters **val1** and **val2**

Function:

Returns the floating point remainder of val1/val2. Returns the value val1 - i*val2 for some integer “i” such that, if val2 is nonzero, the result has the same sign as val1 and magnitude less than the magnitude of val2.

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
float result;
result=fmod(3,2);           // result is 1
```

printf() fprintf()

Syntax:

printf (**string**)

or

printf (**cstring, values...**)

or

printf (**fname, cstring, values...**)

fprintf (**stream, cstring, values...**)

Parameters:

String is a constant string or an array of characters null terminated.

C String is a constant string. Note that format specifiers cannot be used in RAM strings.

Values is a list of variables separated by commas, fname is a function name to be used for outputting (default is **putc** is none is specified).

Stream is a stream identifier (a constant byte)

Returns:

Undefined

Function:

Outputs a string of characters to either the standard RS-232 pins (first two forms) or to a specified function. Formatting is in accordance with the string argument. When variables are used this string must be a constant. The % character is used within the string to indicate a variable value is to be formatted and output. Longs in the printf may be 16 or 32 bit. A %% will output a single %. Formatting rules for the % follows.

See the Expressions > Constants and Trigraph sections of this manual for other escape character that may be part of the string.

If **fprintf()** is used then the specified stream is used where **printf()** defaults to STDOUT (the last USE RS232).

Format:

The format takes the generic form %nt. n is optional and may be 1-9 to specify how many characters are to be outputted, or 01-09 to indicate leading zeros, or 1.1 to 9.9 for floating point and %w output. t is the type and may be one of the following:

- c** -- string or character
- u** -- unsigned
- d** -- signed int
- Lu** -- long unsigned int
- Ld** -- long signed int
- x** -- hex int (lower case)
- X** -- hex int (upper case)
- Lx** -- hex long int (lower case)
- LX** -- hex long int (upper case)
- f** -- float with truncated decimal
- g** -- float with rounded decimal
- e** -- float in exponential format
- w** -- unsigned int with decimal place inserted. Specify two numbers for *n*.
The first is a total field width. The second is the desired number of decimal places.

Example Formats:

<u>Specifier</u>	<u>Value=0x12</u>	<u>Value=0xfe</u>
%03u	018	254
%u	18	254
%2u	18	*
%5	18	254
%d	18	-2
%x	12	fe
%X	12	FE

%4X	0012	00FE
%3.1w	1.8	25.4

* Result is undefined - Assume garbage.

Availability:

All Devices

Requires:

#USE RS232 (unless fname is used)

Examples:

```
byte  x,y,z;
printf("HiThere");
printf("RTCCValue=>%2x\r\n",get_rtcc());
printf("%2u %X %4X\r\n",x,y,z);
printf(LCD_PUTC, "n=%u",n);
```

Example Files:

[ex_admm.c](#), [ex_lcdkb.c](#)

See Also:

[atoi\(\)](#), [puts\(\)](#), [putc\(\)](#), [getc\(\)](#) (for a stream example), [RS232 I/O Overview](#)

putc() putchar() fputc()**Syntax:**

```
putc(cdata)
putchar(cdata)
fputc(cdata, stream)
```

Parameters:

cdata is a 8 bit character.

Stream is a stream identifier (a constant byte)

Returns:

Undefined

Function:

This function sends a character over the RS232 XMIT pin. A #USE RS232 must appear before this call to determine the baud rate and pin used. The #USE RS232 remains in effect until another is encountered in the file.

If This function sends a character over the RS232 XMIT pin. A #USE RS232 must appear before this call to determine the baud rate and pin used. The #USE RS232 remains in effect until another is encountered in the file.

If **fputc()** is used then the specified stream is used where **putc()** defaults to STDOUT (the last USE RS232). is used then the specified stream is used where **putc()** defaults to STDOUT (the last USE RS232).

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
putc('*');  
for(i=0; i<10; i++)  
    putc(buffer[i]);  
putc(13)
```

Example Files:

ex_tgetc.c

See Also:

getc(), printf(), #USE RS232, RS232 I/O Overview

puts() fputs()

Syntax:

puts (*string*).
fputs (*string*, *stream*)

Parameters:

string is a constant string or a character array (null-terminated).

stream is a stream identifier (a constant byte)

Returns:

Undefined

Function:

Sends each character in the string out the RS232 pin using **putc()**. After the string is sent a CARRIAGE-RETURN (13) and LINE-FEED (10) are sent. In general **printf()** is more useful than **puts()**.

If **fputs()** is used then the specified stream is used where **puts()** defaults to STDOUT (the last USE RS232)

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
puts( " ----- " );  
puts( " |      HI      | " );  
puts( " ----- " );
```

See Also:

[printf\(\)](#), [gets\(\)](#), [RS232 I/O Overview](#)

free()

Syntax:

free(*ptr*)

Parameters:

ptr is a pointer earlier returned by the calloc, malloc or realloc

Returns:

No Value

Function:

The free function causes the space pointed to by the *ptr* to be deallocated, that is made available for further allocation. If *ptr* is a null pointer, no action occurs. If the *ptr* does not match a pointer earlier returned by the **calloc**, **malloc** or **realloc**, or if the space has been deallocated by a call to free or **realloc** function, the behavior is undefined.

Availability:

All Devices

Requires:

#INCLUDE <stdlibm.h>

Examples:

```
int * iptr;  
iptr=malloc(10);
```



```
free(iptr)                // iptr will be deallocated
```

See Also:

realloc(), malloc(), calloc()

frexp()**Syntax:**

result=frexp (*value*, &*exp*)

Parameters:

value is a float

[PCD] *value* is any float type

exp is a signed int

Returns:

result is a float

[PCD] result is a float with precision equal to *value*

Function:

The **frexp** function breaks a floating point number into a normalized fraction and an integral power of 2. It stores the integer in the signed **int** object **exp**. The result is in the interval [1/2 to1) or zero, such that value is result times 2 raised to power **exp**. If value is zero then both parts are zero.

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
float result;
signed int exp;
result=frexp(.5,&exp);           // result is .5 and exp is 0
```

See Also:

ldexp(), exp(), log(), log10(), modf()

scanf() fscanf()**Syntax:**

```
scanf(cstring);
scanf(cstring, values...)
fscanf(stream, cstring, values...)
```

Parameters:

cstring is a constant string.

values is a list of variables separated by commas.

stream is a stream identifier

Returns:

0 if a failure occurred, otherwise it returns the number of conversion specifiers that were read in, plus the number of constant strings read in.

Function:

Reads in a string of characters from the standard RS-232 pins and formats the string according to the format specifiers. The format specifier character (%) used within the string indicates that a conversion specification is to be done and the value is to be saved into the corresponding argument variable. A %% will input a single %. Formatting rules for the format specifier as follows:

If fscanf() is used, then the specified stream is used, where scanf() defaults to STDIN (the last USE RS232).

Format:

The format takes the generic form %nt. **n** is an option and may be 1-99 specifying the field width, the number of characters to be inputted. **t** is the type and maybe one of the following:

- c** Matches a sequence of characters of the number specified by the field width (1 if no field width is specified). The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence.
- s** Matches a sequence of non-white space characters. The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.
- u** Matches an unsigned decimal integer. The corresponding argument shall be a pointer to an unsigned integer.

- Lu** Matches a long unsigned decimal integer. The corresponding argument shall be a pointer to a long unsigned integer.
- d** Matches a signed decimal integer. The corresponding argument shall be a pointer to a signed integer.
- Ld** Matches a long signed decimal integer. The corresponding argument shall be a pointer to a long signed integer.
- o** Matches a signed or unsigned octal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
- Lo** Matches a long signed or unsigned octal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- x or X** Matches a hexadecimal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
- Lx or LX** Matches a long hexadecimal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- i** Matches a signed or unsigned integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
- Li** Matches a long signed or unsigned integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- f,g or e** Matches a floating point number in decimal or exponential format. The corresponding argument shall be a pointer to a float.
- [** Matches a non-empty sequence of characters from a set of expected characters. The sequence of characters included in the set are made up of all character following the left bracket ([) up to the matching right bracket (]). Unless the first character after the left bracket is a ^, in which case the set of characters contain all characters that do not appear between the brackets. If a - character is in the set and is not the first or second, where the first is a ^, nor the last character, then the set includes all characters from the character before the - to the character after the -.
For example, %[a-z] would include all characters from **a** to **z** in the set and %[^a-z] would exclude all characters from **a** to **z** from the set. The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.

n Assigns the number of characters read thus far by the call to `scanf()` to the corresponding argument. The corresponding argument shall be a pointer to an unsigned integer.

An optional assignment-suppressing character (*) can be used after the format specifier to indicate that the conversion specification is to be done, but not saved into a corresponding variable. In this case, no corresponding argument variable should be passed to the `scanf()` function.

A string composed of ordinary non-white space characters is executed by reading the next character of the string. If one of the inputted characters differs from the string, the function fails and exits. If a white-space character precedes the ordinary non-white space characters, then white-space characters are first read in until a non-white space character is read.

White-space characters are skipped, except for the conversion specifiers `[%c]`, `[%c]` or `[%n]`, unless a white-space character precedes the `[%]` or `[%c]` specifiers.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
char name[2-];
unsigned int8 number;
signed int32 time;

if (scanf ("%u%s%ld", &number, name, &time))
    printf "\r\nName: %s, Number: %u, Time: %ld", name, number, time
```

See Also:

[RS232 I/O Overview](#), [getc\(\)](#), [putc\(\)](#), [printf\(\)](#)

get_adc_ports()

Syntax:

```
value = get_adc_ports();
```

Parameters:

Returns:

A 32-bit int

Function:

Returns a value that can be passed to `setup_adc_ports()` to setup the analog pins.

Availability:

Devices with an Analog-to-Digital (ADC) module.

Requires:

Examples:

```
adc_pins = get_adc_ports();
```

See Also:

[read_adc\(\)](#), [setup_adc\(mode\)](#), [setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [ADC](#)

get_capture()**Syntax:**

`value = get_capture(x)`

Parameters:

`x` defines which ccp module to read from

Returns:

A 16-bit timer value

Function:

This function obtains the last capture time from the indicated CCP module.

Availability:

Only available on devices with Input Capture modules

Requires:

Example Files:

[ex_ccpmp.c](#)

See Also:

[setup_ccpx\(\)](#)

[PCD] get_capture()

Syntax:

value = get_capture(x, *wait*)

Parameters:

x defines which input capture result buffer module to read from

wait signifies if the compiler should read the oldest result in the buffer or the next result to enter the buffer

Returns:

A 16-bit timer value

Function:

If *wait* is true, the current capture values in the result buffer are cleared, and the next result to be sent to the buffer is returned. If *wait* is false, the default setting, the first value currently in the buffer is returned. However, the buffer will only hold four results while waiting for them to be read, so if read isn't being called for every capture event, when *wait* is false, the buffer will fill with old capture values and any new results will be lost.

Availability:

Only available on devices with Input Capture modules

Requires:

Examples:

```
setup_timer3(TMR_INTERNAL | TMR_DIV_BY_8);
setup_capture(2, CAPTURE_FE | CAPTURE_TIMER3);
while(TRUE) {
    timerValue = get_capture(2, TRUE);
    printf("Capture 2 occurred at: %LU", timerValue);
}
```

See Also:

[setup_capture\(\)](#), [setup_compare\(\)](#), [Input Capture Overview](#)

get_capture32_ccp1() get_capture_ccp1()
get_capture_ccp2() get_capture_ccp3() get_capture_ccp4()
get_capture_ccp5()

Syntax:

value=get_capture_ccpx(**wait**);

Parameters:

wait -signifies if the compiler should read the oldest result in the buffer or the next result in the buffer or the next result to enter the buffer

Returns:

value16 -a 16-bit timer value

Function:

If **wait** is true, the current capture values in the result buffer are cleared, and the next result to be sent, the buffer is returned. If **wait** is false, the default setting, the first value currently in the buffer is return. However, the buffer will only hold four results while waiting for them to be read. If read is not being called for every capture event, when **wait** is false, the buffer will fill with old capture values and any new result will be lost.

Availability:

Available only on PIC24FxxKMxxx family of devices with a MCCP and/or SCCP modules

Requires:

Examples:

```
unsigned int16 value;

setup_ccp1(CCP_CAPTURE_FE);

while(TRUE) {
    value=get_capture_ccp1(TRUE);
    printf("Capture occurred at: %LU", value);
}
```

See Also:

set_pwmX_duty(), setup_ccpX(), set_ccpX_compare_time(), set_timer_ccpX(),
set_timer_period_ccpX(), get_timer_ccpx(), get_capture32_ccpX()

[PCD] get_capture32_ccp1() get_capture32_ccp2()
get_capture32_ccp3() get_capture32_ccp4()
get_capture32_ccp5()

Syntax:

value=get_capture32_ccpx(**wait**);

Parameters:

wait -signifies if the compiler should read the oldest result in the buffer or the next result in the buffer or the next result to enter the buffer

Returns:

value32 -a 32-bit timer value

Function:

If **wait** is true, the current capture values in the result buffer are cleared, and the next result to be sent, the buffer is returned. If **wait** is false, the default setting, the first value currently in the buffer is return. However, the buffer will only hold two results while waiting for them to be read. If read is not being called for every capture event, when **wait** is false, the buffer will fill with old capture values and any new result will be lost.

Availability:

Available only on PIC24FxxKMxxx family of devices with a M CCP and/or SCCP modules

Requires:

Examples:

```
unsigned int32 value;

setup_ccp1(CCP_CAPTURE_FE|CCP_TIMER_32_BIT);

while(TRUE) {
    value=get_capture_ccp1(TRUE);
    printf("Capture occurred at: %LU", value);
}
```

See Also:

set_pwmX_duty(), setup_ccpX(), set_ccpX_compare_time(), set_timer_ccpX(),
set_timer_period_ccpX(), get_timer_ccpx(), get_capture_ccpX()

get_capture_event()**Syntax:**

```
result = get_capture_event([stream]);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE CAPTURE

Returns:

TRUE if a capture event occurred, FALSE otherwise

Function:

To determine if a capture event occurred.

Availability:

All Devices

Requires:

#USE CAPTURE

Examples:

```
#USE CAPTURE(INPUT=PIN_C2,CAPTURE_RISING,TIMER=1,FASTEST)
if(get_capture_event())
    result = get_capture_time()
```

See Also:

[#use_capture](#), [get_capture_time\(\)](#)

get_capture_time()**Syntax:**

```
result = get_capture_time([stream])
```

Parameters:

stream – optional parameter specifying the stream defined in #USE CAPTURE

Returns:

An int16 value representing the last capture time

Function:

To get the last capture time.

Availability:

All Devices

Requires:

#USE CAPTURE

Examples:

```
#USE CAPTURE (INPUT=PIN_C2,CAPTURE_RISING,TIMER=1,FASTEST)
result = get_capture_time();
```

See Also:

[#use_capture, get_capture_event\(\)](#)

[PCD] get_capture32()

Syntax:

```
result = get_capture32(x,[wait])
```

Parameters:

x is 1-16 and defines which input capture result buffer modules to read from.

wait is an optional parameter specifying if the compiler should read the oldest result in the bugger or the next result to enter the buffer

Returns:

A 32-bit timer value

Function:

If **wait** is true, the current capture values in the result buffer are cleared, and the next result to be sent to the buffer is returned. If **wait** is false, the default setting, the first value currently in the buffer is returned. However, the buffer will only hold four results while waiting for them to be read, so if `get_capture32` is not being called for every capture event. When **wait** is false, the buffer will fill with old capture values and any new results will be lost.

Availability:

Only devices with a 32-bit Input Capture module

Requires:

Examples:

```
setup_timer2(TMR_INTERNAL | TMR_DIV_BY_1 | TMR_32_BIT);
setup_capture(1,CAPTURE_FE | CAPTURE_TIMER2 | CAPTURE_32_BIT);
while(TRUE) {
```

```

    timerValue=get_capture32(1,TRUE);
    printf("Capture 1 occurred at: %LU", timerValue);
}

```

See Also:

setup_capture(), setup_compare(), get_capture(), Input Capture Overview

get_hspwm_capture()

Syntax:

result=get_hspwm_capture(**unit**);

Parameters:

unit - The High Speed PWM unit to set

Returns:

Unsigned in16 value representing the capture PWM time base value.

Function:

Gets the captured PWM time base value from the leading edge detection on the current-limit input.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```

    result=get_hspwm_capture(1);

```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock(), setup_hspwm(), setup_hspwm_secondary()

get_hspwm_feedback()

Syntax:

result = get_hspwm_feedback();

Parameters:

Returns:

A 15-bit pseudorandom value.

Function:

To read the Linear Feedback Shift register from the High-Speed PWM (HSPWM) peripheral.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
unsigned int16 value;
value = get_hspwm_feedback();
```

See Also:

[setup_hspwm\(\)](#), [setup_hspwm_event_output x\(\)](#), [setup_hspwm_logic x\(\)](#),
[setup_hspwm_unit\(\)](#),
[setup_hspwm_blanking\(\)](#), [setup_hspwm_event\(\)](#), [setup_hspwm_fault\(\)](#),
[setup_hspwm_current_limit\(\)](#),
[setup_hspwm_feed_forward\(\)](#), [setup_hspwm_sync\(\)](#), [set_hspwm_scaling\(\)](#),
[set_hspwm_override\(\)](#), [set_hspwm_phase\(\)](#), [set_hspwm_duty\(\)](#), [set_hspwm_period\(\)](#),
[set_hspwm_duty_adjustment\(\)](#), [set_hspwm_trigger x\(\)](#), [get_hspwm_capture\(\)](#),
[get_hspwm_status\(\)](#), [hspwm_trigger_pwm\(\)](#),
[hspwm_stop_pwm\(\)](#), [hspwm_do_capture\(\)](#), [hspwm_update\(\)](#)

get_hspwm_status()

Syntax:

```
result = get_hspwm_status(unit);
```

Parameters:

unit - The PWM unit to get the status for.

Returns:

A 16-bit value indicating the status of the specified PWM unit. See the device's header file for the defines that can be and'ed with return value to determine if the corresponding status bits are set.

Function:

To read the Linear Feedback Shift register from the High-Speed PWM (HSPWM) peripheral.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
unsigned int16 status;
status = get_hspwm_status(1);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(),
setup_hspwm_blanking(), setup_hspwm_event(), setup_hspwm_fault(),
setup_hspwm_current_limit(),
setup_hspwm_feed_forward(), setup_hspwm_sync(), set_hspwm_scaling(),
set_hspwm_override(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(), get_hspwm_feedback(),
get_hspwm_capture(), hspwm_trigger_pwm(),
hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update()

get_motor_pwm_count()**Syntax:**

```
Data16 = get_motor_pwm_count(pwm);
```

Parameters:

pwm- Defines the pwm module used

Returns:

16 bits of data

Function:

Returns the PWM count of the motor control unit

Availability:

Devices that have the motor control PWM unit

Requires:

Examples:

```
Data16 = get_motor_pwm_count(1)
```

See Also:

setup_motor_pwm(), set_motor_unit(), set_motor_pwm_event(), set_motor_pwm_duty()

.

get_nco_accumulator()**Syntax:**

```
value = get_nco_accumulator();
```

Parameters:

Returns:

Current value of accumulator

Function:

Returns the PWM count of the motor control unit

Availability:

Devices that have a NCO module

Requires:

Examples:

```
value = get_nco_accumulator();
```

See Also:

setup_nco(), set_nco_inc_value(), get_nco_inc_value()

.

get_nco_inc_value()**Syntax:**

```
value =get_nco_inc_value( );
```

Parameters:

Returns:

Current value set in increment registers

Function:

Returns the PWM count of the motor control unit

Availability:

Devices that have the motor control PWM unit

Requires:

Examples:

```
Data16 = get_motor_pwm_count(1)
```

See Also:

setup_nco(), set_nco_inc_value(), get_nco_accumulator()

get_ticks()**Syntax:**

```
value = get_ticks([stream]);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE TIMER

Returns:

value – a 8, 16 or 32 bit integer. (int8, int16 or int32)

[PCD] value – a 8, 16, 32 or 64 bit integer. (int8, int16, int32 or int64)

Function:

Returns the current tick value of the tick timer. The size returned depends on the size of the tick timer.

Availability:

All Devices

Requires:

#USE TIMER(options)

Examples:

```
#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)
```

```
void main(void) {  
    unsigned int16 current_tick;  
  
    current_tick = get_ticks();  
}
```

See Also:

#USE TIMER, set_ticks()

get_timerA()**Syntax:**

value=get_timerA();

Parameters:

Returns:

The current value of the timer as an int8

Function:

Returns the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, ...).

Availability:

This function is only available on devices with Timer A hardware

Requires:

Examples:

```
set_timerA(0);  
while(timerA < 200);
```

See Also:

set_timerA(), setup_timer_A(), TimerA Overview

get_timerB()**Syntax:**

```
value=get_timerB();
```

Parameters:

```
-----
```

Returns:

The current value of the timer as an int8

Function:

Returns the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, ...).

Availability:

This function is only available on devices with Timer B hardware

Requires:

```
-----
```

Examples:

```
set_timerB(0);
while(timerB < 200);
```

See Also:

set_timerB(), setup_timer_B(), TimerB Overview

get_timerx()**Syntax:**

```
value=get_timer0() Same as: value=get_rtcc()
```

```
value=get_timer1()
```

```
value=get_timer2()
```

```
value=get_timer3()
```

```
value=get_timer4()
```

```
value=get_timer5()
```

```
value=get_timer6()
```

```
value=get_timer7()
```

```
value=get_timer8()
```

```
value=get_timer10()
```

```
value=get_timer12()
```

```
[PCD] value=get_timer1()
```

```
[PCD] value=get_timer2( )
[PCD] value=get_timer3( )
[PCD] value=get_timer4( )
[PCD] value=get_timer5( )
[PCD] value=get_timer6( )
[PCD] value=get_timer7( )
[PCD] value=get_timer8( )
[PCD] value=get_timer9( )
```

Parameters:

Returns:

Timers 1, 3, 5 and 7 return a 16 bit int.

Timers 2,4, 6, 8, 10 and 12 return an 8 bit int.

Timer 0 (AKA RTCC) returns a 8 bit int except on the PIC18XXX where it returns a 16 bit int.

[PCD] The current value of the timer as an int16

Function:

Returns the count value of a real time clock/counter. RTCC and Timer0 are the same. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2...)

[PCD] Retrieves the value of the timer, specified by X (which may be 1-9)

Availability:

Timer 0 - All devices

Timers 1 & 2 - Most but not all PCM devices

Timer 3, 5 and 7 - Some PIC18 and Enhanced PIC16 devices

Timer 4,6,8,10 and 12- Some PIC18 and Enhanced PIC16 devices

[PCD] This function is available on all devices that have a valid timerX

Requires:

Examples:

```
set_timer0(0);
while ( get_timer0() < 200 ) ;
if(get_timer2() % 0xA0 == HALF_WAVE_PERIOD)
output_toggle(PIN_B0);
```

Example Files:

ex_stwt.c

See Also:

[set_timerx\(\)](#), [Timer0 Overview](#), [Timer1 Overview](#), [Timer2 Overview](#), [Timer5 Overview](#)
[\[PCD\] Timer Overview](#), [setup_timerX\(\)](#), [get_timerXY\(\)](#), [set_timerX\(\)](#), [set_timerXY\(\)](#)

get_timerxy()**Syntax:**

```
value=get_timer23()  
value=get_timer45()  
value=get_timer67()  
value=get_timer89()
```

Parameters:

Void

Returns:

The current value of the 32 bit timer as an int32

Function:

Retrieves the 32 bit value of the timers X and Y, specified by XY (which may be 23, 45, 67 and 89)

Availability:

This function is available on all devices that have a valid 32 bit enabled timers. Timers 2 & 3, 4 & 5, 6 & 7 and 8 & 9 may be used. The target device must have one of these timer sets. The target timers must be enabled as 32 bit.

Requires:

Examples:

```
if (get_timer23() > TRIGGER_TIME)  
    ExecuteEvent();
```

Example Files:

[ex_stwt.c](#)

See Also:

[Timer Overview](#), [setup_timerX\(\)](#), [get_timerXY\(\)](#), [set_timerX\(\)](#), [set_timerXY\(\)](#)

**get_timer_ccp1() get_timer_ccp2() get_timer_ccp3()
get_timer_ccp4() get_timer_ccp5()**

Syntax:

```
value32=get_timer_ccpx();
value16=get_timer_ccpx(which);
```

Parameters:

which - when in 16-bit mode determines which timer value to read. 0 reads the lower timer value (CCPxTMRL), and 1 reads the upper timer value (CCPxTMRH)

Returns:

value32 - the 32-bit timer value.

value16- the 16-bit timer value

Function:

This function gets the timer values for the CCP module

Available only on PIC24FxxKMxxx family of devices with a MCCP and/or SCCP modules

Requires:

Examples:

```
unsigned int32 value32;
unsigned int32 value15;
value32=get_timer_ccpx();           //get the 32 bit timer value
value16=get_timer_ccpx(0);          //get the 16 bit timer value
from                                //lower timer
value16=get_timer_ccpx(1);          //get the 16 bit timer value
from                                //upper timer
```

See Also:

set_pwmX_duty(), setup_ccpX(), set_ccpX_compare_time(), set_timer_ccpX(),
set_timer_period_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

get_tris_x()

Syntax:

```
value = get_tris_A();
value = get_tris_B();
value = get_tris_C();
value = get_tris_D();
value = get_tris_E();
value = get_tris_F();
value = get_tris_G();
value = get_tris_H();
value = get_tris_J();
value = get_tris_K();
value = get_tris_L();
```

Parameters:

Returns:

int16, the value of TRIS register

Function:

Returns the value of the TRIS register of port A, B, C, D, E, F, G, H, J, K or L.

Availability:

All Devices

Requires:

Examples:

```
tris_a = GET_TRIS_A()
```

See Also:

input(), output_low(), output_high()

get_wdt()

Syntax:

```
value = get_wdt();
```

Parameters:

Returns:

An 8-bit int

Function:

Returns the current watchdog timer value.

Availability:

Devices with a Windowed Watchdog Timer.

Requires:

Examples:

```
int8 count;
count = get_wdt();
```

See Also:

[setup_wdt\(\)](#), [restart_wdt\(\)](#), [WDT or Watch Dog Timer](#)

getenv()

Syntax:

value = getenv (*cstring*);

Parameters:

cstring - is a constant string with a recognized keyword

Returns:

A constant number, a constant string or 0

Function:

This function obtains information about the execution environment. The following are recognized keywords. This function returns a constant 0 if the keyword is not understood.

FUSE_SET:ffff	Returns 1 if fuse ffff is enabled
FUSE_VALID:ffff	Returns 1 if fuse ffff is valid
INT:iiii	Returns 1 if the interrupt iiii is valid
ID	Returns the device ID (set by #ID)

DEVICE	Returns the device name string (like "PIC16C74")
CLOCK	Returns the MPU FOSC
VERSION	Returns the compiler version as a float
VERSION_STRING	Returns the compiler version as a string
PROGRAM_MEMORY	Returns the size of memory for code (in words)
STACK	Returns the stack size
SCRATCH	Returns the start of the compiler scratch area
DATA_EEPROM	Returns the number of bytes of data EEPROM
EEPROM_ADDRESS	Returns the address of the start of EEPROM. 0 if not supported by the device.
READ_PROGRAM	Returns a 1 if the code memory can be read
ADC_CHANNELS	Returns the number of A/D channels
ADC_RESOLUTION	Returns the number of bits returned from READ_ADC()
ICD	Returns a 1 if this is being compiled for a ICD
SPI	Returns a 1 if the device has SPI
USB	Returns a 1 if the device has USB
CAN	Returns a 1 if the device has CAN
I2C_SLAVE	Returns a 1 if the device has I2C slave H/W
I2C_MASTER	Returns a 1 if the device has I2C master H/W
PSP	Returns a 1 if the device has PSP
COMP	Returns a 1 if the device has a comparator

VREF	Returns a 1 if the device has a voltage reference
LCD	Returns a 1 if the device has direct LCD H/W
UART	Returns the number of H/W UARTs
AUART	Returns 1 if the device has an ADV UART
CCPx	Returns a 1 if the device has CCP number x
TIMERx	Returns a 1 if the device has TIMER number x
FLASH_WRITE_SIZE	Smallest number of bytes that can be written to FLASH
FLASH_ERASE_SIZE	Smallest number of bytes that can be erased in FLASH
BYTES_PER_ADDRESS	Returns the number of bytes at an address location
BITS_PER_INSTRUCTION	Returns the size of an instruction in bits
RAM	Returns the number of RAM bytes available for your device.
SFR:name	Returns the address of the specified special file register. The output format can be used with the preprocessor command #bit. name must match SFR denomination of your target PIC (example: STATUS, INTCON, TXREG, RCREG, etc)
BIT:name	Returns the bit address of the specified special file register bit. The output format will be in "address:bit", which can be used with the preprocessor command #byte. name must match SFR.bit denomination of your target PIC (example: C, Z, GIE, TMR0IF, etc)
SFR_VALID:name	Returns TRUE if the specified special file register name is valid and exists for your target PIC (example: getenv("SFR_VALID:INTCON"))

BIT_VALID:name	Returns TRUE if the specified special file register bit is valid and exists for your target PIC (example: getenv("BIT_VALID:TMR0IF"))
PIN:PB	Returns 1 if PB is a valid I/O PIN (like A2)
UARTx_RX	Returns UARTxPin (like PINxC7)
UARTx_TX	Returns UARTxPin (like PINxC6)
SPIx_DI	Returns SPIxDI Pin
SPIxDO	Returns SPIxDO Pin
SPIxCLK	Returns SPIxCLK Pin
ETHERNET	Returns 1 if device supports Ethernet
QEI	Returns 1 if device has QEI
DAC	Returns 1 if device has a D/A Converter
DSP	Returns 1 if device supports DSP instructions
DCI	Returns 1 if device has a DCI module
DMA	Returns 1 if device supports DMA
CRC	Returns 1 if device has a CRC module
CWG	Returns 1 if device has a CWG module
NCO	Returns 1 if device has a NCO module
CLC	Returns 1 if device has a CLC module
DSM	Returns 1 if device has a DSM module
OPAMP	Returns 1 if device has op amps
RTC	Returns 1 if device has a Real Time Clock

CAP_SENSE	Returns 1 if device has a CSM cap sense module and 2 if it has a CTMU module
EXTERNAL_MEMORY	Returns 1 if device supports external program memory
INSTRUCTION_CLOCK	Returns the MPU instruction clock
ENH16	Returns 1 for Enhanced 16 devices
[PCD] ENH24	Returns 2 for Enhanced 24 devices
[PCD] IC	Returns number of Input Capture units device has
[PCD] ICx	Returns TRUE if ICx is on this part
[PCD] OC	Returns number of Output Compare units device has
[PCD] OCx	Returns TRUE if OCx is on this part
[PCD] RAM_START	Returns the starting address of the first general purpose RAM location
[PCD] PSV	Returns TRUE if program space visibility (PSV) is enabled. If PSV is enabled, data in program memory ('const char *' or 'rom char *') can be assigned to a regular RAM pointer ('char *') and a regular RAM pointer can dereference data from program memory or RAM.
[PCD] MIN_FLASH_WRITE	The smallest number of bytes that can be written to FLASH using the write_program_memory() function. The write_program_memory() function can only write multiples of this size to the FLASH. Additionally, the start address passed to the write_program_memory() function must be multiples of this value divided by two. For example, if MIN_FLASH_WRITE is 4, then start address can be 0x0000, 0x0002, 0x0004, etc.

Availability:

All Devices

Requires:

Examples:

```
#IF getenv("VERSION")<3.050
    #ERROR Compiler version too old
#endif

for(i=0;i<getenv("DATA_EEPROM");i++)
    write_eeprom(i,0);

#ifdef FUSE_VALID:BROWNOUT
    #FUSE BROWNOUT
#endif

byte status_reg=GETENV("SFR:STATUS")
bit carry_flag=GETENV("BIT:C")
```

goto address()

Syntax:

goto_address(**location**);

Parameters:

location - is a ROM address, 16 or 32 bit int

Returns:

Function:

This function jumps to the address specified by location. Jumps outside of the current function should be done only with great caution. This is not a normally used function except in very special situations.

Availability:

All Devices

Requires:

Examples:

```
#define LOAD_REQUEST PIN_B1
#define LOADER 0x1f00
```

```
if(input (LOAD_REQUEST) )
    goto_address (LOADER);
```

Example Files:

[setjmp.h](#)

See Also:

[label_address\(\)](#)

high_speed_adc_done()

Syntax:

```
value = high_speed_adc_done([pair]);
```

Parameters:

pair – Optional parameter that determines which ADC pair's ready flag to check. If not used all ready flags are checked

Returns:

An int16. If pair is used 1 will be return if ADC is done with conversion, 0 will be return if still busy. If pair is not used, it will return a bit map of which conversion are ready to be read.

For example a return value of 0x0041 means that ADC pair 6, AN12 and AN13, and ADC pair 0, AN0 and AN1, are ready to be read.

Function:

Can be polled to determine if the ADC has valid data to be read.

Availability:

Only on dsPIC33FJxxGSxxx devices

Requires:

Examples:

```
int16 result[2]
setup_high_speed_adc_pair(1,  INDIVIDUAL_SOFTWARE_TRIGGER);
setup_high_speed_adc( ADC_CLOCK_DIV_4);

read_high_speed_adc(1, ADC_START_ONLY);
while(!high_speed_adc_done(1));
read_high_speed_adc(1, ADC_READ_ONLY, result);
```

```
printf("AN2 value = %LX, AN3 value =  
%LX\n\r", result[0], result[1])
```

See Also:

setup_high_speed_adc(), setup_high_speed_adc_pair(), read_high_speed_adc()

hspwm_do_capture()

Syntax:

hspwm_do_capture(**unit**);

Parameters:

unit - The PWM unit to capture.

Returns:

Function:

To initiate a software capture for the specified PWM unit of the High-Speed PWM (HSPWM) peripheral. Once a capture event has occurred, no further captures will occur until it is cleared. The capture event is cleared when read with the get_hspwm_capture() function.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
hspwm_do_capture(1);           //initiate a software capture for PWM unit 1
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(), setup_hspwm_feed_forward(),
setup_hspwm_sync(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(), get_hspwm_feedback(),
get_hspwm_capture(), get_hspwm_status(), hspwm_trigger_pwm(), hspwm_stop_pwm(),
hspwm_update()

hspwm_stop_pwm()

Syntax:

hspwm_stop_pwm(**unit**);

Parameters:

unit - The PWM unit to stop.

Returns:

Function:

To stop a PWM cycle for the specified unit of the High-Speed PWM (HSPWM) peripheral.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
hspwm_stop_pwm(1);           // stop a PWM cycle for PWM unit 1
```

See Also:

[setup_hspwm\(\)](#), [setup_hspwm_event_output x\(\)](#), [setup_hspwm_logic x\(\)](#),
[setup_hspwm_unit\(\)](#), [setup_hspwm_blanking\(\)](#), [setup_hspwm_event\(\)](#),
[setup_hspwm_fault\(\)](#), [setup_hspwm_current_limit\(\)](#), [setup_hspwm_feed_forward\(\)](#),
[setup_hspwm_sync\(\)](#), [set_hspwm_scaling\(\)](#), [set_hspwm_override\(\)](#),
[set_hspwm_phase\(\)](#), [set_hspwm_duty\(\)](#), [set_hspwm_period\(\)](#),
[set_hspwm_duty_adjustment\(\)](#), [set_hspwm_trigger x\(\)](#), [get_hspwm_feedback\(\)](#),
[get_hspwm_capture\(\)](#), [get_hspwm_status\(\)](#), [hspwm_trigger_pwm\(\)](#),
[hspwm_do_capture\(\)](#), [hspwm_update\(\)](#)

hspwm_trigger_pwm()

Syntax:

hspwm_trigger_pwm(**unit**);

Parameters:

unit - The PWM unit to trigger.

Returns:

Function:

To trigger a PWM cycle for the specified unit of the High-Speed PWM (HSPWM) peripheral.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
hspwm_trigger_pwm(1);    //trigger a software capture for PWM unit 1
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(), setup_hspwm_feed_forward(),
setup_hspwm_sync(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(), get_hspwm_feedback(),
get_hspwm_capture(), get_hspwm_status(), hspwm_stop_pwm(), hspwm_do_capture(),
hspwm_update()

hspwm_update()

Syntax:

hspwm_update(*unit*);

Parameters:

unit - The PWM unit to update.

Returns:

Function:

To request an update of the PWM data registers for the specified PWM unit of the High-Speed PWM (HSPWM) peripheral. When an update is pending, the UPDATE status bits will be set and the `get_hspwm_status()` function can be used to determine if an update is pending.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
hspwm_update(1);           // request an update for PWM unit 1
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(), setup_hspwm_feed_forward(),
setup_hspwm_sync(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(), get_hspwm_feedback(),
get_hspwm_capture(), get_hspwm_status(), hspwm_trigger_pwm(), hspwm_stop_pwm(),
hspwm_do_capture(),

i2c_init()**Syntax:**

```
i2c_init([stream],baud);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE I2C.

baud – if baud is 0, I2C peripheral will be disable. If baud is 1, I2C peripheral is initialized and enabled with baud rate specified in #USE I2C directive. If baud is > 1 then I2C peripheral is initialized and enabled to specified baud rate

Returns:

Function:

To initialize I2C peripheral at run time to specified baud rate.

Availability:

All Devices

Requires:

#USE I2C

Examples:

```
#USE I2C(MASTER,I2C1, FAST,NOINIT)
i2c_init(TRUE);           //initialize and enable
I2C peripheral             //to baud rate specified

in // #USE I2C
i2c_init(500000);         //initialize and enable
I2C peripheral            //to a baud rate of 500
KBPS
```

See Also:

[i2c_poll\(\)](#), [i2c_speed\(\)](#), [i2c_slaveaddr\(\)](#), [i2c_isr_state\(\)](#), [i2c_write\(\)](#),
[i2c_read\(\)](#), [_use_i2c\(\)](#), [i2c\(\)](#)

i2c_isr_state()

Syntax:

```
state = i2c_isr_state();
state = i2c_isr_state(stream);
```

Parameters:

Returns:

state - is an 8 bit int

0 - Address match received with R/W bit clear, perform **i2c_read()** to read the I2C address.

1-0x7F - Master has written data; **i2c_read()** will immediately return the data

0x80 - Address match received with R/W bit set; perform **i2c_read()** to read the I2C address, and use **i2c_write()** to pre-load the transmit buffer for the next transaction (next I2C read performed by master will read this byte).

0x81-0xFF - Transmission completed and acknowledged; respond with **i2c_write()** to pre-load the transmit buffer for the next transition (the next I2C read performed by master will read this byte).

Function:

Returns the state of I2C communications in I2C slave mode after an SSP interrupt. The return value increments with each byte received or sent.

If 0x00 or 0x80 is returned, an `i2c_read()` needs to be performed to read the I2C address that was sent (it will match the address configured by `#USE I2C` so this value can be ignored)

Availability:

Devices with built-in I2C

Requires:

`#USE I2C`

Examples:

```
#INT_SSP
void i2c_isr() {
    state = i2c_isr_state();
    if(state== 0 ) i2c_read();
    i@c_read();
    if(state == 0x80)
        i2c_read(2);
    if(state >= 0x80)
        i2c_write(send_buffer[state - 0x80]);
    else if(state > 0)
        rcv_buffer[state - 1] = i2c_read();
}
```

Example Files:

[ex_slave.c](#)

See Also:

[i2c_poll](#), [i2c_speed](#), [i2c_start](#), [i2c_stop](#), [i2c_slaveaddr](#), [i2c_write](#), [i2c_read](#), [#USE I2C](#), [I2C Overview](#)

i2c_poll()**Syntax:**

`i2c_poll()`
`i2c_poll(stream)`

Parameters:

stream (optional)- specify the stream defined in `#USE I2C`

Returns:

1 (TRUE) or 0 (FALSE)

Function:

The **i2c_poll()** function should only be used when the built-in SSP is used. This function returns TRUE if the hardware has a received byte in the buffer. When a TRUE is returned, a call to **i2c_read()** will immediately return the byte that was received.

Availability:

Devices with built-in I2C

Requires:

#USE I2C

Examples:

```
if(i2c_poll())
    buffer[index]=i2c_read();//read data
}
```

See Also:

[i2c_speed](#), [i2c_start](#), [i2c_stop](#), [i2c_slaveaddr](#), [i2c_isr_state](#), [i2c_write](#), [i2c_read](#), [#USE I2C](#), [I2C Overview](#)

i2c_read()

Syntax:

```
data = i2c_read();
data = i2c_read(ack);
data = i2c_read(stream, ack);
```

Parameters:

ack -Optional, defaults to 1

0 indicates do not ack

1 indicates to ack

2 slave only, indicates to not release clock at end of read. Use when **i2c_isr_state()** returns 0x80

stream - specify the stream defined in #USE I2C

Returns:

data - 8 bit int

Function:

Reads a byte over the I2C interface. In master mode this function will generate the clock and in slave mode it will wait for the clock. There is no timeout for the slave, use

i2c_poll() to prevent a lockup. Use **restart_wdt()** in the **#USE I2C** to strobe the watch-dog timer in the slave mode while waiting.

Availability:

All devices

Requires:

#USE I2C

Examples:

```
i2c_start();
i2c_write(0xa1);
data1 = i2c_read(TRUE);
data2 = i2c_read(FALSE);
i2c_stop();
```

Example Files:

ex_extee.c with 2416.c

See Also:

i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, #USE I2C, I2C Overview

i2c_slaveaddr()**Syntax:**

```
i2c_slaveaddr(addr);
i2c_slaveaddr(stream, addr)
```

Parameters:

addr = 8 bit device address

stream(optional) - specifies the stream used in #USE I2C

Returns:

Function:

This functions sets the address for the I2C interface in slave mode.

Availability:

Devices with built-in I2C

Requires:

#USE I2C

Examples:

```
i2c_SlaveAddr(0x08);  
i2c_SlaveAddr(i2cStream1, 0x08)
```

Example Files:

ex_slave.c

See Also:

i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_speed()**Syntax:**

```
i2c_speed (baud)  
i2c_speed (stream, baud)
```

Parameters:

baud is the number of bits per second.

stream - specify the stream defined in #USE I2C

Returns:

Function:

This function changes the I2c bit rate at run time. This only works if the hardware I2C module is being used.

Availability:

All Devices

Requires:

#USE I2C

Examples:

```
i2c_Speed (400000);  
putc(13)
```

Example Files:

ex_tgetc.c

See Also:

[i2c_poll](#), [i2c_start](#), [i2c_stop](#), [i2c_slaveaddr](#), [i2c_isr_state](#), [i2c_write](#), [i2c_read](#), [#USE I2C](#), [I2C Overview](#)

i2c_start()**Syntax:**

```
i2c_start()
i2c_start(stream)
i2c_start(stream, restart)
```

Parameters:

stream - specify the stream defined in `#USE I2C`

restart:- 2 - new restart is forced instead of start

1 - normal start is performed

0 - (or not specified) – restart is done only if the compiler last encountered a

i2c_start() and no **i2c_stop()**

Returns:

Undefined

Function:

Issues a start condition when in the I2C master mode. After the start condition the clock is held low until **i2c_write()** is called. If another **i2c_start()** is called in the same function before an **i2c_stop()** is called, then a special restart condition is issued.

Note that specific I2C protocol depends on the slave device. The **i2c_start()** function will now accept an optional parameter. If 1 the compiler assumes the bus is in the stopped state. If 2 the compiler treats this **i2c_start()** as a restart. If no parameter is passed a 2 is used only if the compiler compiled a **i2c_start()** last with no **i2c_stop()** since.

Availability:

All Devices

Requires:

`#USE I2C`

Examples:

```
i2c_start();
i2c_write(0xa0);      // Device address
i2c_write(address);   // Data to device
i2c_start();          // Restart
i2c_write(0xa1);      // to change data direction
```

```
data=i2c_read(0);    // Now read from slave  
i2c_stop()
```

Example Files:

ex_extee.c with 2416.c

See Also:

i2c_poll, i2c_speed, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_stop()

Syntax:

```
i2c_stop()  
i2c_stop(stream)
```

Parameters:

stream - (optional) specify the stream defined in #USE I2C

Returns:

Undefined

Function:

Issues a stop condition when in the I2C master mode.

Availability:

All Devices

Requires:

#USE I2C

Examples:

```
i2c_start();           // Start condition  
i2c_write(0xa0);       // Device address  
i2c_write(5);          // Device command  
i2c_write(12);         // Device data  
i2c_stop();            // Stop condition
```

Example Files:

ex_extee.c with 2416.c

See Also:

[i2c_poll](#), [i2c_speed](#), [i2c_start](#), [i2c_slaveaddr](#), [i2c_isr_state](#), [i2c_write](#), [i2c_read](#), [#USE_I2C](#), [I2C Overview](#)

i2c_transfer()

Syntax:

```
i2c_transfer([stream], address, wData, wCount, [rData], [rCount]);
```

Parameters:

stream - Optional, the stream defined in #USE I2C to use.

address - The device address to transfer data to and from.

wData - Pointer to data to transfer to device.

wCount - Number of bytes to transfer to device.

rData - Optional, pointer to save transferred data from device to.

Rcount - Optional, number of byte to transfer from device. Must be used if rData is used.

Returns:

0 for ACK and 1 for NACK. When only writing data, it returns whether the Slave device ACK'd or NACK'd the write command or last byte transmitted; whichever occurred last. If writing and reading data, if the Slave NACK'd one of the bytes that were transmitted, it returns a NACK, otherwise it returns whether the Slave ACK'd or NACK'd the read command.

Function:

Transfer data to and from an I2C device. This function does the I2C start, restart, write, read and stop operations. If the Slave device NACK's the write command, read command or one of the write bytes, the function will exit at that point even if it did not finish writing and/or reading all the data.

Availability:

All devices when #USE I2C is setup for Master Mode.

Requires:

Examples:

```
unsigned int8 rAddress=0;
```



```

unsigned int8 rData[16];
int1 ack;

ack = i2c_transfer(0xA0,&rAddress, 1, rData, 16);

if(ack==0)
    printf("\r\nData transferred successfully");
else
    printf("\r\nData transferred unsuccessfully");

```

Example File:

ex_i2c_master_hw_k42.c

See Also:

[i2c_poll\(\)](#), [i2c_speed\(\)](#), [i2c_stop\(\)](#), [i2c_slaveaddr\(\)](#), [i2c_isr_state\(\)](#), [i2c_write\(\)](#), [i2c_read\(\)](#), [i2c_transfer_out\(\)](#), [i2c_transfer_in\(\)](#), [#USE_I2C](#), [I2C Overview](#)

i2c_transfer_in()

Syntax:

`i2c_transfer_in([stream], address, rData, rCount);`

Parameters:

stream - Optional, the stream defined in #USE I2C to use.

address - The device address to transfer data from.

rData - Optional, pointer to save transferred data from device to.

Rcount - Number of byte to transfer from device.

Returns:

0 for ACK and 1 for NACK from the read command.

Function:

Transfer data to and from an I2C device. This function does the I2C start, restart, write, read and stop operations. If the Slave NACK'd the read command, the function will exit without reading any data.

Availability:

All devices when #USE I2C is setup for Master Mode.

Requires:

Examples:

```

unsigned int8 rData[16];
int1 ack;

ack=i2c_transfer_in(0xA0,rData,16);

if(ack==0)
    printf("Data read successfully");
else
    printf("data not read");

```

Example File:

ex_i2c_master_hw_k42.c

See Also:

[i2c_poll\(\)](#), [i2c_speed\(\)](#), [i2c_stop\(\)](#), [i2c_slaveaddr\(\)](#), [i2c_isr_state\(\)](#), [i2c_write\(\)](#), [i2c_read\(\)](#), [i2c_transfer_out\(\)](#), [i2c_transfer\(\)](#), [#USE I2C](#), [I2C Overview](#)

i2c_transfer_out()**Syntax:**

```
i2c_transfer_out([stream], address, wData, wCount);
```

Parameters:

stream - Optional, the stream defined in #USE I2C to use.

address - The device address to transfer data to.

wData - Pointer to data to transfer to device.

wcount - Number of bytes to transfer to device.

Returns:

0 for ACK and 1 for NACK of either the write command or last byte transmitted, whichever occurred last.

Function:

Transfer data to and from an I2C device. This function does the I2C start, restart, write, read and stop operations. If the Slave device NACK's the write command or one of the write bytes the function will exit at that point, even if it did not finish writing all the data.

Availability:

All devices when #USE I2C is setup for Master Mode.

Requires:

Examples:

```
unsigned int8wData[16];
int1 ack;

ack = i2c_transfer_out(0xA0,wData, 16);

if(ack==0)
    printf("\r\nData transferred successfully");
else
    printf("\r\nData transferred unsuccessfully");
```

Example File:

ex_i2c_master_hw_k42.c

See Also:

[i2c_poll\(\)](#), [i2c_speed\(\)](#), [i2c_stop\(\)](#), [i2c_slaveaddr\(\)](#), [i2c_isr_state\(\)](#), [i2c_write\(\)](#), [i2c_read\(\)](#), [i2c_transfer_in\(\)](#), [i2c_transfer\(\)](#), [#USE I2C](#), [I2C Overview](#)

i2c_write()

Syntax:

```
i2c_write (data)
i2c_write (stream, data)
```

Parameters:

data is an 8 bit int

stream - specify the stream defined in #USE I2C

Returns:

This function returns the ACK Bit.

0 means ACK, 1 means NO ACK, 2 means there was a collision if in Multi_Master Mode.

This does not return an ACK if using i2c in slave mode.

Function:

Sends a single byte over the I2C interface. In master mode this function will generate a clock with the data and in slave mode it will wait for the clock from the master. No automatic time-out is provided in this function. This function returns the ACK bit. The LSB of the first write after a start determines the direction of data transfer (0 is master to slave). Note that specific I2C protocol depends on the slave device.

Availability:

All Devices

Requires:

#USE I2C

Examples:

```
long cmd;

...

i2c_start();           // Start condition
i2c_write(0xa0);       // Device address
i2c_write(cmd);        // Low byte of command
i2c_write(cmd>>8);     // High byte of command
i2c_stop();            // Stop condition
```

Example Files:

ex [extee.c](#) with [2416.c](#)

See Also:

[i2c_poll](#), [i2c_speed](#), [i2c_start](#), [i2c_stop](#), [i2c_slaveaddr](#), [i2c_isr_state](#), [i2c_read](#), [#USE I2C](#), [I2C Overview](#)

input()**Syntax:**

value = input (*pin*)

Parameters:

Pin to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43. This is defined as follows: #define PIN_A3 43.

[PCD] ***Pin*** to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of 0x2C2*8+3 or 5651. This is defined as follows: #define PIN_A3 5651.

The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. note that doing I/O with a variable instead of a constant will take much longer time.

Returns:

0 (or FALSE) if the pin is low,
1 (or TRUE) if the pin is high

Function:

This function returns the state of the indicated pin. The method of I/O is dependent on the last USE *_IO directive. By default with standard I/O before the input is done the data direction is set to input.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
while ( !input(PIN_B1) );           // waits for B1 to go high

if( input(PIN_A0) )
    printf("A0 is now high\r\n");

int16 i=PIN_B1;
while(!i);                          //waits for B1 to go high
```

Example Files:

ex_pulse.c

See Also:

input x(), output low(), output high(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

input_change x()**Syntax:**

```
value = input_change_a();
value = input_change_b();
value = input_change_c();
value = input_change_d();
```

```
value = input_change_e();
value = input_change_f();
value = input_change_g();
value = input_change_h();
value = input_change_j();
value = input_change_k();
value = input_change_l();
```

Parameters:

Returns:

An 8-bit or 16-bit int representing the changes on the port

Function:

This function reads the level of the pins on the port and compares them to the results the last time the **input_change_x()** function was called. A 1 is returned if the value has changed, 0 if the value is unchanged.

Availability:

All Devices

Requires:

Examples:

```
pin_check = input_change_b( );
```

See Also:

[input\(\)](#), [input_x\(\)](#), [output_x\(\)](#), [#USE FIXED_IO](#), [#USE FAST_IO](#), [#USE STANDARD_IO](#), [General Purpose I/O](#)

input_state()

Syntax:

```
value = input_state(pin)
```

Parameters:

pin to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43. This is defined as follows: `#define PIN_A3 43`.

[PCD] **pin** to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of 0x2C2*8+3 or 5651. This is defined as follows: `#define PIN_A3 5651`.

Returns:

Bit specifying whether pin is high or low. A 1 indicates the pin is high and a 0 indicates it is low.

Function:

This function reads the level of a pin without changing the direction of the pin as INPUT() does.

Availability:

All Devices

Requires:

Examples:

```
level = input_state(pin_A3);  
printf("level: %d", level)
```

See Also:

input(), set_tris_x(), output_low(), output_high(), General Purpose I/O

input_x()**Syntax:**

```
value = input_a()  
value = input_b()  
value = input_c()  
value = input_d()  
value = input_e()  
value = input_f()  
value = input_g()  
value = input_h()  
value = input_j()  
value = input_k()  
value = input_l()
```

Parameters:

Returns:

An 8 bit int representing the port input data.

[PCD] An 16 bit int representing the port input data.

Function:

Inputs an entire byte from a port. The direction register is changed in accordance with the last specified `#USE * _IO` directive. By default with standard I/O before the input is done the data direction is set to input.

[PCD] Inputs an entire word from a port. The direction register is changed in accordance with the last specified `#USE * _IO` directive. By default with standard I/O before the input is done the data direction is set to input.

Availability:

All Devices

Requires:

Examples:

```
data = input_b();
```

See Also:

`input()`, `output_x()`, `#USE FIXED_IO`, `#USE FAST_IO`, `#USE STANDARD_IO`

interrupt_active()**Syntax:**

```
interrupt_active (interrupt)
```

Parameters:

Interrupt – constant specifying the interrupt

Returns:

Boolean value

Function:

The function checks the interrupt flag of the specified interrupt and returns true in case the flag is set.

Availability:

Devices with Interrupts

Requires:

Should have a #INT_xxxx, Constants are defined in the devices .h file

Examples:

```
interrupt_active(INT_TIMER0);  
interrupt_active(INT_TIMER1);
```

See Also:

[Interrupts Overview](#), [clear_interrupt](#), [enable_interrupts\(\)](#), [disable_interrupts\(\)](#), [#INT](#), [disable_interrupts\(\)](#), [#INT](#)

interrupt_enabled()

This function checks the interrupt enabled flag for the specified interrupt and returns TRUE if set.

Syntax:

```
interrupt_enabled(interrupt);
```

Parameters:

interrupt- constant specifying the interrupt

Returns:

Boolean value

Function:

The function checks the interrupt enable flag of the specified interrupt and returns TRUE when set.

Availability:

Devices with Interrupts

Requires:

Interrupt Constants are defined in the devices .h file

Examples:

```
if(interrupt_enabled(INT_RDA))  
    disable_interrupt(INT_RDA);
```

See Also:

[Interrupts Overview](#), [clear_interrupt](#), [interrupt_active\(\)](#), [disable_interrupts\(\)](#), [#INT](#), [#INT](#)

isalnum(char) isalpha(char) iscntrl(x) isdigit(char)
isgraph(x) islower(char) isspace(char) isupper(char)
isxdigit(char) isprint(x) ispunct(x)

Syntax:

```
value = isalnum(datac)
value = isalpha(datac)
value = isdigit(datac)
value = islower(datac)
value = isspace(datac)
value = isupper(datac)
value = isxdigit(datac)
value = iscntrl(datac)
value = isgraph(datac)
value = isprint(datac)
value = punct(datac)
```

Parameters:

datac - is a 8 bit character

Returns:

0 (or FALSE) if datac dose not match the criteria, 1 (or TRUE) if datac does match the criteria.

Function:

Tests a character to see if it meets specific criteria as follows:

isalnum(x)	X is 0..9, 'A'..'Z', or 'a'..'z'
isalpha(x)	X is 'A'..'Z' or 'a'..'z'
isdigit(x)	X is '0'..'9'
islower(x)	X is 'a'..'z'
isupper(x)	X is 'A'..'Z'
isspace(x)	X is a space
isxdigit(x)	X is '0'..'9', 'A'..'F', or 'a'..'f'
iscntrl(x)	X is less than a space
isgraph(x)	X is greater than a space
isprint(x)	X is greater than or equal to a space
ispunct(x)	X is greater than a space and not a letter or number

Availability:

All Devices

Requires:

#INCLUDE <ctype.h>

Examples:

```

char id[20];

...
if (isalpha(id[0])) {
    valid_id=TRUE;
    for(i=1;i<strlen(id);i++)
        valid_id=valid_id && isalnum(id[i]);
} else
    valid_id=FALSE;

```

Example Files:ex_str.c**See Also:**isamong()**isamong()****Syntax:**result = isamong (*value*, *cstring*)**Parameters:****value** - is a character**cstring** - is a constant sting**Returns:**

0 (or FALSE) if value is not in cstring

1 (or TRUE) if value is in cstring

Function:

Returns TRUE if a character is one of the characters in a constant string.

Availability:

All devices

Requires:

Examples:

```

char x='x';

```

```
...
if (isamong (x,"0123456789ABCDEFGHIJKLMNOPQRSTUVWXYZ"))
    printf ("The character is valid");
```

Example Files:

```
#INCLUDE <ctype.h>
```

See Also:

[isalnum\(\)](#), [isalpha\(\)](#), [isdigit\(\)](#), [isspace\(\)](#), [islower\(\)](#), [isupper\(\)](#), [isxdigit\(\)](#)

itoa()

Syntax:

```
string = itoa(i32value, i8base, string)
```

```
[PCDJ] string = itoa(i48value, i8base, string)
```

```
[PCDJ] string = itoa(i64value, i8base, string)
```

Parameters:

i32value is a 32 bit int

[PCDJ] **i48value** is a 48 bit int

[PCDJ] **i64value** is a 64 bit int

i8base is a 8 bit int

string is a pointer to a null terminated string of characters

Returns:

string is a pointer to a null terminated string of characters

Function:

Converts the signed int32 to a string according to the provided base and returns the converted value if any. If the result cannot be represented, the function will return 0.

[PCDJ] Converts the signed int48, or a int64 to a string according to the provided base and returns the converted value if any. If the result cannot be represented, the function will return 0.

Availability:

All Devices

Requires:

```
#INCLUDE <stdlib.h>
```

Examples:

```
int32 x=1234;
char string[5];

itoa(x,10, string);      // string is now "1234"
```

jump_to_isr()

Syntax:

jump_to_isr (*address*)

Parameters:

address is a valid program memory address

Returns:

Function:

The jump_to_isr function is used when the location of the interrupt service routines are not at the default location in program memory. When an interrupt occurs, program execution will jump to the default location and then jump to the specified address.

Availability:

All Devices

Requires:

Examples:

```
int_global
void global_isr(void) {
    jump_to_isr(isr_address);
}
```

Example Files:

ex_bootloader.c

See Also:

#BUILD

kbhit()

Syntax:

value = kbhit()

value = kbhit (**stream**)

Parameters:

stream - is the stream id assigned to an available RS232 port. If the stream parameter is not included, the function uses the primary stream used by **getc()**.

Returns:

0 (or FALSE) if getc() will need to wait for a character to come in, 1 (or TRUE) if a character is ready for getc()

Function:

If the RS232 is under software control this function returns TRUE if the start bit of a character is being sent on the RS232 RCV pin. If the RS232 is hardware this function returns TRUE if a character has been received and is waiting in the hardware buffer for getc() to read. This function may be used to poll for data without stopping and waiting for the data to appear. Note that in the case of software RS232 this function should be called at least 10 times the bit rate to ensure incoming data is not lost.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
char timed_getc() {
    long timeout;
    timeout_error=FALSE;
    timeout=0;
    while(!kbhit() && (++timeout<50000)) // 1/2 second
        delay_us(10);
    if(kbhit())
        return(getc());
    else {
        timeout_error=TRUE;
        return(0);
    }
}
```

Example Files:

ex_tgetc.c

See Also:

getc(), #USE RS232, RS232 I/O Overview

label_address()

Syntax:

value = label_address(*label*);

Parameters:

label - is a C label anywhere in the function

Returns:

16 bit int in PCB and PCM and 32 bit int for PCH

[PCD] 32 bit int for PCD

Function:

This function obtains the address in ROM of the next instruction after the label. This is not a normally used function except in very special situations.

Availability:

All Devices

Requires:

Examples:

```

start:
    a = (b+c)<<2;
end:
printf("It takes %lu ROM locations.\r\n",
    label_address(end)-label_address(start))

```

Example Files:

setjmp.h

See Also:

goto_address()

labs()

Syntax:

result = labs (*value*)

Parameters:

value is a 16 bit signed long int

[PCD] *value* is a 32, 48 or 64 bit signed long int

Returns:

A 16 bit signed long int

[PCD] A signed long int of type **value**

Function:

Computes the absolute value of a long integer.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
if(labs( target_value - actual_value ) > 500)
    printf("Error is over 500 points\r\n");
```

See Also:

abs()

lcd_contrast()**Syntax:**

lcd_contrast(**contrast**)

Parameters:

contrast is used to set the internal contrast control resistance ladder

Returns:

Undefined

Function:

This function controls the contrast of the LCD segments with a value passed in between 0 and 7. A value of 0 will produce the minimum contrast, 7 will produce the maximum contrast.

Availability:

Only on select devices with built-in LCD Driver Module

Requires:

Examples:

```
lcd_contrast( 0 );          // Minimum Contrast
```



```
lcd_contrast( 7 );      // Maximum Contrast
```

See Also:

[lcd_load\(\)](#), [lcd_symbol\(\)](#), [setup_lcd\(\)](#), [Internal LCD Overview](#)

lcd_load()

Syntax:

`lcd_load ( buffer_pointer, offset, length )`

Parameters:

buffer_pointer - points to the user data to send to the LCD, ***offset*** is the offset into the LCD segment memory to write the data.

length - is the number of bytes to transfer to the LCD segment memory.

Returns:

Undefined

Function:

This function will load ***length*** bytes from ***buffer_pointer*** into the LCD segment memory beginning at ***offset***. The [lcd_symbol\(\)](#) function provides as easier way to write data to the segment memory.

Availability:

Only on select devices with built-in LCD Driver Module

Requires:

Constants are defined in the devices *.h file.

Examples:

```
lcd_load(buffer, 0, 16);
```

Example Files:

[ex_92lcd.c](#)

See Also:

[lcd_symbol\(\)](#), [setup_lcd\(\)](#), [lcd_contrast\(\)](#), [Internal LCD Overview](#)

lcd_symbol()

Syntax:

`lcd_symbol ( symbol, bX_addr );`

Parameters:

symbol is a 8 bit or 16 bit constant.

bX_addr is a bit address representing the segment location to be used for bit X of the specified symbol.

1-16 segments could be specified

Returns:

Undefined

Function:

This function loads the bits for the symbol into the segment data registers for the LCD with each bit address specified. If bit X in symbol is set, the segment at bX_addr is set, otherwise it is cleared. The bX_addr is a bit address into the LCD RAM.

Availability:

Only on select devices with built-in LCD Driver Module

Requires:

Constants are defined in the devices *.h file.

Examples:

```
byte CONST DIGIT_MAP[10] = {0xFC, 0x60, 0xDA, 0xF2, 0x66, 0xB6, 0xBE, 0xE0,
0xFE, 0xE6};

#define DIGIT1    COM1+20, COM1+18, COM2+18, COM3+20, COM2+28, COM1+28,
COM2+20, COM3+18

for(i = 0; i <= 9; i++) {
    lcd_symbol( DIGIT_MAP[i], DIGIT1 );
    delay_ms( 1000 );
}
```

Example Files:

ex_92lcd.c

See Also:

setup_lcd(), lcd_load(), lcd_contrast(), Internal LCD Overview

ldexp()**Syntax:**

result= ldexp (***value***, ***exp***);

Parameters:

value is float

[PCD] **value** any float type

exp is a signed int

Returns:

Result is a float with value result times 2 raised to power exp.

[PCD] Result will have a precision equal to **value**

Function:

The **ldexp()** function multiplies a floating-point number by an integral power of 2.

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
float result;
result=ldexp(.5,0);           // result is .5
```

See Also:

frexp(), exp(), log(), log10(), modf()

load_slave_program()

Syntax:

load_slave_program(**address, instructions**);

Parameters:

address - The address in the Master's program memory that the Slave program is stored at. Because of how the data is stored and written the address must be a multiple of 4.

Instructions - The number of instructions to copy from the Master's Flash to the Slave's PRAM, because of how the data is written the number of instructions must be a multiple of 2.

Returns:

Function:

Copy the Slave program stored in the Master's Flash to the Slave's PRAM.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
load_slave_program(0x10000, 512);
```

See Also:

verify_slave_program()

log()

Syntax:

result= ldexp (*value*, *exp*);

Parameters:

value is float

[PCD] *value* any float type

exp is a signed int

Returns:

Result is a float with value result times 2 raised to power exp

[PCD] Result will have a precision equal to *value*

Function:

Computes the natural logarithm of the float x. If the argument is less than or equal to zero or too large, the behavior is undefined.

Note on error handling: "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Domain error occurs in the following cases: log: when the argument is negative

□

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
lnx = log(x);
```

See Also:

[log10\(\)](#), [exp\(\)](#), [pow\(\)](#)

log10()

Syntax:

result= log10 (**value**)

Parameters:

value is float

[PCD] **value** any float type

exp is a signed int

Returns:

Result is a float with value result times 2 raised to power exp

[PCD] Result will have a precision equal to **value**

Function:

Computes the natural logarithm of the float x. If the argument is less than or equal to zero or too large, the behavior is undefined.

Note on error handling: "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Domain error occurs in the following cases: log10: when the argument is negative

□

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
db = log10( read_adc() * (5.0/255) ) * 10;
```

See Also:

[log\(\)](#), [exp\(\)](#), [pow\(\)](#)

longjmp()

Syntax:

longjmp (*env*, *val*)

Parameters:

env - The data object that will be restored by this function

val -: The value that the function setjmp will return. If val is 0 then the function setjmp will return 1 instead

Returns:

After longjmp is completed, program execution continues as if the corresponding invocation of the setjmp function had just returned the value specified by val

Function:

Performs the non-local transfer of control

□

Availability:

All Devices

Requires:

#INCLUDE <setjmp.h>

Examples:

```
longjmp(jmpbuf, 1);
```

See Also:

[setjmp\(\)](#)

make8()

Syntax:

i8 = MAKE8(*var*, *offset*);

Parameters:

var is a 16 or 32 bit integer.

offset is a byte offset of 0,1,2 or 3

Returns:

8 bit integer

Function:

Extracts the byte at offset from var. Same as: i8 = (((var >> (offset*8)) & 0xff) except it is done with a single byte move

□

Availability:

All Devices

Requires:

Examples:

```
int32 x;
int y;
```

```
y = make8(x, 3);           // Gets MSB of x
```

See Also:

[make16\(\)](#), [make32\(\)](#)

make16()

Syntax:

i16 = MAKE16(*varhigh*, *varlow*)

Parameters:

varhigh and *varlow* are 8 bit integer

Returns:

16 bit integer

Function:

Makes a 16 bit number out of two 8 bit numbers. If either parameter is 16 or 32 bits only the lsb is used. Same as: i16 = (int16)(varhigh&0xff)*0x100+(varlow&0xff) except it is done with two byte moves

□

Availability:

All Devices

Requires:

Examples:

```
long x;
int hi, lo;
```

```
x = make16(hi, lo)
```

Example Files:

[ltc1298.c](#)

See Also:

[make8\(\)](#), [make32\(\)](#)

make32()

Syntax:

i32 = MAKE32(*var1*, *var2*, *var3*, *var4*)

Parameters:

var1-4 are a 8 or 16 bit integers

var2-4 are optional

Returns:

32 bit integer

Function:

Makes a 32 bit number out of any combination of 8 and 16 bit numbers. Note that the number of parameters may be 1 to 4. The msb is first. If the total bits provided is less than 32 then zeros are added at the msb

□

Availability:

All Devices

Requires:

Examples:

```
int32 x;
int y;
long z;
x = make32(1,2,3,4);           // x is 0x01020304
y=0x12;
z=0x4321;
x = make32(y,z);               // x is 0x00124321

x = make32(y,y,z);             // x is 0x12124321
```

Example Files:

[ex_freqc.c](#)

See Also:

[make8\(\)](#), [make16\(\)](#)

malloc()

Syntax:

`ptr=malloc(size)`

Parameters:

size - is an integer representing the number of bytes to be allocated

Returns:

A pointer to the allocated memory, if any. Returns null otherwise

Function:

The malloc function allocates space for an object whose size is specified by size and whose value is indeterminate

□

Availability:

All Devices

Requires:

`#INCLUDE <stdlib.h>`

Examples:

```
int * iptr;
iptr=malloc(10);           // iptr will point to a block of memory of
10 bytes
```

See Also:

[realloc\(\)](#), [free\(\)](#), [calloc\(\)](#)

memcpy() memmove()

Syntax:

`memcpy(destination, source, n)`
`memmove(destination, source, n)`

Parameters:

destination - is a pointer to the destination memory

source - is a pointer to the source memory

n - is the number of bytes to transfer

Returns:

Undefined

Function:

Copies **n** bytes from source to destination in RAM. Be aware that array names are pointers where other variable names and structure names are not (and therefore need a & before them).

memmove() performs a safe copy (overlapping objects does not cause a problem). Copying takes place as if the **n** characters from the source are first copied into a temporary array of **n** characters that does not overlap the destination and source objects. Then the **n** characters from the temporary array are copied to destination.

□

Availability:

All Devices

Requires:

Examples:

```
memcpy(&structA, &structB, sizeof (structA));
memcpy(arrayA, arrayB, sizeof (arrayA));
memcpy(&structA, &databyte, 1);
```

```
char a[20]="hello";
memmove(a, a+2, 5); // a is now "llo"
```

See Also:

[strcpy\(\)](#), [memset\(\)](#)

memset()

Syntax:

memset (*destination*, *value*, *n*)

Parameters:

destination - is a pointer to memory.

value - is a 8 bit int

n - is a 16 bit int

PCB and PCM parts n can only be 1-255.

Returns:

Undefined

Function:

Sets n number of bytes, starting at destination, to value. Be aware that array names are pointers where other variable names and structure names are not (and therefore need a & before them).

□

Availability:

All Devices

Requires:

Examples:

```
memset(arrayA, 0, sizeof(arrayA));
memset(arrayB, '?', sizeof(arrayB));
memset(&structA, 0xFF, sizeof(structA))
```

See Also:

[memcpy\(\)](#)

modf()**Syntax:**

result= modf (*value*, & *integral*)

Parameters:

value is a float

[PCD] **value** is any float type

integral is a float

[PCD] **integral** is any float type

Returns:

Result is a float

[PCD] Result is a float with precision equal to **value**

Function:

The **modf()** function breaks the argument value into integral and fractional parts, each of which has the same sign as the argument. It stores the integral part as a float in the object integral.

□

Availability:

All Devices

Requires:

```
#INCLUDE <math.h>
```

Examples:

```
float result, integral;
result=modf(123.987,&integral);    // result is .987 and integral is
123.000
```

msi_fifo_status()**Syntax:**

```
Status = smi_fifo_status();
```

Parameters:

```
-----
```

Returns:

An int16 value indicating the status of the MSI FIFO registers. See the device's header file for defines that can be and'ed with return value to determine if the corresponding status bits are set.

Function:

Read the status bits from the FIFO Control/Status register from the Master Slave Interface (MSI) peripheral.

Availability:

Only available on Dual Core devices.

Requires:

```
-----
```

Examples:

```
unsigned int16 Status;
unsigned int16 Value;

Status = msi_fifo_status();

if((Status & MSI_READ_FIFO_EMPTY) == FALSE)
    Value = smi_read_fifo();
```

See Also:

[msi_write_mailbox\(\)](#), [msi_read_mailbox\(\)](#), [msi_status\(\)](#), [msi_read_fifo\(\)](#),
[msi_mailbox_status\(\)](#),
[msi_write_fifo\(\)](#), [setup_msi\(\)](#)

msi_mailbox_status()

Syntax:

Status = msi_mailbox_status();

Parameters:

Returns:

An int8 value indicating whether the mailbox associated with corresponding handshake protocol has data to be read. Bit 0 is for handshake protocol A, Bit 1 is for handshake protocol B, etc. If the corresponding bit is a 1, then mailbox registers have been written, i.e. has data to be read. If bit is a 0, then mailbox registers have not been written, i.e. has no data to be read, or the corresponding handshake protocol block is disabled.

Function:

Read the MSI1MBSX, master core, or SI1MBSX, slave core, register from the Master Slave Interface (MSI) peripheral. This is used to determine if mailboxes associated with the corresponding handshake protocols have data to red or can be written.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```

unsigned int16 Status;

unsigned int16 Value;

Status = msi_mailbox_status():

if(bit_tst(Status, 0) ==1)      //check if protocol A has data to read
    Value = msi_read_mailbox(0);

```

See Also:

[msi_write_mailbox\(\)](#), [msi_read_mailbox\(\)](#), [msi_status\(\)](#), [msi_read_fifo\(\)](#), [msi_write_fifo\(\)](#), [setup_msi\(\)](#), [msi_fifo_status\(\)](#)

msi_read_fifo()

Syntax:

Success = msi_read_fifo(*data);

Parameters:

Data - pointer to int16 variable to return read data to.

Returns:

True if data was successfully read from FIFO, FALSE if data was not read.

Function:

Read from the read FIFO register from the Master Slave Interface (MSI) peripheral. Additionally, the function checks the corresponding Read FIFO Empty Status bit from the FIFO Control/Status Register and only performs the read if the Status bit indicates that the read FIFO buffer is not empty. This is to keep a read underflow from happening.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
unsigned int16 Status;  
unsigned int16 Value;  
  
Status = msi_read_fifo(&Value);
```

See Also:

[msi_write_mailbox\(\)](#), [msi_read_mailbox\(\)](#), [msi_status\(\)](#), [msi_fifo_status\(\)](#), [msi_write_fifo\(\)](#), [setup_msi\(\)](#)

msi_read_mailbox()**Syntax:**

Value=msi_read_mailbox(**mailbox**);

Parameters:

mailbox - The mailbox register to read from can be a value from 0 to 15.

Returns:

An int16 value read from the corresponding mailbox register.

Function:

Read one of the mailbox registers from the Master Slave Interface (MSI) peripheral. The direction of the mailbox registers depends on how the associated configuration bits are set.

This function should only be used to read mailbox registers that are set as read registers for the corresponding core.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
unsigned int16 Value;  
  
unsigned int8 Mailbox = 0;  
  
Value = msi_read_mailbox(Mailbox);    //reads mailbox 0 register
```

See Also:

msi_write_mailbox(), msi_status(), msi_read_fifo(), msi_mailbox_status(),
msi_write_fifo(), setup_msi(), msi_fifo_status()

msi_status()**Syntax:**

Status=msi_status();

Parameters:**Returns:**

The status of the MSI peripheral. See the device's header file for the defines that can be and'd with return value to determine if the corresponding status bits are set.

Function:

Read the MSI1STAT, master core, or SI1STAT, slave core, register from the Master Slave Interface (MSI) peripheral.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
unsigned int16 Status;  
  
Status=msi_status();
```

```
if((Status & MSI_SLAVE_IN_RESET) == MSI_SLAVE_IN_RESET)
    setup_msi(MSI_SLAVE_ENABLE);
```

See Also:

[msi_write_mailbox\(\)](#), [msi_read_mailbox\(\)](#), [msi_read_fifo\(\)](#), [msi_mailbox_status\(\)](#),
[msi_write_fifo\(\)](#), [setup_msi\(\)](#), [msi_fifo_status\(\)](#)

msi_write_fifo()**Syntax:**

Success = msi_write_fifo(**data**);

Parameters:

Data - int16 data to write to FIFO register..

Returns:

True if data was successfully written to FIFO, FALSE is data was not written..

Function:

Write data to the write FIFO register from the Master Slave Interface (MSI) peripheral. Additionally, the function checks the corresponding Write FIFO Empty Status bit from the FIFO Control/Status Register and only performs the write, the Status bit indicates that the write FIFO buffer is not full. This is to keep a write underflow from happening.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
unsigned int16 Status;
unsigned int16 Value = 0x1122;

Status = msi_write_fifo(Value);
```

See Also:

[msi_write_mailbox\(\)](#), [msi_read_mailbox\(\)](#), [msi_status\(\)](#), [msi_read_fifo\(\)](#),
[msi_fifo_status\(\)](#),
[setup_msi\(\)](#)

msi_write_mailbox()

Syntax:

```
msi_write_mailbox(mailbox, data);
```

Parameters:

mailbox - The mailbox register to write from can be a value from 0 to 15.

data - An int16 value to write to the mailbox register.

Returns:

Function:

Write to one of the mailbox registers from the Master Slave Interface (MSI) peripheral.

The direction of the mailbox registers depends how the associated configuration bits are set. This function should only be used to read mailbox registers that are set as write registers for the corresponding core.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
unsigned int16 Value = 0x1122;

unsigned int8 Mailbox = 0;

msi_write_mailbox(Mailbox, Value);    //writes mailbox 0 register
```

See Also:

msi_read_mailbox(), msi_mailbox_status(), msi_read_fifo(), msi_write_fifo(), msi_fifo_status(), setup_msi()

mul()

Syntax:

```
prod=_mul(val1, val2);
```

Parameters:

val1 and **val2** are both 8-bit or 16-bit integers

[PCD] **val1** and **val2** are both 8-bit, 16-bit, or 48-bit integers

Returns:

A 16-bit integer if both parameters are 8-bit integers, or a 32-bit integer if both parameters are 16-bit integers.

[PCD]

<i>val1</i>	<i>val2</i>	<i>prod</i>
8	8	16
16*	16	32
32*	32	64
48*	48	64**

* or less

** large numbers will overflow with wrong results

Function:

Performs an optimized multiplication. By accepting a different type than it returns, this function avoids the overhead of converting the parameters to a larger type.

□

Availability:

All Devices

Requires:

Examples:

```
int a=50, b=100;
long int c;
c = _mul(a, b);           //c holds 5000
```

nargs()**Syntax:**

```
void foo(char * str, int count, ...)
```

Parameters:

The function can take variable parameters. The user can use stdarg library to create functions that take variable parameters.

Returns:

Function dependent

Function:

The stdarg library allows the user to create functions that supports variable arguments.

The function that will accept a variable number of arguments must have at least one actual, known parameters, and it may have more. The number of arguments is often passed to the function in one of its actual parameters. If the variable-length argument list can involve more than one type, the type information is generally passed as well. Before processing can begin, the function creates a special argument pointer of type `va_list`.

□

Availability:

All Devices

Requires:

`#INCLUDE <stdarg.h>`

Examples:

```
int foo(int num, ...)
{
    int sum = 0;
    int i;
    va_list argptr;
    va_start(argptr, num);           // create special argument pointer
    for(i=0; i<num; i++)             // initialize argptr
        sum = sum + va_arg(argptr, int);
    va_end(argptr);                  // end variable processing
    return sum;
}

void main()
{
    int total;
    total = foo(2,4,6,9,10,2);
}
```

See Also:

[va_start\(\)](#), [va_end\(\)](#), [va_arg\(\)](#)

offset() offsetofbit()**Syntax:**

```
value = offsetof(stype, field);
value = offsetofbit(stype, field);
```

Parameters:

stype - is a structure type name.

field - is a field from the above structure

Returns:

8 bit byte

Function:

These functions return an offset into a structure for the indicated field.

offsetof() returns the offset in bytes and **offsetofbit** returns the offset in bits.

□

Availability:

All Devices

Requires:

#INCLUDE <stddef.h>

Examples:

```
struct time_structure {
    int hour, min, sec;
    int zone : 4;
    int1 daylight_savings;
}
x = offsetof(time_structure, sec);           // x will be 2
x = offsetofbit(time_structure, sec);        // x will be 16
x = offsetof (time_structure,
               daylight_savings);           // x will be 3
x = offsetofbit(time_structure,
               daylight_savings);           // x will be 28total =
foo(2,4,6,9,10,2);
}
```

outputx()

Syntax:

output_a (*value*)

output_b (*value*)

output_c (*value*)

output_d (*value*)

output_e (*value*)

output_f (*value*)

output_g (*value*)

output_h (*value*)

output_j (*value*)

output_k (*value*)

output_l (*value*)

Parameters:

value - is a 8 bit int

[PCD] value - is a 16 bit int

Returns:

Undefined

Function:

Output an entire byte to a port. The direction register is changed in accordance with the last specified `#USE *_IO` directive.

[PCD] Output an entire word to a port. The direction register is changed in accordance with the last specified `#USE *_IO` directive.

Availability:

All Device that include all ports (A-E)

Requires:

Examples:

```
OUTPUT_B(0xf0);
```

Example Files:

ex_patq.c

See Also:

input(), output_low(), output_high(), output_float(), output_bit(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_bit()**Syntax:**

`output_bit` (*pin*, *value*)

Parameters:

pins - defined in the devices .h file. The actual number is a bit address. For example, port a (byte 5) bit 3 would have a value of $5*8+3$ or 43. This is defined as follows: `#DEFINE PIN_A3 43`. The PIN could also be a variable. The variable must have a value equal to one of the constants (like `PIN_A1`) to work properly. The tristate register is updated unless the `FAST_IO` mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCD] ***pins*** - defined in the devices .h file. The actual number is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of $0x2C2*8+3$ or 5651. This is defined as follows: `#define PIN_A3 5651`.

value is a 1 or a 0.

Returns:

Undefined

Function:

Outputs the specified value (0 or 1) to the specified I/O pin. The method of setting the direction register is determined by the last `#USE*_IO` directive.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
output_bit(PIN_B0, 0);           // Same as
output_low(pin_B0);
output_bit(PIN_B0, input(PIN_B1)); // Make pin B0 the same as
B1

output_bit(PIN_B0, shift_left(&data, 1, input(PIN_B1))); // Output
the MSB of data to
// B0 and at the same time
// shift B1 into the LSB of

data
int16 i=PIN_B0;
output_bit(i, shift_left(&data, 1, input(PIN_B1))); //same as
above example, but
//uses a variable instead of
a constant
```

Example Files:

ex_extee.c with 9356.c

See Also:

input(), output_low(), output_high(), output_float(), output_x(), #USE_FIXED_IO, #USE_FAST_IO, #USE_STANDARD_IO, General Purpose I/O

output_drive()**Syntax:**

`output_drive(pin)`

Parameters:

pins - are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of $5*8+3$ or 43. This is defined as follows: `#DEFINE PIN_A3 43`. The PIN could also be a variable. The variable must have a value equal to one of the constants (like `PIN_A1`) to work properly. The tristate register is updated unless the `FAST_IO` mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCD] pins - are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of $0x2C2*8+3$ or 5651. This is defined as follows: `#DEFINE PIN_A3 5651`.

Returns:

Undefined

Function:

Sets the specified pin to the output mode.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
output_drive(pin_A0);           // sets pin_A0 to output its
value
output_bit(pin_B0, input(pin_A0)) // makes B0 the same as A0
```

See Also:

[input\(\)](#), [output_low\(\)](#), [output_high\(\)](#), [output_bit\(\)](#), [output_x\(\)](#), [output_float\(\)](#)

output_float()

Syntax:

`output_float(pin)`

Parameters:

pins - are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of $5*8+3$ or 43. This is defined as follows: `#DEFINE PIN_A3 43`. The PIN could also be a variable. The variable must have a value equal to one of the constants (like `PIN_A1`) to work properly. The tristate register is updated unless the `FAST_IO` mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCD] pins - are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of 0x2C2*8+3 or 5651. This is defined as follows: `#DEFINE PIN_A3 5651`.

Returns:

Undefined

Function:

Sets the specified pin to the input mode. This will allow the pin to float high to represent a high on an open collector type of connection.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
if( (data & 0x80)==0 )
    output_low(pin_A0);
else
    output_float(pin_A0);
```

See Also:

[input\(\)](#), [output_low\(\)](#), [output_high\(\)](#), [output_bit\(\)](#), [output_x\(\)](#), [output_drive\(\)](#), [#USE FIXED_IO](#), [#USE FAST_IO](#), [#USE STANDARD_IO](#), [General Purpose I/O](#)

output_high()

Syntax:

`output_high(pin)`

Parameters:

pin to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43. This is defined as follows: `#DEFINE PIN_A3 43`. The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCD] pin to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of 0x2C2*8+3 or 5651. This is defined as follows: `#DEFINE PIN_A3 5651`.

Returns:

Undefined

Function:

Sets a given pin to the high state. The method of I/O used is dependent on the last USE *_IO directive.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
output_high(PIN_A0);
```

```
Int16 i=PIN_A1;
output_low(PIN_A1);
```

Example Files:ex_sqw.c**See Also:**

input(), output_low(), output_float(), output_bit(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_low()**Syntax:**

output_low(pin)

Parameters:

pin to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43. This is defined as follows: #DEFINE PIN_A3 43. The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCDJ] pin to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of 0x2C2*8+3 or 5651. This is defined as follows: #DEFINE PIN_A3 5651.

Returns:

Undefined

Function:

Sets a given pin to the ground state. The method of I/O used is dependent on the last `USE *_IO` directive.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
output_low(PIN_A0);
```

```
Int16i=PIN_A1;
output_low(PIN_A1);
```

Example Files:

ex_sqw.c

See Also:

input(), output_high(), output_float(), output_bit(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_toggle()**Syntax:**

`output_toggle(pin)`

Parameters:

pin to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of $5*8+3$ or 43. This is defined as follows: `#DEFINE PIN_A3 43`. The PIN could also be a variable. The variable must have a value equal to one of the constants (like `PIN_A1`) to work properly. The tristate register is updated unless the `FAST_IO` mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

[PCD] ***pin*** to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 0x2C2) bit 3 would have a value of $0x2C2*8+3$ or 5651. This is defined as follows: `#DEFINE PIN_A3 5651`.

Returns:

Undefined

Function:

Toggles the high/low state of the specified pin.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
output_toggle(PIN_B4);
```

See Also:

[input\(\)](#), [output_high\(\)](#), [output_low\(\)](#), [output_bit\(\)](#), [output_x\(\)](#)

perror()**Syntax:**

perror(*string*);

Parameters:

string is a constant string or array of characters (null terminated)

Returns:

Function:

This function prints out to STDERR the supplied string and a description of the last system error (usually a math error).

Availability:

All Devices

Requires:

#USE RS232, #INCLUDE <errno.h>, #INCLUDE<stdio.h>

Examples:

```
x = sin(y);
```

```
if(errno!=0)
```

```
perror("Problem in find_area");
```

See Also:

[RS232 I/O Overview](#)

pid_busy()

Syntax:

```
result = pid_busy();
```

Parameters:

Returns:

Function:

TRUE if PID module is busy or FALSE if PID module is not busy

Availability:

All Devices with a PID Module

Requires:

Examples:

```
pid_get_result(PID_START_ONLY, ADCResult);
while(pid_busy());
pid_get_result(PID_READ_ONLY, &PIDResult);
```

See Also:

[setup_pid\(\)](#), [pid_write\(\)](#), [pid_get_result\(\)](#), [pid_read\(\)](#)

pid_get_result()

Syntax:

```
pid_get_result(set_point, input, &output);
pid_get_result(mode, set_point, input);
pid_get_result(mode, &output);
pid_get_result(mode, set_point, input, &output);
```

Parameters:

mode - constant parameter specifying whether to only start the calculation, only read the result, or start the calculation and read the result. The options are defined in the device's header file as:

- `pd_start_read`
- `pid_read_only`
- `pid_start_only`

set_point - a 16-bit variable or constant representing the set point of the control system, the value the input from the control system is compared against to determine the error in the system.

input - a 16-bit variable or constant representing the input from the control system.

output - a structure that the output of the PID module will be saved to. Either pass the address of the structure as the parameter, or a pointer to the structure as the parameter.

Returns:

Function:

To pass the set point and input from the control system to the PID module, start the PID calculation and get the result of the PID calculation. The PID calculation starts, automatically when the input is written to the PID module's input registers.

Availability:

All Devices with a PID Module

Requires:

Constants are defined in the device's .h file

Examples:

```
pid_get_result(SetPoint, ADCResult, &PIDOutput);           //Start
and Read
pid_get_result(PID_START_ONLY, SetPoint, ADCResult);       //Start
Only
pid_get_result(PID_READ_ONLY, &PIDResult);                 //Read
Only
```

See Also:

[setup_pid\(\)](#), [pid_read\(\)](#), [pid_write\(\)](#), [pid_busy\(\)](#)

pid_read()

Syntax:

`pid_read(register, &output);`

Parameters:

register- constant specifying which PID registers to read. The registers that can be written are defined in the device's header file as:

- `pid_addr_accumulator`
- `pid_addr_output`
- `pid_addr_z1`
- `pid_addr_z2`
- `pid_addr_k1`
- `pid_addr_k2`
- `pid_addr_k3`

output -a 16-bit variable, 32-bit variable or structure that specified PID registers value will be saved to. The size depends on the registers that are being read. Either pass the address of the variable or structure as the parameter, or a pointer to the variable or structure as the parameter.

Returns:

Function:

To read the current value of the Accumulator, Output, Z1, Z2, Set Point, K1, K2 or K3 PID registers. If the PID is busy with a calculation the function will wait for module to finish calculation before reading the specified register.

Availability:

All Devices with a PID Module

Requires:

Constants are defined in the device's .h file

Examples:

```
pid_read(PID_ADDR_Z1, &value_z1);
```

See Also:

[setup_pid\(\)](#), [pid_write\(\)](#), [pid_get_result\(\)](#), [pid_busy\(\)](#)

pid_write()

Syntax:

```
pid_write(register, &output);
```

Parameters:

register- constant specifying which PID registers to read. The registers that can be written are defined in the device's header file as:

```
pid_addr_accumulator
pid_addr_output
pid_addr_z1
pid_addr_z2
pid_addr_k1
pid_addr_k2
pid_addr_k3
```

output -a 16-bit variable, 32-bit variable or structure that specified PID registers value will be saved to. The size depends on the registers that are being read. Either pass the address of the variable or structure as the parameter, or a pointer to the variable or structure as the parameter.

Returns:

Function:

To write a new value for the Accumulator, Output, Z1, Z2, Set Point, K1, K2 or K3 PID registers. If the PID is busy with a calculation the function will wait for module to finish the calculation before writing the specified register.

Availability:

All Devices with a PID Module

Requires:

Constants are defined in the device's .h file

Examples:

```
pid_write(PID_ADDR_Z1, &value_z1);
```

See Also:

setup_pid(), pid_read(), pid_get_result(), pid_busy()

pin_select()

Syntax:

`pin_select(peripheral_pin, pin, [unlock],[lock])`

Parameters:

peripheral_pin – a constant string specifying which peripheral pin to map the specified pin to. Refer to #pin_select for all available strings. Using “NULL” for the peripheral_pin parameter will unassign the output peripheral pin that is currently assigned to the pin passed for the pin parameter.

pin – the pin to map to the specified peripheral pin. Refer to device's header file for pin defines. If the peripheral_pin parameter is an input, passing FALSE for the pin parameter will unassign the pin that is currently assigned to that peripheral pin.

unlock – optional parameter specifying whether to perform an unlock sequence before writing the RPINRx or RPORx register register determined by peripheral_pin and pin options. Default is TRUE if not specified. The unlock sequence must be performed to allow writes to the RPINRx and RPORx registers. This option allows calling pin_select() multiple times without performing an unlock sequence each time.

lock – optional parameter specifying whether to perform a lock sequence after writing the RPINRx or RPORx registers. Default is TRUE if not specified. Although not necessary it is a good idea to lock the RPINRx and RPORx registers from writes after all pins have been mapped. This option allows calling pin_select() multiple times without performing a lock sequence each time.

Returns:

Availability:

On device with remappable peripheral pins.

Requires:

Pin defines in device's header file.

Examples:

```

pin_select("U2TX",PIN_B0);           //Maps PIN_B0 to U2TX
peripheral_pin,                     //performs unlock and lock
sequences.

pin_select("U2TX",PIN_B0,TRUE,FALSE); //Maps PIN_B0 to U2TX
peripheral_pin
```



```

sequence.                                     //and performs unlock

pin_select("U2RX",PIN_B1,FALSE,TRUE); //Maps PIN_B1 to U2RX
peripheral pin

sequence.                                     //and performs lock

```

See Also:#pin_select**pll_locked()****Syntax:**

result=pll_locked();

Parameters:

Returns:

A short int.

TRUE if the PLL is locked/ready,

FALSE if PLL is not locked/ready

Function:

Allows testing the PLL Ready Flag bit to determined if the PLL is stable and running.

Availability:

All Devices with a Phase Locked Loop (PLL).

Not all devices have a PLL Ready Flag, for those devices the pll_locked() function will always return TRUE

Requires:

Examples:

```
while(!pll_locked())
```

See Also:#use delay

pmp_address(address)

Syntax:

pmp_address (*address*);

Parameters:

address- The address which is a 16 bit destination address value. This will setup the address register on the PMP module and is only used in Master mode.

Returns:

Undefined

Function:

Configures the address register of the PMP module with the destination address during Master mode operation. The address can be either 14, 15 or 16 bits based on the multiplexing used for the Chip Select Lines 1 and 2.

Availability:

All Devices with a built-in Parallel Port Module

Requires:

Examples:

```
pmp_address( 0x2100);           // Sets up Address register to
0x2100
```

See Also:

[setup_pmp\(\)](#), [pmp_address\(\)](#), [pmp_read\(\)](#), [psp_read\(\)](#), [psp_write\(\)](#), [pmp_write\(\)](#),
[psp_output_full\(\)](#), [psp_input_full\(\)](#), [psp_overflow\(\)](#), [pmp_output_full\(\)](#),
[pmp_input_full\(\)](#),[pmp_overflow\(\)](#)

pmp_output_full() pmp_input_full() pmp_overflow() pmp_error() pmp_timeout()

Syntax:

```
result = pmp_output_full()
result = pmp_input_full()
result = pmp_overflow()
result = pmp_error()
result = pmp_timeout()
```

Parameters:

Returns:

A 0 (FALSE) or 1 (TRUE)

Function:

These functions check the Parallel Port for the indicated conditions and return TRUE or FALSE.

Availability:

Only available on devices with Parallel Port

Requires:

Examples:

```
while (pmp_output_full());
pmp_data = command;
while(!pmp_input_full());
if ( pmp_overflow() )
    error = TRUE;
else
    data = pmp_data
```

See Also:

setup_pmp(), pmp_write(), pmp_read()

pmp_read()**Syntax:**

```
result = pmp_read ( );
result = pmp_read8(address);
result = pmp_read16(address);
pmp_read8(address,pointer,count);
pmp_read16(address,pointer,count);
```

Parameters:

address- EPMP only, address in EDS memory that is mapped to address from parallel port device to read data from or start reading data from. (All address in EDS memory are word aligned)

pointer- EPMP only, pointer to array to read data to.

count- EPMP only, number of bytes to read. For `pmp_read16()` number of bytes must be even.

Returns:

For `pmp_read()`, `pmp_read8(address)` or `pmp_read16()` an 8 or 16 bit value. For `pmp_read8(address,pointer,count)` and `pmp_read16(address,pointer,count)` undefined.

Function:

For PMP module, this will read a byte from the next buffer location. For EPMP module, reads one byte/word or count bytes of data from the address mapped to the EDS memory location. The address is used in conjunction with the offset address set with the `setup_pmp_cs1()` and `setup_pmp_cs2()` functions to determine which address lines are high or low during the read.

Availability:

Only available on devices with Parallel Port or an Enhanced Parallel Master Port module.

Requires:

Examples:

```
result = pmp_read();           //PMP reads next byte of data
result = pmp_read8(0x8000);    //EPMP reads byte of data from
the                             //address mapped to first address
in                             //EDS memory.
pmp_read16(0x8002,ptr,16);     //EPMP reads 16 bytes of data and
ptr                             //returns to array pointed to by
address                         //starting at address mapped to
                                //0x8002 in EDS memory
```

See Also:

`setup_pmp()`, `setup_pmp_csx()`, `pmp_address()`, `pmp_read()`, `psp_read()`, `psp_write()`, `pmp_write()`, `psp_output_full()`, `psp_input_full()`, `psp_overflow()`, `pmp_output_full()`, `pmp_input_full()`, `pmp_overflow()`

pmp_write()

Syntax:

`pmp_write (data);`

```
pmp_write8(address,data);
pmp_write8(address,pointer,data);
pmp_write16(address,data);
pmp_write16(address,pointer,data);
```

Parameters:

data- The byte of data to be written.

address- EPMP only, address in EDS memory that is mapped to address from parallel port device to write data to or start writing data to. (All addresses in EDS memory are word aligned)

pointer- EPMP only, pointer to data to be written

count- EPMP only, number of bytes to write. For pmp_write16() number of bytes must be even.

Returns:

Undefined

Function:

For PMP modules, this will write a byte of data to the next buffer location. For EPMP modules writes one byte/word or count bytes of data from the address mapped to the EDS memory location. The address is used in conjunction with the offset address set with the setup_pmp_cs1() and setup_pmp_cs2() functions to determine which address lines are high or low during write.

Availability:

Only available on devices with Parallel Port or an Enhanced Parallel Master Port module.

Requires:

Examples:

```
pmp_write( data );           //Write the data byte to
                             //the next buffer location.
pmp_write8(0x8000,data);     //EPMP writes the data byte to
                             //the address mapped to the first
                             //location in EDS memory.
pmp_write16(0x8002,ptr,16);  //EPMP writes 16 bytes of data
pointed                      //to by ptr starting at address
mapped                      //to address 0x8002 in EDS memory.
```

See Also:

setup_pmp(), setup_pmp_csx(), pmp_address(), pmp_read(), psp_read(), psp_write(), pmp_write(), psp_output_full(), psp_input_full(), psp_overflow(), pmp_output_full(), pmp_input_full(), pmp_overflow()

port_a_current_source()

Syntax:

`port_a_current_source(mask);`

Parameters:

mask - an int8 value indicating which port pins have the weak current source enabled. 1 indicates the weak current source is enabled.

Returns:

Function:

Used to enable and disable the weak current source on port A pins.

Availability:

Devices that have a weak current source on some of the port A pins.

Requires:

Examples:

```
port_a_current_source(0x0C);           //enables weak current source
                                         //on PIN_A2 and PIN_A3.
```

See Also:

set_tris_x(), get_trisx(), output_x(), input_x(), input_change_x(), port_x_pullups(), input(), input_state(), output_low(), output_high(), output_toggle(), output_bit(), output_float(), output_drive(), General Purpose I/O

port_x_pullups()

Syntax:

`port_a_pullups(value)`
`port_b_pullups(value)`
`port_d_pullups(value)`
`port_e_pullups(value)`

```
port_j_pullups (value)
port_k_pullups (value)
port_l_pullups (value)
port_x_pullups (upmask)
port_x_pullups (upmask, downmask)
```

Parameters:

value - is TRUE or FALSE on most parts, some parts that allow pullups to be specified on individual pins permit an 8 bit int here, one bit for each port pin.

upmask - for ports that permit pullups to be specified on a pin basis. This mask indicates what pins should have pullups activated. A 1 indicates the pullups is on.

downmask - for ports that permit pulldowns to be specified on a pin basis. This mask indicates what pins should have pulldowns activated. A 1 indicates the pulldowns is on.

Returns:

Undefined

Function:

Sets the input pullups. TRUE will activate, and a FALSE will deactivate.

Availability:

Only 14 and 16 bit devices (PCM and PCH). (Note: use SETUP_COUNTERS on PCB parts).

Requires:

Examples:

```
port_a_pullups (FALSE) ;
```

Example Files:

[ex_lcdkb.c](#), [kbd.c](#)

See Also:

[input\(\)](#), [input_x\(\)](#), [output_float\(\)](#)

pow() pwr()**Syntax:**

f = pow (x,y)

f = pwr (x,y)

Parameters:

x and **y** are of type float

[PCD] **x** and **y** are any float type

Returns:

A float

[PCD] A float with precision equal to function parameters x and y.

Function:

Calculates X to the Y power.

Note on error handling: If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Range error occurs in the following case: pow: when the argument X is negative

Availability:

All Devices

Requires:

#INCLUDE <math.h>

Examples:

```
area = pow (size,3.0)
```

prgx_status()

Syntax:

```
status = prg1_status();
```

```
status = prg2_status();
```

```
status = prg3_status();
```

```
status = prg4_status();
```

Parameters:

Returns:

An 8-bit value indicating the status of the PRGx module. See the device's header file for constants that can be returned by function.

Function:

Used to set the PRGx modules.

Availability:

Devices that have a Programmable Ramp Generator (PRG) module.

Requires:

Examples:

```
int8 Status;  
Status = prgl_status();
```

See Also:

setup_prgx()

printf() fprintf()**Syntax:**

printf (*string*)

or

printf (*cstring, values...*)

or

printf (*fname, cstring, values...*)

fprintf (*stream, cstring, values...*)

Parameters:

String is a constant string or an array of characters null terminated.

C String is a constant string. Note that format specifiers cannot be used in RAM strings.

Values is a list of variables separated by commas, *fname* is a function name to be used for outputting (default is **putc** if none is specified).

Stream is a stream identifier (a constant byte)

Returns:

Undefined

Function:

Outputs a string of characters to either the standard RS-232 pins (first two forms) or to a specified function. Formatting is in accordance with the string argument. When variables are used this string must be a constant. The % character is used within the string to indicate a variable value is to be formatted and output. Longs in the printf may be 16 or 32 bit. A %% will output a single %. Formatting rules for the % follows.

See the Expressions > Constants and Trigraph sections of this manual for other escape character that may be part of the string.

If **fprintf()** is used then the specified stream is used where **printf()** defaults to STDOUT (the last USE RS232).

Format:

The format takes the generic form %nt. n is optional and may be 1-9 to specify how many characters are to be outputted, or 01-09 to indicate leading zeros, or 1.1 to 9.9 for floating point and %w output. t is the type and may be one of the following:

- c** -- string or character
- u** -- unsigned
- d** -- signed int
- Lu** -- long unsigned int
- Ld** -- long signed int
- x** -- hex int (lower case)
- X** -- hex int (upper case)
- Lx** -- hex long int (lower case)
- LX** -- hex long int (upper case)
- f** -- float with truncated decimal
- g** -- float with rounded decimal
- e** -- float in exponential format
- w** -- unsigned int with decimal place inserted. Specify two numbers for *n*.
The first is a total field width. The second is the desired number of decimal places.

Example Formats:

<u>Specifier</u>	<u>Value=0x12</u>	<u>Value=0xfe</u>
%03u	018	254
%u	18	254
%2u	18	*
%5	18	254
%d	18	-2
%x	12	fe
%X	12	FE
%4X	0012	00FE
%3.1w	1.8	25.4

* Result is undefined - Assume garbage.

Availability:

All Devices

Requires:

#USE RS232 (unless fname is used)

Examples:

```
byte  x,y,z;
printf("HiThere");
printf("RTCCValue=>%2x\r\n",get_rtcc());
printf("%2u %X %4X\r\n",x,y,z);
printf(LCD_PUTC, "n=%u",n);
```

Example Files:

[ex_admm.c](#), [ex_lcdkb.c](#)

See Also:

[atoi\(\)](#), [puts\(\)](#), [putc\(\)](#), [getc\(\)](#) (for a stream example), [RS232 I/O Overview](#)

profileout()**Syntax:**

```
profileout(string);
profileout(string, value);
profileout(value);
```

Parameters:

string - is any constant string, and value can be any constant or variable integer.

Despite the length of string the user specifies here, the code profile run-time will actually only send a one or two byte identifier tag to the code profile tool to keep transmission and execution time to a minimum.

Returns:

Undefined

Function:

Typically the code profiler will log and display function entry and exits, to show the call sequence and profile the execution time of the functions. By using **profileout()**, the user can add any message or display any variable in the code profile tool. Most messages sent by **profileout()** are displayed in the 'Data Messages' and 'Call Sequence' screens of the code profile tool.

If a **profileout(string)** is used and the first word of string is "START", the code profile tool will then measure the time it takes until it sees the same **profileout(string)** where the "START" is replaced with "STOP". This measurement is then displayed in the 'Statistics' screen of the code profile tool, using string as the name (without "START" or "STOP")

Availability:

All Devices

Requires:

#use profile() used somewhere in the project source code

Examples:

```

// send a simple string.
profileout("This is a text string"); // send a variable with a
string identifier.
profileout("RemoteSensor=", adc);    // just send a variable.
profileout(adc);                      // time how long a block of
code takes to execute.

// this will be displayed
in the 'Statistics'

// of the Code Profile
tool.
profileout("start my algorithm");
/* code goes here */
profileout("stop my algorithm")

```

Example Files:

ex_profile.c

See Also:

[#use profile\(\)](#), [#profile](#), [Code Profile Overview](#)

psmc blanking()

Syntax:

psmc_blanking(*unit*, *rising_edge*, *rise_time*, *falling_edge*, *fall_time*);

Parameters:

unit - is the PSMC unit number 1-4

rising_edge - are the events that are ignored after the signal activates.

rise_time - is the time in ticks (0-255) that the above events are ignored.

falling_edge - are the events that are ignored after the signal goes inactive.

fall_time - is the time in ticks (0-255) that the above events are ignored.

Events:

```
psmc_event_c1out
psmc_event_c2out
psmc_event_c3out
psmc_event_c4out
psmc_event_in_pin
```

Returns:

Undefined

Function:

This function is used when system noise can cause an incorrect trigger from one of the specified events. This function allows for ignoring these events for a period of time around either edge of the signal. See **setup_psmc()** for a definition of a tick.

Pass a 0 or FALSE for the events to disable blanking for an edge.

Availability:

All Devices with PSMC module

Requires:

psmc_deadband()

Syntax:

```
psmc_deadband(unit,rising_edge,falling_edge);
```

Parameters:

unit - is the PSMC unit number 1-4

rising_edge - is the deadband time in ticks after the signal goes active. If this function is not called, 0 is used.

falling_edge - is the deadband time in ticks after the signal goes inactive. If this function is not called, 0 is used.

Returns:

Undefined

Function:

This function sets the deadband time values. Deadbands are a gap in time where both sides of a complementary signal are forced to be inactive. The time values are in ticks. See **setup_psmc()** for a definition of a tick.

Availability:

All Devices with PSMC module

Requires:

Examples:

```
                                // 5 tick deadband when the signal
goes active.
    psmc_deadband(1, 5, 0)
```

See Also:

[setup_psmc\(\)](#), [psmc_sync\(\)](#), [psmc_blanking\(\)](#), [psmc_modulation\(\)](#), [psmc_shutdown\(\)](#),
[psmc_duty\(\)](#), [psmc_freq_adjust\(\)](#), [psmc_pins\(\)](#)

psmc_duty()**Syntax:**

`psmc_duty(unit, pins_used, pins_active_low);`

Parameters:

unit - is the PSMC unit number 1-4

fall_time - is the time in ticks that the signal goes inactive (after the start of the period) assuming the event PSMC_EVENT_TIME has been specified in the setup_psmc().

Returns:

Undefined

Function:

This function changes the fall time (within the period) for the active signal. This can be used to change the duty of the active pulse. Note that the time is NOT a percentage nor is it the time the signal is active. It is the time from the start of the period that the signal will go inactive. If the rise_time was set to 0, then this time is the total time the signal will be active.

Availability:

All Devices with PSMC module

Requires:

Examples:

```


// For a 10khz PWM, based on Fosc


divided by 1


// the following sets the duty from



// 0% to 100% baed on the ADC reading


while(TRUE) {
    psmc_duty(1, (read_adc()*(int16)10)/25)*
        (getenv("CLOCK")/1000000));
}

```

See Also:

[setup_psmc\(\)](#), [psmc_deadband\(\)](#), [psmc_sync\(\)](#), [psmc_blanking\(\)](#), [psmc_modulation\(\)](#), [psmc_shutdown\(\)](#), [psmc_freq_adjust\(\)](#), [psmc_pins\(\)](#)

psmc_freq_adjust()**Syntax:**

`psmc_freq_adjust(unit, freq_adjust);`

Parameters:

unit - is the PSMC unit number 1-4

freq_adjust - is the time in tick/16 increments to add to the period. The value may be 0-15.

Returns:

Undefined

Function:

This function adds a fraction of a tick to the period time for some modes of operation.

Availability:

All Devices with PSMC module

Requires:

See Also:

[setup_psmc\(\)](#), [psmc_deadband\(\)](#), [psmc_sync\(\)](#), [psmc_blanking\(\)](#), [psmc_modulation\(\)](#), [psmc_shutdown\(\)](#), [psmc_dutyt\(\)](#), [psmc_pins\(\)](#)

psmc_modulation()

Syntax:

`psmc_modulation(unit, options);`

Parameters:

unit is the PSMC unit number 1-4

Options may be one of the following:

`psmc_mod_off`
`psmc_mod_active`
`psmc_mod_inactive`
`psmc_mod_c1out`
`psmc_mod_c2out`
`psmc_mod_c3out`
`psmc_mod_c4out`
`psmc_mod_ccp1`
`psmc_mod_ccp2`
`psmc_mod_in_pin`

The following may be OR'ed with the above

`psmc_mod_invert`
`psmc_mod_not_bdf`
`psmc_mod_not_ace`

Returns:

Undefined

Function:

This function allows some source to control if the PWM is running or not. The active/inactive are used for software to control the modulation. The other sources are hardware controlled modulation. There are also options to invert the inputs, and to ignore some of the PWM outputs for the purpose of modulation.

Availability:

All Devices with PSMC module

Requires:

See Also:

[setup_psmc\(\)](#), [psmc_deadband\(\)](#), [psmc_sync\(\)](#), [psmc_blanking\(\)](#), [psmc_shutdown\(\)](#), [psmc_duty\(\)](#), [psmc_freq_adjust\(\)](#), [psmc_pins\(\)](#)

psmc_pins()

Syntax:

psmc_pins(*unit*, *pins_used*, *pins_active_low*);

Parameters:

unit - is the PSMC unit number 1-4

used_pins - is the any combination of the following or'ed together:

psmc_A
psmc_B
psmc_C
psmc_D
psmc_E
psmc_F
psmc_on_next_period

If the last constant is used, all the changes made take effect on the next period (as opposed to immediate)

pins_active_low - is an optional parameter. When used it lists the same pins from above as the pins that should have an inverted polarity.

Returns:

Undefined

Function:

This function identified the pins allocated to the PSMC unit, the polarity of those pins and it enables the PSMC unit. The tri-state register for each pin is set to the output state.

Availability:

All Devices with PSMC module

Requires:

Examples:

```
// Simple PWM, 10khz out on pin C0
assuming a 20mhz crystal
// Duty is initially set to 25%
setup_psmc(1, PSMC)SINGLE,
    PSMC_EVENT_TIME | PSMC_SOURCE_FOSC, us(100,
    PSMC_EVENT_TIME, 0,
    PSMC_EVENT_TIME, us(25));
```

```
psmc_pins(1, PSMC_A);
}
```

See Also:

setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust()

psmc_shutdown()

Syntax:

```
psmc_shutdown(unit, options, source, pins_high);
psmc_shutdown(unit, command);
```

Parameters:

unit - is the PSMC unit number 1-4

Options may be one of the following:

```
psmc_shutdown_
psmc_shutdown_normal
psmc_shutdown_auto_restart
```

command may be one of the following:

```
psmc_shutdown_restart
psmc_shutdown_force
psmc_shutdown_check
```

source may be any of the following or'ed together:

```
psmc_shutdown_c1out
psmc_shutdown_c2out
psmc_shutdown_c3out
psmc_shutdown_c4out
psmc_shutdown_in_pin
```

pins_high is any combination of the following or'ed together:

```
psmc_A
psmc_B
psmc_C
psmc_D
psmc_E
psmc_F
```

Returns:

Non-zero if the unit is now in shutdown

Function:

This function implements a shutdown capability. When any of the listed events activate the PSMC unit will shutdown and the output pins are driven low unless they are listed in the pins that will be driven high.

The auto restart option will restart when the condition goes inactive, otherwise a call with the restart command must be used. Software can force a shutdown with the force command.

Availability:

All Devices with PSMC module

Requires:

See Also:

setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psmc_sync()**Syntax:**

`psmc_sync(slave_unit, master_unit, options);`

Parameters:

slave_unit is the PSMC unit number 1-4 to be controlled.

master_unit is the PSMC unit number 1-4 to be synchronized to

Options may be:

psmc_source_is_phase
psmc_source_is_period
psmc_source_disconnect

The following may be OR'ed with the above:

psmc_invert_duty
psmc_invert_period

Returns:

Non-zero if the unit is now in shutdown

Function:

This function allows one PSMC unit (the slave) to be synchronized (the outputs) with another PSMC unit (the master).

Availability:

All Devices with PSMC module

Requires:

See Also:

[setup_psmc\(\)](#), [psmc_deadband\(\)](#), [psmc_sync\(\)](#), [psmc_modulation\(\)](#), [psmc_shutdown\(\)](#), [psmc_duty\(\)](#), [psmc_freq_adjust\(\)](#), [psmc_pins\(\)](#)

psp_output_full() psp_input_full() psp_overflow() psp_error() psp_timeout()

Syntax:

```
result = psp_output_full()
result = psp_input_full()
result = psp_overflow()
result = psp_error();
result = psp_timeout();
```

Parameters:

Returns:

A 0 (FALSE) or 1 (TRUE)

Function:

These functions check the Parallel Slave Port (PSP) for the indicated conditions and return TRUE or FALSE.

Availability:

All Devices with PSP module

Requires:

Examples:

```
while (psp_output_full()) ;
psp_data = command;
```

```
while(!psp_input_full()) ;  
if ( psp_overflow() )  
    error = TRUE;  
else  
    data = psp_data;
```

Example Files:

[ex_psp.c](#)

See Also:

[setup_psp\(\)](#), [PSP Overview](#)

psp_read()**Syntax:**

```
Result = psp_read ( );  
Result = psp_read (address);
```

Parameters:

address - The address of the buffer location that needs to be read. If address is not specified, use the function **psp_read()** which will read the next buffer location.

Returns:

A byte of data

Function:

psp_read() will read a byte of data from the next buffer location and **psp_read(address)** will read the buffer location **address**.

Availability:

Only the devices with a built in Parallel Master Port module of Enhanced Parallel Master Port module

Requires:

Examples:

```
Result = psp_read();           // Reads next byte of data  
Result = psp_read(3);         // Reads the buffer location 3
```

See Also:

setup_pmp(), pmp_address(), pmp_read(), psp_read(), psp_write(), pmp_write(),
psp_output_full(), psp_input_full(), psp_overflow(), pmp_output_full(),
pmp_input_full(), pmp_overflow()

psp_write**Syntax:**

```
psp_write (data);  
psp_write(address, data);
```

Parameters:

address - The buffer location that needs to be written to

data - The byte of data to be written

Returns:

Undefined

Function:

This will write a byte of data to the next buffer location or will write a byte to the specified buffer location.

Availability:

Only the devices with a built in Parallel Master Port module or Enhanced Parallel Master Port module

Requires:

Examples:

```
psp_write( data ); // Write the data byte to the next buffer  
location
```

See Also:

setup_pmp(), pmp_address(), pmp_read(), psp_read(), psp_write(), pmp_write(),
psp_output_full(), psp_input_full(), psp_overflow(), pmp_output_full(),
pmp_input_full(), pmp_overflow().

putc_send() fputc_send()**Syntax:**

```
putc_send();  
fputc_send(stream);
```

Parameters:

stream – *parameter specifying the stream defined in #USE RS232*

Returns:

Undefined

Function:

Function used to transmit bytes loaded in transmit buffer over RS232. Depending on the options used in #USE RS232 controls if function is available and how it works.

If using hardware UARTx with NOTXISR option it will check if currently transmitting. If not transmitting it will then check for data in transmit buffer. If there is data in transmit buffer it will load next byte from transmit buffer into the hardware TX buffer, unless using CTS flow control option. In that case it will first check to see if CTS line is at its active state before loading next byte from transmit buffer into the hardware TX buffer.

If using hardware UARTx with TXISR option, function only available if using CTS flow control option, it will test to see if the TBEx interrupt is enabled. If not enabled it will then test for data in transmit buffer to send. If there is data to send it will then test the CTS flow control line and if at its active state it will enable the TBEx interrupt. When using the TXISR mode the TBEx interrupt takes care off moving data from the transmit buffer into the hardware TX buffer.

If using software RS232, only useful if using CTS flow control, it will check if there is data in transmit buffer to send. If there is data it will then check the CTS flow control line, and if at its active state it will clock out the next data byte.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
#USE RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50,NOTXISR)
printf("Testing Transmit Buffer");
while(TRUE){
    putc_send();
}
```

See Also:

USE RS232(), rcv_buffer_full(), tx_buffer_full(), tx_buffer_bytes(), getc(), putc(), rintf(), setup_uart(), putc()

pwm_off()

Syntax:

`pwm_on([stream]);`

Parameters:

stream – optional parameter specifying the stream defined in #USE PWM

Returns:

Undefined

Function:

To turn off the PWM signal.

Availability:

All Devices

Requires:

#USE PWM

Examples:

```
#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
while(TRUE) {
    if(kbhit()) {
        c = getc();
        if(c=='O')
            pwm_on();
    }
}
```

See Also:

[#use_pwm](#), [pwm_off\(\)](#), [pwm_set_duty_percent\(\)](#), [pwm_set_duty\(\)](#), [pwm_set_frequency\(\)](#)

pwm_set_duty()

Syntax:

`pwm_set_duty([stream],duty);`

Parameters:

stream – optional parameter specifying the stream defined in #USE PWM.

duty – an int16 constant or variable specifying the new PWM high time

Returns:

Undefined

Function:

To change the duty cycle of the PWM signal. The duty cycle percentage depends on the period of the PWM signal. This function is faster than **`pwm_set_duty_percent()`**, but requires you to know what the period of the PWM signal is.

Availability:

All Devices

Requires:

#USE PWM

Examples:

```
#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
```

See Also:

`#use_pwm`, `pwm_on()`, `pwm_off()`, `pwm_set_frequency()`, `pwm_set_duty_percent()`

`pwm_set_duty_percent()`**Syntax:**

```
pwm_set_duty_percent([stream], percent);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE PWM.

percent- an int16 constant or variable ranging from 0 to 1000 specifying the new PWM duty cycle, 0 is 0% and 1000 is 100.0%.

Returns:

Undefined

Function:

To change the duty cycle of the PWM signal. Duty cycle percentage is based off the current frequency/period of the PWM signal.

Availability:

All Devices

Requires:

#USE PWM

Examples:

```
#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
pwm_set_duty_percent(500); //set PWM duty cycle to 50%
```

See Also:

[#use_pwm](#), [pwm_on\(\)](#), [pwm_off\(\)](#), [pwm_set_frequency\(\)](#), [pwm_set_duty\(\)](#)

pwm_set_frequency()

Syntax:

```
pwm_set_set_frequency([stream],frequency);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE PWM.

frequency – an int32 constant or variable specifying the new PWM frequency.

Returns:

Undefined

Function:

To change the frequency of the PWM signal. Warning this may change the resolution of the PWM signal

Availability:

All Devices

Requires:

#USE PWM

Examples:

```
#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
pwm_set_frequency(1000); //set PWM frequency to 1kHz
```

See Also:

[#use_pwm](#), [pwm_on\(\)](#), [pwm_off\(\)](#), [pwm_set_duty_percent](#), [pwm_set_duty\(\)](#)

pwm1_interrupt_active() **pwm2_interrupt_active()** **pwm3_interrupt_active()** **pwm4_interrupt_active()** **pwm5_interrupt_active()** **pwm6_interrupt_active()**

Syntax:

```
result_pwm1_interrupt_active (interrupt)
result_pwm2_interrupt_active (interrupt)
result_pwm3_interrupt_active (interrupt)
```

result_pwm4_interrupt_active (*interrupt*)
 result_pwm5_interrupt_active (*interrupt*)
 result_pwm6_interrupt_active (*interrupt*)

Parameters:

interrupt - 8-bit constant or variable. Constants are defined in the device's header file as:

```
pwm_period_interrupt
pwm_duty_interrupt
pwm_phase_interrupt
pwm_offset_interrupt
```

Returns:

TRUE if interrupt is active. FALSE if interrupt is not active.

Function:

Tests to see if one of the above PWM interrupts is active, interrupt flag is set.

Availability:

Devices with a 16-bit PWM module

Requires:

#USE PWM

Examples:

```
if (pwm1_interrupt_active(PWM_PERIOD_INTERRUPT))
    clear_pwm1_interrupt(PWM_PERIOD_INTERRUPT)
```

See Also:

[setup_pwm\(\)](#), [set_pwm_duty\(\)](#), [set_pwm_phase\(\)](#), [set_pwm_period\(\)](#), [set_pwm_offset\(\)](#),
[enable_pwm_interrupt\(\)](#), [clear_pwm_interrupt\(\)](#), [disable_pwm_interrupt\(\)](#)

[PCD] qei_get_capture()**Syntax:**

```
value = qei_get_capture();
value = qei_get_capture(unit);
```

Parameters:

unit - optional parameter specifying the QEI unit to read the capture value from. Defaults to 1 if not specified.

Returns:

The 32-bit capture value of the specified QEI unit.

Function:

Used to get the capture value for the specified QEI unit.

Availability:

Some devices that have a QEI module. See the device's header file to determine if function is available.

Requires:

Examples:

```
Unsigned int32 Value;
Value = qei_get_capture(1);
```

See Also:

setup qei(), qei_set_count(), qei_status(), qei_set_index_count(),
qei_get_index_count(), qei_get_velocity_count(), qei_get_interval_count()

qei_get_count()

Syntax:

```
value = qei_get_count( [type] );
[PCD] value = qei_get_count( [unit] );
```

Parameters:

type - Optional parameter to specify which counter to get, defaults to position counter.
Defined in devices .h file as:

```
qei_get_position_count
qei_get_velocity_count
```

[PCD] ***value***- The 16-bit value of the position counter.

[PCD] ***unit***- Optional unit number, defaults to 1.

Returns:

The 16-bit value of the position counter or velocity counter.

[PCD] void

Function:

Reads the current 16-bit value of the position or velocity counter.

[PCD] Reads the current 16-bit value of the position counter.

Availability:

Devices that have the QEI module

Requires:

Examples:

```
value = qei_get_counter(QEI_GET_POSITION_COUNT);
value = qei_get_counter();
value = qei_get_counter(QEI_GET_VELOCITY_COUNT);
[PCD] value = qei_get_counter();
```

See Also:

setup_qei(), qei_set_count(), qei_status()

[PCD] qei_get_index_count()

Syntax:

```
value = qei_get_index_count();
value = qei_get_index_count(unit);
```

Parameters:

unit - optional parameter specifying the QEI unit to read the index count value from.
Defaults to 1 if not specified.

Returns:

The 32-bit index count for the specified QEI unit.

Function:

Used to get the index count for the specified QEI unit.

Availability:

Some devices that have a QEI module. See the device's header file to determine if function is available.

Requires:

Examples:

```
Unsigned int32 IndexCount;
IndexCount = qei_get_index_count(1);
```

See Also:

[setup qei\(\)](#), [qei_set_count\(\)](#), [qei_status\(\)](#), [qei_set_index_count\(\)](#), [qei_get_capture\(\)](#), [qei_get_velocity_count\(\)](#), [qei_get_interval_count\(\)](#)

[PCD] qei_get_interval_count()

Syntax:

```
value = qei_get_interval_count();
value = qei_get_interval_count(unit);
```

Parameters:

unit - optional parameter specifying the QEI unit to read the interval count value from. Defaults to 1 if not specified.

Returns:

The 32-bit interval count for the specified QEI unit.

Function:

Used to get the interval count for the specified QEI unit.

Availability:

Some devices that have a QEI module. See the device's header file to determine if function is available.

Requires:

Examples:

```
Unsigned int32 IntervalCount;
IntervalCount = qei_get_interval_count(1);
```

See Also:

[setup qei\(\)](#), [qei_set_count\(\)](#), [qei_status\(\)](#), [qei_set_index_count\(\)](#), [qei_get_capture\(\)](#), [qei_get_velocity_count\(\)](#), [qei_get_index_count\(\)](#)

[PCD] qei_get_velocity_count()

Syntax:

```
value = qei_get_velocity_count();
value = qei_get_velocity_count(unit);
```

Parameters:

unit - optional parameter specifying the QEI unit to read the velocity count value from. Defaults to 1 if not specified.

Returns:

The 16-bit velocity count for the specified QEI unit.

Function:

Used to get the velocity count for the specified QEI unit.

Availability:

Some devices that have a QEI module. See the device's header file to determine if function is available.

Requires:

Examples:

```
Unsigned int32 VelocityCount;
VelocityCount = qei_get_velocity_count(1);
```

See Also:

[setup_qei\(\)](#), [qei_set_count\(\)](#), [qei_status\(\)](#), [qei_set_index_count\(\)](#), [qei_get_capture\(\)](#), [qei_get_interval_count\(\)](#), [qei_get_index_count\(\)](#)

qei_set_count()

Syntax:

```
qei_set_count( value );
[PCD] qei_set_count( [unit,] value )
```

Parameters:

value - The 16-bit value of the position counter.

[PCD] **value** - The 16-bit value of the position counter.

[PCD] **unit**- Optional unit number, defaults to 1.

Returns:

Void

Function:

Write a 16-bit value to the position counter.

Availability:

Devices that have the QEI module

Requires:

Examples:

```
qei_set_counter(value);
```

See Also:

setup_qei(), qei_get_count(), qei_status()

[PCD] qei_set_index_count()

Syntax:

```
qei_set_index_count();  
qei_set_index_count(unit, count);
```

Parameters:

unit - optional parameter specifying the QEI unit to set the index count value from.
Defaults to 1 if not specified.

count - the 32-bit value to set the index count to.

Returns:

Function:

Used to set the index count for the specified QEI unit.

Availability:

Some devices that have a QEI module. See the device's header file to determine if function is available.

Requires:

Examples:

```
qei_set_index_count(1, 500);
```

See Also:

setup_qei(), qei_set_count(), qei_status(), qei_get_velocity_count(),
qei_get_capture(), qei_get_interval_count(), qei_get_index_count()

qei_status()

Syntax:

```
status = qei_status( );  
[PCD] status = qei_status( [unit] );
```

Parameters:

None

[PCD] **status**- The status of the QEI module

[PCD] **unit**- Optional unit number, defaults to 1

Returns:

The status of the QEI module.

[PCD] Void

Function:

Returns the status of the QEI module.

[PCD] Returns the status of the QEI module

Availability:

Devices that have the QEI module

Requires:

Examples:

```
status = qei_status( );
```

See Also:

setup qei() , qei set count() , qei get count()

qsort()

Syntax:

```
qsort (base, num, width, compare)
```

Parameters:

base: Pointer to array of sort data

num: Number of elements

width: Width of elements

compare: Function that compares two elements

Returns:

Function:

Performs the shell-metzner sort (not the quick sort algorithm). The contents of the array are sorted into ascending order according to a comparison function pointed to by compare

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
int nums[5]={ 2,3,1,5,4};
int compar(void *arg1,void *arg2);

void main()  {
    qsort ( nums, 5, sizeof(int), compar);
}

int compar(void *arg1,void *arg2)  {
    if (* (int *) arg1 < (* (int *) arg2) return -1
    else if (* (int *) arg1 == (* (int *) arg2) return 0
    else return 1;
}
```

Example Files:

[ex_qsort.c](#)

See Also:

[bsearch\(\)](#)

rand()**Syntax:**

re=rand()

Parameters:

Returns:

A pseudo-random integer

Function:

The rand function returns a sequence of pseudo-random integers in the range of 0 to RAND_MAX.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
int I;  
I=rand();
```

See Also:

[srand\(\)](#)

rcv_buffer_bytes()**Syntax:**

value = rcv_buffer_bytes([**stream**]);

Parameters:

stream – optional parameter specifying the stream defined in #USE RS232

Returns:

Number of bytes in receive buffer that still need to be retrieved

Function:

Function to determine the number of bytes in receive buffer that still need to be retrieve

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
#USE_RS232(UART1,BAUD=9600,RECEIVE_BUFFER=100)  
void main(void) {  
    char c;  
    if(rcv_buffer_bytes() > 10)  
        c = getc();  
}
```

See Also:

USE_RS232(), rcv_buffer_full(), tx_buffer_full(), tx_buffer_bytes(), getc(), putc(), printf(), setup_uart(), putc_send()

rcv_buffer_full()

Syntax:

```
value = rcv_buffer_full([stream]);
```

Parameters:

stream – optional parameter specifying the stream defined in #USE_RS232

Returns:

TRUE if receive buffer is full, FALSE otherwise

Function:

Function to test if the receive buffer is full

Availability:

All Devices

Requires:

#USE_RS232

Examples:

```
#USE_RS232(UART1,BAUD=9600,RECEIVE_BUFFER=100)
void main(void) {
    char c;
    if(rcv_buffer_full())
        c = getc();
}
```

See Also:

USE_RS232(), rcv_buffer_full(), tx_buffer_bytes(), tx_buffer_bytes(), getc(), putc(), printf(), setup_uart(), putc_send()

read_adc() [PCD] read_adc2()

Syntax:

```
value = read_adc ([mode])
```

```
[PCD] value = read_adc2 ([mode])
```

```
[PCD] value=read_adc(mode,[channel])
```

Parameters:

mode - is an optional parameter. If used the values may be:

adc_start_and_read (continually takes readings, this is the default)

adc_start_only (starts the conversion and returns)

adc_read_only (reads last conversion result)

[PCD] channel - is an optional parameter for specifying the channel to start the conversion on and/or read the result from. If not specified will use channel specified in last call to **set_adc_channel()**, **read_adc()**, or **adc_done()**.

Returns:

Either a 8 or 16 bit int depending on #DEVICE ADC= directive.

Function:

This function will read the digital value from the analog to digital converter. Calls to **setup_adc()**, **setup_adc_ports()** and **set_adc_channel()** should be made sometime before this function is called. The range of the return value depends on number of bits in the chips A/D converter and the setting in the #DEVICE ADC= directive as follows:

#DEVICE	8 bit	10 bit	11 bit	12 bit	16 bit
ADC=8	00-FF	00-FF	00-FF	00-FF	00-FF
ADC=10	x	0-3FF	x	0-3FF	x
ADC=11	x	x	0-7FF	x	x
[PCD] ADC=12		[PCD] 0-FFC		[PCD] 0-FFF	
ADC=16	0FF00	0-FFC0	0-FFEO	0-FFF0	0-FFFF

Availability:

This function is only available on devices with A/D hardware.

[PCD] Only available on devices with built in analog to digital converters.

Requires:

Pin constants are defined in the devices .h file

Examples:

```

setup_adc( ADC_CLOCK_INTERNAL );
setup_adc_ports( ALL_ANALOG );
set_adc_channel(1);
while ( input(PIN_B0) ) {
    delay_ms( 5000 );
    value = read_adc();
    printf("A/D value = %2x\n\r", value);
}

```

```

read_adc(ADC_START_ONLY);
sleep();
value=read_adc(ADC_READ_ONLY);

[PCD]
int16 value;
setup_adc_ports(sAN0|sAN1, VSS_VDD);
setup_adc(ADC_CLOCK_DIV_4|ADC_TAD_MUL_8);

while (TRUE)
{
    set_adc_channel(0);
    value = read_adc();
    printf("Pin AN0 A/C value = %LX\n\r", value);

    delay_ms(5000);

    set_adc_channel(1);
    read_adc(ADC_START_ONLY);
    ...
    value = read_adc(ADC_READ_ONLY);
    printf("Pin AN1 A/D value = %LX\n\r", value);
}

```

Example Files:

ex_admm.c, ex_14kad.c

See Also:

setup_adc(), set_adc_channel(), setup_adc_ports(), #DEVICE, ADC Overview

read_bank()

Syntax:

value = read_bank (*bank*, *offset*)

Parameters:

bank - is the physical RAM bank 1-3 (depending on the device)

offset - is the offset into user RAM for that bank (starts at 0)

Returns:

8 bit int

Function:

Read a data byte from the user RAM area of the specified memory bank. This function may be used on some devices where full RAM access by auto variables is not efficient. For example, setting the pointer size to 5 bits on the PIC16C57 chip will generate the most efficient ROM code. However, auto variables can not be above 1Fh. Instead of going to 8 bit pointers, you can save ROM by using this function to read from the hard-to-reach banks. In this case, the bank may be 1-3 and the offset may be 0-15.

Availability:

All devices but only useful on PCB parts with memory over 1Fh and PCM parts with memory over FFh

Requires:

Examples:

```
// See write_bank() example to see
// how we got the data
// Moves data from buffer to LCD

i=0;
do {
    c=read_bank(1,i++);
    if(c!=0x13)
        lcd_putc(c);
} while (c!=0x13);
```

Example Files:

ex_psp.c

See Also:

write_bank()

read_calibration()**Syntax:**

value = read_calibration (*n*)

Parameters:

n is an offset into calibration memory beginning at 0

Returns:

8 bit byte

Function:

The `read_calibration` function reads location "n" of the 14000-calibration memory

Availability:

This function is only available on the PIC14000

Requires:

Examples:

```
fin = read_calibration(16);
```

Example Files:

ex 14kad.c with 14kcal.c

read_calibration_memory()**Syntax:**

`value = read_calibration_memory (cal_word)`

Parameters:

cal_word - calibration word to read from calibration memory (1-16).

Returns:

unsigned int16 value read from calibration memory.

Function:

Allows for reading one of the calibration words from the calibration memory.

Availability:

This function is only available on MCP191xx devices.

Requires:

Examples:

```
CALWD1=read_calibration_memory(1);
```

See Also:

Program EEPROM Overview

read_config_info()

Syntax:

`read_config_info([offset], ramPtr, count)`

Parameters:

ramPTR - is the destination pointer for the read results.

count - is the number of bytes to read.

Offset - is an optional parameter specifying the offset into the DCI memory to start reading from, offset default to zero if not used.

Returns:

Function:

Read **count** bytes from Device Configuration Area (DCI) memory and saves the values to **ramPtr**. The DCI region of memory contains read-only data about the device's configuration.

Availability:

Devices with a DCI memory region.

Requires:

Examples:

```
unsigned int16 EraseSize;
read_device_info(&EraseSize, 2);    //reads Erase Row Size from DCI
memory
```

See Also:

[read_configuration_memory\(\)](#), [read_device_info\(\)](#), [Configuration Memory Overview](#)

read_configuration_memory()

Syntax:

`read_configuration_memory([offset], ramPtr, n)`

Parameters:

ramPtr - is the destination pointer for the read results

count - is an 8 bit integer

offset - is an optional parameter specifying the offset into configuration memory to start reading from, offset defaults to zero if not used.

Returns:

Undefined

Function:

Reads **n** bytes of configuration memory and saves the values to **ramPtr**.

For **Enhanced16** devices function reads User ID, Device ID and configuration memory regions.

Availability:

All Devices

Requires:

Examples:

```
int data[6];  
read_configuration_memory(data, 6)
```

See Also:

[write_configuration_memory\(\)](#), [read_program_memory\(\)](#), [Configuration Memory Overview](#), [Configuration Memory Overview](#)

read_device_info()

Syntax:

`read_device_info([offset], ramPtr, count)`

Parameters:

ramPTR - is the destination pointer for the read results.

count - is the number of bytes to read.

Offset - is an optional parameter specifying the offset into the DIA memory to start reading from, offset default to zero if not used.

Returns:

Function:

Read **count** bytes from Device Information Area (DIA) memory and saves the values to **ramPtr**. The DIA region of memory contains read-only data used to identify the device.

Availability:

Devices with a DIA memory region.

Requires:

Examples:

```
unsigned int16 identifier[9];
read_device_info(identifier, 18);    //reads Unique Identifier from
DIA memory.
```

See Also:

[read_configuration_memory\(\)](#), [read_config_info\(\)](#), [Configuration Memory Overview](#)

read_dmt()**Syntax:**

Value = read_dmt(**which**);

Parameters:

which - an 8-bit constant indicating which DMT registers to read. The following defines are made in the device's header for selecting the register to read:

```
DMT_READ_COUNT           // the current count
DMT_READ_MAX_VALUE       // the value the count needs to reach for a DMT
event to occur
DMT_READ_WINDOW_VALUE    // the value the count needs to reach before it can
be cleared
```

Returns:

An int32 value indicating the value that was read from the specified DMT registers.

Function:

Used to read the DMTCNT, DMTSCNT and DMTSINTV registers of the Deadman Timer (DMT) peripheral.

Availability:

Requires:

Examples:

```
Value = read_dmt(DMT_READ_COUNT);
```

See Also:

[clear_dmt\(\)](#), [disable_dmt\(\)](#), [enable_dmt\(\)](#), [dmt_status\(\)](#), [setup_dmt\(\)](#)

read_eeprom()

Syntax:

value = read_eeprom (**address**)

```
[PCD] value = read_eeprom (address , [N])
      read_eeprom(address,variable)
      read_eeprom(address, pointer, N)
```

Parameters:

address - is an 8 bit or 16 bit int depending on the part

[PCD] **N** - specifies the number of EEPROM bytes to read

[PCD] **variable** - a specified location to store EEPROM read results

[PCD] **pointer** - is a pointer to location to store EEPROM read results

Returns:

An 8 bit int

[PCD] A 16 bit int

Function:

Reads a byte from the specified data EEPROM address. The address begins at 0 and the range depends on the part.

[PCD] By default the function reads a word from EEPROM at the specified address. The number of bytes to read can optionally be defined by argument N. If a variable is used as an argument, then EEPROM is read and the results are placed in the variable until the variable data size is full. Finally, if a pointer is used as an argument, then n bytes of EEPROM at the given address are read to the pointer.

Availability:

This command is only for parts with built-in EEPROMs

Requires:

Examples:

```
#define LAST_VOLUME 10
volume = read_EEPROM (LAST_VOLUME);
```

See Also:

[write_eeprom\(\)](#), [erase_eeprom\(\)](#), [Data Eeprom Overview](#)

read_extended_ram()**Syntax:**

```
read_extended_ram(page,address,data,count);
```

Parameters:

page – the page in extended RAM to read from

address – the address on the selected page to start reading from

data – pointer to the variable to return the data to

count – the number of bytes to read (0-32768)

Returns:

Undefined

Function:

To read data from the extended RAM of the device.

Availability:

On devices with more than 30K of RAM

Requires:

Examples:

```
unsigned int8 data[8];
read_extended_ram(1, 0x0000, data, 8);
```

See Also:

[Extended RAM Overview](#)

read_program_memory()

Syntax:

READ_PROGRAM_MEMORY (*address*, *dataptr*, *count*);

Parameters:

address is 32 bits. The least significant bit should always be 0 in PCM.

dataptr is a pointer to one or more bytes.

count is a 8 bit integer on PIC16

count is a 16 bit integer for PIC18 and dsPIC/PIC24

Returns:

Undefined

Function:

Reads **count** bytes from program memory at **address** to RAM at **dataptr**.

Availability:

On devices with the ability to Read program memory.

Requires:

Examples:

```
char buffer[64];
read_program_memory(0x40000, buffer, 64);
```

See Also:

[write_program_memory\(\)](#), [External memory overview](#) , [Program Eeprom Overview](#)

read_high_speed_adc()

Syntax:

read_high_speed_adc(pair , mode , result);	// Individual start and read or read only
read_high_speed_adc(pair , result);	// Individual start and read
read_high_speed_adc(pair);	// Individual start only
read_high_speed_adc(mode , result);	// Global start and read or read only
read_high_speed_adc(result);	// Global start and read
read_high_speed_adc();	// Global start only

Parameters:

pair – Optional parameter that determines which ADC pair number to start and/or read. Valid values are 0 to total number of ADC pairs. 0 starts and/or reads ADC pair AN0 and AN1, 1 starts and/or reads ADC pair AN2 and AN3, etc. If omitted then a global start and/or read will be performed.

mode – Optional parameter, if used the values may be:

adc_start_and_read (starts conversion and reads result)

adc_start_only (starts conversion and returns)

adc_read_only (reads conversion result)

result – Pointer to return ADC conversion too. Parameter is optional, if not used the **read_fast_adc()** function can only perform a start.

Returns:

Undefined

Function:

This function is used to start an analog to digital conversion and/or read the digital value when the conversion is complete. Calls to **setup_high_speed_adc()** and **setup_high_speed_adc_pairs()** should be made sometime before this function is called.

When using this function to perform an individual start and read or individual start only, the function assumes that the pair's trigger source was set to **individual_software_trigger**.

When using this function to perform a global start and read, global start only, or global read only. The function will perform the following steps:

1. Determine which ADC pairs are set for **global_software_trigger**
2. Clear the corresponding ready flags (if doing a start).
3. Set the global software trigger (if doing a start).
4. Read the corresponding ADC pairs in order from lowest to highest (if doing a read).
5. Clear the corresponding ready flags (if doing a read).

When using this function to perform a individual read only. The function can read the ADC result from any trigger source.

Availability:

Only on dsPIC33FJxxGSxxx devices

Requires:

Constants are define in the device .h file

Examples:

```

                                                                    //Individual
start and read
int16 result[2];

setup_high_speed_adc(ADC_CLOCK_DIV_4);
setup_high_speed_adc_pair(0, INDIVIDUAL_SOFTWARE_TRIGGER);
read_high_speed_adc(0, result);           //starts
conversion for AN0

                                                                    //and AN1 and
stores result
                                                                    //in result[0]
and result[1]
                                                                    //Global start
and read
int16 result[4];

setup_high_speed_adc(ADC_CLOCK_DIV_4);
setup_high_speed_adc_pair(0, GLOBAL_SOFTWARE_TRIGGER);
setup_high_speed_adc_pair(4, GLOBAL_SOFTWARE_TRIGGER);
read_high_speed_adc(result);             //starts
conversion for AN0, AN1,
                                                                    //AN8 and AN9 and
stores result in
                                                                    //result[0],
result //[1], result[2]
                                                                    //and result[3]
```

See Also:

setup_high_speed_adc(), setup_high_speed_adc_pair(), high_speed_adc_done()

read_program_memory()

Syntax:

value = read_program_eeprom (**address**)

Parameters:

address - is 16 bits on PCM parts and 32 bits on PCH parts

Returns:

16 bits

Function:

Reads data from the program memory

Availability:

Only devices that allow reads from program memory

Requires:

Examples:

```
checksum = 0;
for(i=0; i<8196; i++)
    checksum^=read_program_eeprom(i);
printf("Checksum is %2X\r\n", checksum);
```

See Also:

[write_program_eeprom\(\)](#), [write_eeprom\(\)](#), [read_eeprom\(\)](#), [Program Eeprom Overview](#)

read_program_memory()

Syntax:

READ_PROGRAM_MEMORY (*address*, *dataptr*, *count*);

Parameters:

address is 32 bits. The least significant bit should always be 0 in PCM.

dataptr is a pointer to one or more bytes.

count is a 8 bit integer on PIC16

count is a 16 bit integer for PIC18 and dsPIC/PIC24

Returns:

Undefined

Function:

Reads **count** bytes from program memory at **address** to RAM at **dataptr**.

Availability:

On devices with the ability to Read program memory.

Requires:

Examples:

```
char buffer[64];
read_program_memory(0x40000, buffer, 64);
```

See Also:

[write_program_memory\(\)](#), [External memory overview](#) , [Program Eeprom Overview](#)

read_program_memory8()

Syntax:

`READ_PROGRAM_MEMORY8(address, dataptr, count);`

Parameters:

address is 16 bits to start reading data from the program memory.

dataptr is a pointer to an array of bytes to store read data to.

count is the number of bytes to read from program memory.

Returns:

Undefined

Function:

Reads ***count*** bytes from program memory. This function only reads the least significant byte from each address in program memory. See [read_program_memory\(\)](#) for a function that can read all the data from each address in program memory.

Availability:

Only on PCM devices with the ability to Read program memory.

Requires:

Examples:

```
read_program_memory8(Address, Data, 128);
```

See Also:

[read_program_memory\(\)](#), [write_program_memory\(\)](#), [write_program_memory8\(\)](#), [Program Eeprom Overview](#)

read_rom_memory()

Syntax:

`read_rom_memory(address, dataptr, count);`

Parameters:

address - is 32 bits. The least significant bit should always be 0.

dataptr - is a pointer to one or more bytes.

count - is a 16 bit integer

Returns:

Undefined

Function:

Reads **count** bytes from program memory at **address** to **dataptr**.

[PCD] 24 bit program instruction size, 3 bytes are read from each address location

Availability:

Only devices that allow reads from program memory

Requires:

Examples:

```
char buffer[64];
read_program_memory(0x40000, buffer, 64);
```

See Also:

[write_program_eeprom\(\)](#), [write_eeprom\(\)](#), [read_eeprom\(\)](#), [Program eeprom overview](#)

read_sd_adc()

Syntax:

```
value = read_sd_adc();
```

Parameters:

Returns:

A signed 32 bit int

Function:

To poll the SDRDY bit and if set return the signed 32 bit value stored in the SD1RESH and SD1RESL registers, and clear the SDRDY bit. The result returned depends on settings made with the **setup_sd_adc()** function, but will always be a signed int32 value with the most significant bits being meaningful. Refer to Section 66, 16-bit Sigma-Delta

A/D Converter, of the PIC24F Family Reference Manual for more information on the module and the result format.

Availability:

Only devices with a Sigma-Delta Analog to Digital Converter (SD ADC) module

Requires:

Examples:

```
value = read_sd_adc()
```

See Also:

setup_sd_adc(), set_sd_adc_calibration(), set_sd_adc_channel()

realloc()**Syntax:**

`realloc (ptr, size)`

Parameters:

ptr - is a null pointer or a pointer previously returned by `calloc` or `malloc` or `realloc` function, **size** is an integer representing the number of bytes to be allocated.

Returns:

A pointer to the possibly moved allocated memory, if any. Returns null otherwise.

Function:

The **realloc** function changes the size of the object pointed to by the **ptr** to the size specified by the **size**. The contents of the object shall be unchanged up to the lesser of new and old sizes. If the new size is larger, the value of the newly allocated space is indeterminate. If **ptr** is a null pointer, the **realloc** function behaves like **malloc** function for the specified size. If the **ptr** does not match a pointer earlier returned by the **calloc**, **malloc** or **realloc**, or if the space has been deallocated by a call to `free` or **realloc** function, the behavior is undefined. If the space cannot be allocated, the object pointed to by **ptr** is unchanged. If **size** is zero and the **ptr** is not a null pointer, the object is to be freed.

Availability:

All Devices

Requires:

`#INCLUDE <stdlibm.h>`

Examples:

```
int * iptr;
iptr=malloc(10);
realloc(iptr,20)           // iptr will point to a block of
memory of                  // 20 bytes, if available
```

See Also:

malloc(), free(), calloc()

release_io()**Syntax:**

```
release_io();
```

Parameters:

Returns:

Function:

The function is used to release the I/O on devices that have woken up from deep sleep.

Availability:

Devices with a Deep Sleep Watch Dog Timer (DSWDT) peripheral.

Requires:

Examples:

```
restart=restart_cause();

switch(restart)
{
    case RTC_FROM_DS:
    case DSWDT_FROM_DS:
    case ULPWU_FROM_DS:
    case EXT_FROM_DS:
        release_io();
        break;
```

```
}
```

See Also:

[sleep\(\)](#)

reset_cpu()

Syntax:

```
reset_cpu()
```

Parameters:

Returns:

This function never returns

Function:

This is a general purpose device reset. It will jump to location 0 on PCB and PCM parts and also reset the registers to power-up state on the PIC18.

Availability:

All Devices

Requires:

Examples:

```
if (checksum!=0)
    reset_cpu();
```

restart_cause()

Syntax:

```
value = restart_cause()
```

Parameters:

Returns:

A value indicating the cause of the last processor reset. The actual values are device dependent. See the device .h file for specific values for a specific device. Some example values are: wdt_from_sleep, wdt_timeout, mclr_from_sleep and normal_power_up

[PCD] reset_power_up, restart_brownout, restart_wdt and sstart_mclr, wdt_from_sleep

Function:

Returns the cause of the last processor reset.

[PCD] In order for the result to be accurate, it should be called immediately in main().

Availability:

All Devices

Requires:

Constants are defined in the devices .h file

Examples:

```
switch ( restart_cause() ) {
    case WDT_FROM_SLEEP:
    case WDT_TIMEOUT:
        handle_error();
}
[PCD]
switch ( restart_cause() ) {
    case RESTART_BROWNOUT:
    case RESTART_WDT:
    case RESTART_MCLR:
        handle_error();
}
```

Example Files:

ex_wdt.c

See Also:

restart_wdt(), reset_cpu()

restart_wdt()**Syntax:**

restart_wdt()

Parameters:

Returns:

Function:

Restarts the watchdog timer. If the watchdog timer is enabled, this must be called periodically to prevent the processor from resetting.

The watchdog timer is used to cause a hardware reset if the software appears to be stuck.

The timer must be enabled, the timeout time set and software must periodically restart the timer. These are done differently on the PCB/PCM and PCH parts as follows:

	PCB/PCM	PCH
Enable/Disable	#fuses	setup_wdt()
Timeout time	setup_wdt()	#fuses
restart	restart_wdt()	restart_wdt()

Availability:

All Devices

Requires:

#FUSES

Examples:

```
#fuses WDT          // PCB/PCM example
                      // See setup_wdt for a PIC18 example

main() {
    setup_wdt(WDT_2304MS);
    while (TRUE) {
        restart_wdt();
        perform_activity();
    }
}
```

Example Files:

ex_wdt.c

See Also:

#FUSES, setup_wdt(), WDT or Watch Dog Timer Overview

rotate_left()**Syntax:**

rotate_left(*address*, *bytes*)

Parameters:

address - is a pointer to memory

bytes - is a count of the number of bytes to work with

Returns:

Undefined

Function:

Rotates a bit through an array or structure. The address may be an array identifier or an address to a byte or structure (such as &data). Bit 0 of the lowest BYTE in RAM is considered the LSB.

Availability:

All Devices

Requires:

Examples:

```
x = 0x86;  
rotate_left( &x, 1);           // x is now 0x0d
```

See Also:

rotate_right(), shift_left(), shift_right()

rotate_right()**Syntax:**

rotate_right (**address**, **bytes**)

Parameters:

address - is a pointer to memory

bytes - is a count of the number of bytes to work with

Returns:

Undefined

Function:

Rotates a bit through an array or structure. The address may be an array identifier or an address to a byte or structure (such as &data). Bit 0 of the lowest BYTE in RAM is considered the LSB.

Availability:

All Devices

Requires:

Examples:

```
struct {
    int cell_1 : 4;
    int cell_2 : 4;
    int cell_3 : 4;
    int cell_4 : 4; } cells;
rotate_right( &cells, 2);
rotate_right( &cells, 2);
rotate_right( &cells, 2);
rotate_right( &cells, 2);           // cell_1->4, 2->1, 3->2 and 4-
> 3
```

See Also:

rotate left(), shift left(), shift right()

rtc_alarm_read()

Syntax:

rtc_alarm_read(&*datetime*);

Parameters:

datetime- A structure that will contain the values to be written to the alarm in the RTCC module.

Structure used in read and write functions are defined in the device header file as

rtc_time_t

Returns:

Void

Function:

Reads the date and time from the alarm in the RTCC module to structure ***datetime***.

Availability:

Devices that an RTCC module

Requires:

Examples:

```
rtc_alarm_read(&datetime);
```

See Also:

rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(), setup_rtc()

rtc_alarm_write()**Syntax:**

```
rtc_alarm_write(&datetime);
```

Parameters:

datetime- A structure that will contain the values to be written to the alarm in the RTCC module.

Structure used in read and write functions are defined in the device header file as

rtc_time_t

Returns:

Void

Function:

Write the date and time from the alarm in the RTCC module to structure ***datetime***.

Availability:

Devices that an RTCC module

Requires:

Examples:

```
rtc_alarm_write(&datetime);
```

See Also:

[rtc_read\(\)](#), [rtc_alarm_read\(\)](#), [rtc_alarm_write\(\)](#), [setup_rtc_alarm\(\)](#), [rtc_write\(\)](#), [setup_rtc\(\)](#)

rtc_read()**Syntax:**

```
rtc_read(&datetime);
```

Parameters:

datetime- A structure that will contain the values returned by the RTCC module.

Structure used in read and write functions are defined in the device header file as

rtc_time_t

Returns:

Void

Function:

Reads the current value of Time and Date from the RTCC module and stores the structure date time.

Availability:

Devices that have a Real-Time Clock and Calendar (RTCC) module.

Requires:

Examples:

```
rtc_read(&datetime);
```

Example Files:

[ex_rtcc.c](#)

See Also:

[rtc_read\(\)](#), [rtc_alarm_read\(\)](#), [rtc_alarm_write\(\)](#), [setup_rtc_alarm\(\)](#), [rtc_write\(\)](#), [setup_rtc\(\)](#)

[PCD] rtc_status()**Syntax:**

```
Status = rtc_status();
```

Parameters:

```
-----
```

Returns:

An int8 value indicating the status of the RTCC module. See the device's header file for constants that can be and'ed with return value to determine that state of the individual status bits.

Function:

Used to determine the status of the RTCC module.

Availability:

Devices that have a Real-Time Clock and Calendar (RTCC) with Timestamp module.

Requires:

```
-----
```

Examples:

```
rtc_time_t TimeStamp;
rtc_tsa_read(&TimeStamp);           //read Timestamp A registers
rtc_tsb_read(&TimeStamp);           //read Timestamp B registers
```

See Also:

setup rtc(), setup rtc alarm(), rtc read(), rtc write(), rtc alarm read(), rtc alarm write(), rtc tsx read()

[PCD] rtc_tsx_read()**Syntax:**

```
rtc_tsa_read(&timestamp);
rtc_tsb_read(&timestamp);
```

Parameters:

timestamp - a structure of **rtc_time_t** to return the timestamp value.

Returns:

```
-----
```

Function:

Used to read the Timestamp A and Timestamp B registers and converts them to be compatible with the **rtc_time_t** structure.

Availability:

Devices that have a Real-Time Clock and Calendar (RTCC) with Timestamp module.

Requires:

Examples:

```
rtc_time_t TimeStamp;  
rtc_tsa_read(&TimeStamp);           //read Timestamp A registers  
rtc_tsb_read(&TimeStamp);           //read Timestamp B registers
```

See Also:

setup_rtc(), setup_rtc_alarm(), rtc_read(), rtc_write(), rtc_alarm_read(), rtc_alarm_write(), rtc_status()

rtc_write()**Syntax:**

rtc_write(&datetime);

Parameters:

datetime- A structure that will contain the values to be written to the RTCC module.

Structure used in read and write functions are defined in the device header file as

rtc_time_t

Returns:

Void

Function:

Writes the date and time to the RTCC module as specified in the structure date time.

Availability:

Devices that an RTCC module

Requires:

Examples:

```
rtc_write(&datetime);
```

Example Files:

[ex_rtcc.c](#)

See Also:

[rtc_read\(\)](#) , [rtc_alarm_read\(\)](#) , [rtc_alarm_write\(\)](#) , [setup_rtc_alarm\(\)](#) , [rtc_write\(\)](#),
[setup_rtc\(\)](#)

rtos_await()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

`rtos_await (expre)`

Parameters:

expre is a logical expression

Returns:

Function:

This function can only be used in an RTOS task. This function waits for *expre* to be true before continuing execution of the rest of the code of the RTOS task. This function allows other tasks to execute while the task waits for *expre* to be true.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_await(kbhit());
```

See Also:

rtos_disable()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

`rtos_disable` (*task*)

Parameters:

task - is the identifier of a function that is being used as an RTOS task

Returns:

Function:

This function disables a task which causes the task to not execute until enabled by `rtos_enable()`. All tasks are enabled by default.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_disable(toggle_green);
```

See Also:

[rtos_enable\(\)](#)

rtos_enable()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

`rtos_enable` (*task*)

Parameters:

task - is the identifier of a function that is being used as an RTOS task

Returns:

Function:

This function enables a task to execute at it's specified rate.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_enable(toggle_green);
```

See Also:

rtos_disable()

rtos_msg_poll()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

```
i = rtos_msg_poll()
```

Parameters:

Returns:

An integer that specifies how many messages are in the queue

Function:

This function can only be used inside an RTOS task. This function returns the number of messages that are in the queue for the task that the `rtos_msg_poll()` function is used in.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
if(rtos_msg_poll())
```

See Also:

rtos msg send(), rtos msg read()

rtos msg read()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

b = rtos_msg_read()

Parameters:

Returns:

A byte that is a message for the task

Function:

This function can only be used inside an RTOS task. This function reads in the next (message) of the queue for the task that the rtos_msg_read() function is used in.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
if(rtos_msg_poll()) {  
    b = rtos_msg_read();  
}
```

See Also:

rtos msg poll(), rtos msg send()

rtos msg send()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

rtos_msg_send(*task*, *byte*)

Parameters:

task - is the identifier of a function that is being used as an RTOS task

byte - is the byte to send to **task** as a message

Returns:

Function:

This function can be used anytime after `rtos_run()` has been called.

This function sends a byte long message (**byte**) to the task identified by **task**.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
if(kbhit())
{
    rtos_msg_send(echo, getc());
}
```

See Also:

`rtos_msg_poll()`, `rtos_msg_read()`

rtos_overrun()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

`rtos_overrun([task])`

Parameters:

task - is an optional parameter that is the identifier of a function that is being used as an RTOS task

Returns:

A 0 (FALSE) or 1 (TRUE)

Function:

This function returns TRUE if the specified task took more time to execute than it was allocated. If no task was specified, then it returns TRUE if any task ran over it's allotted execution time.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_omerrun();
```

rtos_run()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

```
rtos_run()
```

Parameters:

Returns:

Function:

This function begins the execution of all enabled RTOS tasks. This function controls the execution of the RTOS tasks at the allocated rate for each task. This function will return only when rtos_terminate() is called.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_run();
```

See Also:
[rtos terminate\(\)](#)

rtos_signal()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:
`rtos_signal (sem)`

Parameters:
sem is a global variable that represents the current availability of a shared system resource (a semaphore)

Returns:

Function:
This function can only be used by an RTOS task. This function increments ***sem*** to let waiting tasks know that a shared resource is available for use.

Availability:
All Devices

Requires:
#USE RTOS

Examples:

```
rtos_signal(uart_use);
```

See Also:
[rtos wait\(\)](#)

rtos_stats()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:
`rtos_stats(task,&stat)`

Parameters:

task - is the identifier of a function that is being used as an RTOS task.

stat - is a structure containing the following:

```

    struct rtos_stas_struct {
        unsigned int32 task_total_ticks;    //number of ticks the
task has used
        unsigned int16 task_min_ticks;      //the minimum number
of ticks used
        unsigned int16 task_max_ticks;      //the maximum number
of ticks used
        unsigned int16 hns_per_tick;        //us =
(ticks*hns_per_tick)/10

```

Returns:

Undefined

Function:

This function returns the statistic data for a specified **task**.

Availability:

All Devices

Requires:

#USE RTOS(statistics)

Examples:

```

    rtos_stats(echo, &stats);

```

See Also:**rtos_terminate()**

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

```

rtos_terminate()

```

Parameters:

Returns:

Function:

This function ends the execution of all RTOS tasks. The execution of the program will continue with the first line of code after the `rtos_run()` call in the program. (This function causes `rtos_run()` to return.)

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_terminate()
```

See Also:

[rtos_run\(\)](#)

rtos_wait()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

`rtos_wait (sem)`

Parameters:

sem is a global variable that represents the current availability of a shared system resource (a semaphore)

Returns:

Function:

This function can only be used by an RTOS task. This function waits for ***sem*** to be greater than 0 (shared resource is available), then decrements ***sem*** to claim usage of the shared resource and continues the execution of the rest of the code the RTOS task. This function allows other tasks to execute while the task waits for the shared resource to be available.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
rtos_wait(uart_use)
```

See Also:

rtos signal()

rtos_yield()

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:

rtos_yield()

Parameters:

Returns:

Function:

This function can only be used in an RTOS task. This function stops the execution of the current task and returns control of the processor to **rtos_run()**. When the next task executes, it will start its execution on the line of code after the **rtos_yield()**.

Availability:

All Devices

Requires:

#USE RTOS

Examples:

```
void yield(void)
{
    printf("Yielding...\r\n");
    rtos_yield();
}
```



```
    printf("Executing code after yield\r\n");
}
```

set_adc_channel() set_adc2_channel()

Syntax:

```
set_adc_channel(chan [,neg]))
```

[PCD] set_adc_channel(chan, [differential]) //dsPIC33EPxxGSxxx only

[PCD] set_adc2_channel(**chan**)

Parameters:

chan is the channel number to select. Channel numbers start at 0 and are labeled in the data sheet AN0, AN1. For devices with a differential ADC it sets the positive channel to use.

neg is optional and is used for devices with a differential ADC only. It sets the negative channel to use, channel numbers can be 0 to 6 or VSS. If no parameter is used the negative channel will be set to VSS by default.

Returns:

Undefined

[PCD] **differential** is an optional parameter to specify if channel is differential or single-ended. TRUE is differential and FALSE is single-ended. Only available for dsPIC33EPxxGSxxx family.

Function:

Specifies the channel to use for the next read_adc() call. Be aware that you must wait a short time after changing the channel before you can get a valid read. The time varies depending on the impedance of the input source. In general 10us is good for most applications. You need not change the channel before every read if the channel does not change.

Availability:

This function is only available on devices with A/D hardware.

[PCD] Only available on devices with built in analog to digital converters

Requires:

Examples:

```
set_adc_channel(2);
delay_us(10);
value = read_adc();
```

Example Files:

ex_admm.c

See Also:

read_adc(), setup_adc(), setup_adc_ports(), ADC Overview

set_adc_trigger()

Syntax:

set_adc_trigger(**trigger**)

Parameters:

trigger - ADC trigger source. Constants defined in device's header, see the device's .h file for all options. Some typical options include:

```
ADC_TRIGGER_DISABLED
ADC_TRIGGER_ADACT_PIN
ADC_TRIGGER_TIMER1
ADC_TRIGGER_CCP1
```

Returns:

Undefined

Function:

Sets the Auto-Conversion trigger source for the Analog-to-Digital Converter with Computation (ADC2) Module.

Availability:

All devices with an ADC2 Module

Requires:

Constants defined in the device's .h file

Examples:

```
set__adc_trigger(ADC_TRIGGER_TIMER1);
```

See Also:

ADC Overview, setup_adc(), setup_adc_ports(), set_adc_channel(), read_adc(), #DEVICE, adc_read(), adc_write(), adc_status()

set_analog_pins()

Syntax:

`set_analog_pins(pin, pin, pin, ...)`

Parameters:

pin - pin to set as an analog pin. Pins are defined in the device's .h file. The actual value is a bit address. For example, bit 3 of port A at address 5, would have a value of $5 \times 8 + 3$ or 43. This is defined as follows: `#define PIN_A3 43`

Returns:

Undefined

Function:

To set which pins are analog and digital. Usage of function depends on method device has for setting pins to analog or digital. For devices with ANSELx, x being the port letter, registers the function is used as described above. For all other devices the function works the same as **setup_adc_ports()** function.

Availability:

On all devices with an Analog to Digital Converter

Requires:

Examples:

```
set_analog_pins(PIN_A0, PIN_A1, PIN_E1, PIN_B0, PIN_B5);
```

See Also:

[setup_adc_reference\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#), [setup_adc\(\)](#), [setup_adc_ports\(\)](#), [ADC Overview](#)

scanf() fscanf()

Syntax:

`scanf(cstring);`

`scanf(cstring, values...)`

`fscanf(stream, cstring, values...)`

Parameters:

cstring is a constant string.

values is a list of variables separated by commas.

stream is a stream identifier

Returns:

0 if a failure occurred, otherwise it returns the number of conversion specifiers that were read in, plus the number of constant strings read in.

Function:

Reads in a string of characters from the standard RS-232 pins and formats the string according to the format specifiers. The format specifier character (%) used within the string indicates that a conversion specification is to be done and the value is to be saved into the corresponding argument variable. A %% will input a single %. Formatting rules for the format specifier as follows:

If fscanf() is used, then the specified stream is used, where scanf() defaults to STDIN (the last USE RS232).

Format:

The format takes the generic form %nt. **n** is an option and may be 1-99 specifying the field width, the number of characters to be inputted. **t** is the type and maybe one of the following:

- c** Matches a sequence of characters of the number specified by the field width (1 if no field width is specified). The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence.
- s** Matches a sequence of non-white space characters. The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.
- u** Matches an unsigned decimal integer. The corresponding argument shall be a pointer to an unsigned integer.
- Lu** Matches a long unsigned decimal integer. The corresponding argument shall be a pointer to a long unsigned integer.
- d** Matches a signed decimal integer. The corresponding argument shall be a pointer to a signed integer.
- Ld** Matches a long signed decimal integer. The corresponding argument shall be a pointer to a long signed integer.
- o** Matches a signed or unsigned octal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.

- Lo** Matches a long signed or unsigned octal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- x or X** Matches a hexadecimal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
- Lx or LX** Matches a long hexadecimal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- i** Matches a signed or unsigned integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
- Li** Matches a long signed or unsigned integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
- f,g or e** Matches a floating point number in decimal or exponential format. The corresponding argument shall be a pointer to a float.
- [** Matches a non-empty sequence of characters from a set of expected characters. The sequence of characters included in the set are made up of all character following the left bracket ([) up to the matching right bracket (]). Unless the first character after the left bracket is a ^, in which case the set of characters contain all characters that do not appear between the brackets. If a - character is in the set and is not the first or second, where the first is a ^, nor the last character, then the set includes all characters from the character before the - to the character after the -.
For example, %[a-z] would include all characters from **a** to **z** in the set and %[^a-z] would exclude all characters from **a** to **z** from the set. The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.
- n** Assigns the number of characters read thus far by the call to scanf() to the corresponding argument. The corresponding argument shall be a pointer to an unsigned integer.

An optional assignment-suppressing character (*) can be used after the format specifier to indicate that the conversion specification is to be done, but not saved into a corresponding variable. In this case, no corresponding argument variable should be passed to the scanf() function.

A string composed of ordinary non-white space characters is executed by reading the next character of the string. If one of the inputted characters differs from the string, the function fails and exits. If a white-space character precedes the ordinary non-white space characters, then white-space characters are first read in until a non-white space character is read.

White-space characters are skipped, except for the conversion specifiers `[%c]` or `[%n]`, unless a white-space character precedes the `[%c]` or `[%n]` specifiers.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
char name[2-];
unsigned int8 number;
signed int32 time;

if(scanf("%u%s%d", &number, name, &time))
    printf("\r\nName: %s, Number: %u, Time: %d", name, number, time)
```

See Also:

[RS232 I/O Overview](#), [getc\(\)](#), [putc\(\)](#), [printf\(\)](#)

[PCD] sent_getd()**Syntax:**

```
data = sent_getd(module);
```

Parameters:

module - the SENT peripheral to setup, 1 or 2 for most devices.

Returns:

The data read by the SENT peripheral when it is setup as a receiver. The data type `SENT_DATA_TYPE` is defined in the device's header file for organizing the nibble data.

Function:

Gets data from the Single-Edge Nibble Transmission (SENT) peripheral's data registers.

Availability:

Devices with a SENT peripheral.

Requires:

Examples:

```
SENT_DATA_TYPE Data;  
Data = sent_getd(1);
```

Example Files:

ex_sent_transmitter.c, ex_sent_receiver.c

See Also:

sent_putd(), setup_sent(), sent_status()

[PCD] sent_putd()**Syntax:**

sent_putd(**module**, **data**);

Parameters:

module - the SENT peripheral to setup, 1 or 2 for most devices.

data - the data to transmit when SENT peripheral is setup as a transmitter. The data type SENT_DATA_TYPE is defined in the device's header file for organizing the nibble data.

Returns:

Function:

Puts data for transmission into the Single-Edge Nibble Transmission (SENT) peripheral's data registers.

Availability:

Devices with a SENT peripheral.

Requires:

Examples:

```
SENT_DATA_TYPE Data;  
sent_putd(1, Data);
```

Example Files:

ex_sent_transmitter.c, ex_sent_receiver.c

See Also:

sent_getd(), setup_sent(), sent_status()

[PCD] sent_status()

Syntax:

status = sent_status(**module**);

Parameters:

module - the SENT peripheral to setup, 1 or 2 for most devices.

Returns:

The status of the SENT peripheral. See device's header file for constants that can be and'ed with return value to determine which status flags are set.

Function:

Gets status from the Single-Edge Nibble Transmission (SENT) peripheral's status register.

Availability:

Devices with a SENT peripheral.

Requires:

Examples:

```
unsigned int8 status;
status = sent_status(1);
```

Example Files:

ex_sent_transmitter.c, ex_sent_receiver.c

See Also:

sent_putd(), sent_getd(), setup_sent()

set_ccp1_compare_time() **set_ccp2_compare_time()**
set_ccp3_compare_time() **set_ccp5_compare_time()**
set_ccp5_compare_time()

Syntax:

```
set_ccpx_compare_time(time);
set_ccpx_compare_time(timeA, timeB)
```

Parameters:

time - may be a 16 or 32-bit constant or variable. If 16-bit, it sets the CCPxRAL register to the value time and CCPxRBL to zero; used for single edge output compare mode set for 16-bit timer mode. If 32-bit, it sets the CCPxRAL and CCPxRBL register to the value time, CCPxRAL least significant word and CCPxRBL most significant word; used for single edge output compare mode set for 32-bit timer mode.

timeA - is a 16-bit constant or variable to set the CCPxRAL register to the value of timeA, used for dual edge output compare and PWM modes.

timeB - is a 16-bit constant or variable to set the CCPxRBL register to the value of timeB, used for dual edge output compare and PWM modes.

Returns:

Undefined

Function:

This function sets the compare value for the CCP module. If the CCP module is performing a single edge compare in 16-bit mode, then the CCPxRBL register is not used. If 32-bit mode, the CCPxRBL is the most significant word of the compare time. If the CCP module is performing dual edge compare to generate an output pulse, then timeA, CCPxRAL register, signifies the start of the pulse, and timeB, CCPxRBL register signifies the pulse termination time.

Availability:

Available only on PIC24FxxKMxxx family of devices with a M CCP and/or SCCP modules

Requires:

Examples:

```
setup_ccp1(CCP_COMPARE_PULSE);
set_timer_period_ccp1(800);
set_ccp1_compare_time(200,300);           //generate a pulse starting
at time
```

```
300 // 200 and ending at time
```

See Also:

set_pwmX_duty(), setup_ccpX(), set_timer_period_ccpX(), set_timer_ccpX(),
get_timer_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

set_cog_blanking() set_cog2_blanking()
set_cog3_blanking() set_cog4_blanking()

Syntax:

```
set_cog_blanking(falling_time, rising_time);
```

Parameters:

falling time - sets the falling edge blanking time.

rising time - sets the rising edge blanking time

Returns:

Function:

To set the falling and rising edge blanking times on the Complementary Output Generator (COG) module.

The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device, refer to the device's datasheet for the correct width.

Availability:

All devices with a COG module

Requires:

Examples:

```
set_cog_blanking(10,10);
```

See Also:

setup_cog(), set_cog_phase(), set_cog_dead_band(), cog_status(), cog_restart()

set cog dead band() set cog2 dead band() set cog3 dead band() set cog4 dead band()

Syntax:

set_cog_dead_band(falling_time, rising_time);

Parameters:

falling time - sets the falling edge dead-band time.

rising time - sets the rising edge dead-band time.

Returns:

Function:

To set the falling and rising edge dead-band times on the Complementary Output Generator (COG) module.

The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device, refer to the device's datasheet for the correct width.

Availability:

All devices with a COG module

Requires:

Examples:

```
set_cog_dead_band(16,32);
```

See Also:

[setup_cog\(\)](#), [set_cog_phase\(\)](#), [set_cog_blanking\(\)](#), [cog_status\(\)](#), [cog_restart\(\)](#)

set cog phase() set cog2 phase() set cog3 phase() set cog4 phase()

Syntax:

set_cog_phase(rising_time);

set_cog_phase(falling_time, rising_time);

Parameters:

falling time - sets the falling edge phase time.

rising time - sets the rising edge phase time.

Returns:

Function:

To set the falling and rising edge phase times on the Complementary Output Generator (COG) module.

The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device.

Some devices only have a rising edge delay, refer to the device's datasheet.

Availability:

All devices with a COG module

Requires:

Examples:

```
set_cog_phase(10,10);
```

See Also:

[setup_cog\(\)](#), [set_cog_dead_band\(\)](#), [set_cog_blanking\(\)](#), [cog_status\(\)](#), [cog_restart\(\)](#)

set_compare_time()

Syntax:

set_compare_time(*x*, *time*)

[PCD] set_compare_time(*x*, *ocr*, [*ocrs*])

Parameters:

x - is 1-8 and defines which output compare module to set time for.

time - is the compare time for the primary compare register.

[PCD]

x - is 1-16 and defines which output compare module to set time for.

ocr - is the compare time for the primary compare register.

ocrs - is the optional compare time for the secondary register. Used for dual compare mode.

Returns:

Function:

This function sets the compare value for the CCP module.

[PCD] This function sets the compare value for the output compare module. If the output compare module is to perform only a single compare than the **ocrs** register is not used. If the output compare module is using double compare to generate an output pulse, the **ocr** signifies the start of the pulse and **ocrs** defines the pulse termination time.

Availability:

All devices with a CCP module

[PCD] All devices with Output Compare modules

Requires:

Example Files:

[ex_ccp1s.c](#)

[PCD] Example File:

```

// Pin OC1 will be set
when
    //timer 2 is equal to
    0xF000
    setup_timer2(TMR_INTERNAL | TIMER_DIV_BY_8);
    setup_compare_time(1, 0xF000);
    setup_compare(1, COMPARE_SET_ON_MATCH | COMPARE_TIMER2);

```

See Also:

[get_capture\(\)](#), [setup_ccpx\(\)](#)

[PCD] [Output Compare](#)

set_dedicated_adc_channel()

Syntax:

set_dedicated_adc_channel(**core**,**channel**, [**differential**]);

Parameters:

core - the dedicated ADC core to setup

channel - the channel assigned to the specified ADC core. Channels are defined in the device's .h file as follows:

```

ADC_CHANNEL_AN0
ADC_CHANNEL_AN7

```

```
ADC_CHANNEL_PGA1
ADC_CHANNEL_AN0ALT
ADC_CHANNEL_AN1
ADC_CHANNEL_AN18
ADC_CHANNEL_PGA2
ADC_CHANNEL_AN1ALT
ADC_CHANNEL_AN2
ADC_CHANNEL_AN11
ADC_CHANNEL_VREF_BAND_GAP
ADC_CHANNEL_AN3
ADC_CHANNEL_AN15
```

Not all of the above defines can be used with all the dedicated ADC cores. Refer to the device's header for which can be used with each dedicated ADC core.

differential - optional parameter to specify if channel is differential or single-ended. TRUE is differential and FALSE is single-ended.

Returns:

Undefined

Function:

Sets the channel that will be assigned to the specified dedicated ADC core. Function does not set the channel that will be read with the next call to `read_adc()`, use `set_adc_channel()` or `read_adc()` functions to set the channel that will be read.

Availability:

Only dsPIC33EPxxGSxxx family of devices

Requires:

Examples:

```
setup_dedicated_adc_channel(0,ADC_CHANNEL_AN0);
```

See Also:

[setup_adc\(\)](#), [setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#), [adc_done\(\)](#), [setup_dedicated_adc\(\)](#), [ADC Overview](#)

set_hspwm_event() set_hspwm_secondary_event()

Syntax:

```
set_hs_hspwm_event(settings, compare_time);
set_hswpm_secondary_event(settings, compare_time);    //if available
```

Parameter:

settings - special event timer setting or'd with a value from 1 to 16 to set the prescaler.

The following are the settings available for the special event time:

- HSPWM_SPECIAL_EVENT_INT_ENABLED
- HSPWM_SPECIAL_EVENT_INT_DISABLED

compare_time - the compare time for the special event to occur

Returns:

Function:

Sets the specified High Speed PWM unit.

Availability:

Only on devices with a built-in High Speed PWM module

(dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx,
and dsPIC33EVxxxGMxxx devices)

Requires:

Constants are defined in the device's .h file

Examples:

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(),
setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(),
get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock()
setup_hspwm(), setup_hspwm_secondary()

set_hspwm_duty()

Syntax:

```
set_hspwm_duty(duty);
set_hspwm_duty(unit,primary, [secondary]);
```

Parameters:

duty - A 16-bit constant or variable to set the master duty cycle

unit - The High Speed PWM unit to set.

primary - A 16-bit constant or variable to set the primary duty cycle.

secondary - An optional 16-bit constant or variable to set the secondary duty cycle. Secondary duty cycle is only used in Independent PWM mode. Not available on all devices, refer to the device datasheet for availability.

Returns:

Undefined

Function:

Sets the specified High Speed PWM unit.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```
set_hspwm_duty(0x7FFF);      //sets the high speed PWM
                              //master duty cycle
set_hspwm_duty(1, 0x3FFF);  //sets unit 1's primary duty cycle
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_event(),
setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(),
get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock()
setup_hspwm(), setup_hspwm_secondary()

set_hspwm_duty_adjustment()**Syntax:**

```
set_hspwm_duty_adjustment(unit, value);
```


Parameters:

unit - The High-Speed PWM unit to set.

value - An int8 value to set the PWM unit's duty cycle adjustment value to.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) duty cycle adjustment register. This is the value that is added to the duty cycle when the PCI source is active.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
set_hspwm_duty_ajustment(1, 10);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(), setup_hspwm_feed_forward(),
setup_hspwn_sync(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(), set_hspwm_trigger x(),
get_hspwm_feedback(), get_hspwm_capture(), get_hspwm_status(),
hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update()

set_hspwm_override()**Syntax:**

```
set_hspwm_override(unit, setting);
```

Parameters:

unit - the High Speed PWM unit to override.

settings - the override settings to use. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include:

```
HSPWM_FORCE_H_1  
HSPWM_FORCE_H_0
```

HSPWM_FORCE_L_1
HSPWM_FORCE_L_0

Returns:

Undefined

Function:

Setup and High Speed PWM override settings.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```
setup_hspwm_override(1, HSPWM_FORCE_H_1 | HSPWM_FORCE_L_0);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(),
setup_hspwm_blanking(), setup_hspwm_trigger(), get_hspwm_capture(),
setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock(), setup_hspwm(),
setup_hspwm_secondary()

set_hspwm_period()

Syntax:

```
set_hspwm_period(period);  
set_hspwm_period(unit, value);
```

Parameters:

period - An int16 value to set the PWM master period to.

unit - The High-Speed PWM unit to set.

value - An int16 value to set the PWM unit's period to.

Returns:

Function:

Sets up the High-Speed PWM (HSPWM) period registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
set_hspwm_period(0x8000);    //set master period
set_hspwm_period(4,0x9000);  //set PWM unit 4 period
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(),
setup_hspwm_feed_forward(), setup_hspwm_sync(), set_hspwm_scaling(),
set_hspwm_override(), set_hspwm_phase(), set_hspwm_duty(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(),
get_hspwm_feedback(), get_hspwm_capture(), get_hspwm_status(),
hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update()

set_hspwm_phase()

Syntax:

set_hspwm_phase(**unit**, **primary**, [**secondary**]);

Parameters:

unit - The High Speed PWM unit to set.

primary - A 16-bit constant or variable to set the primary duty cycle.

secondary - An optional 16-bit constant or variable to set the secondary duty cycle.

Secondary duty cycle is only used in Independent PWM mode. Not available on all devices, refer to device datasheet for availability.

Returns:

Undefined

Function:

Sets up the specified High Speed PWM unit.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Constants are defined in the device's .h file

Examples:

```
set_hspwm(1, 0x1000, 0x8000);
```

See Also:

[setup_hspwm_unit\(\)](#), [set_hspwm_duty\(\)](#), [set_hspwm_event\(\)](#), [setup_hspwm_blanking\(\)](#), [setup_hspwm_trigger\(\)](#), [set_hspwm_override\(\)](#), [get_hspwm_capture\(\)](#), [setup_hspwm_chop_clock\(\)](#), [setup_hspwm_unit_chop_clock\(\)](#), [setup_hspwm\(\)](#), [setup_hspwm_secondary\(\)](#)

set_hspwm_scaling()

Syntax:

```
set_hspwm_scaling(period, inc_value);
```

Parameters:

period - An int16 value to set the frequency scaling minimum period to.

inc_value - An int16 value to set the value added to the frequency scaling accumulator for each PWM clock.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) frequency scaling registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
set_hspwm_scaling(0x8000, 16);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(),
setup_hspwm_feed_forward(), setup_hspwm_sync(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(),
get_hspwm_feedback(), get_hspwm_capture(), get_hspwm_status(),
hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update()

set_hspwm_scaling()

Syntax:

```
set_hspwm_trigger_a(unit, value);  

set_hspwm_trigger_b(unit, value);  

set_hspwm_trigger_c(unit, value);
```

Parameters:

unit - The High-Speed PWM unit to set.

value - An int16 value to set the PWM unit's trigger x register to.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) trigger A, B and C registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
set_hspwm_trigger_a(1, 0x1000);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(),

setup hspwm blanking(), setup hspwm event(), setup hspwm fault(),
setup hspwm current limit(), setup hspwm feed forward(), setup hspwm sync(),
set hspwm scaling(), set hspwm override(), set hspwm phase(), set hspwm duty(),
set hspwm period(), set hspwm duty adjustment(), get hspwm feedback(),
get hspwm capture(), get hspwm status(), hspwm trigger_pwm(),
hspwm stop_pwm(), hspwm do capture(), hspwm update()

set input level x()

Syntax:

```
set_input_level_a(value)
set_input_level_b(value)
set_input_level_v(value)
set_input_level_d(value)
set_input_level_e(value)
set_input_level_f(value)
set_input_level_g(value)
set_input_level_h(value)
set_input_level_j(value)
set_input_level_k(value)
set_input_level_l(value)
```

Parameters:

value- is an 8-bit int with each bit representing a bit of the I/O port.

Returns:

Undefined

Function:

These functions allow the I/O port Input Level Control (INLVLx) registers to be set. Each bit in the value represents one pin. A 1 sets the corresponding pin's input level to Schmitt Trigger (ST) level, and a 0 sets the corresponding pin's input level to TTL level.

Availability:

All devices with ODC registers, however not all devices have all I/O ports and not all devices port's have a corresponding ODC register.

Requires:

Constants are defined in the device's .h file

Examples:

```
set_input_level_a(0x0);    //sets PIN_A0 input level to ST and
all other
```

```
//PORTA pins to TTL level
```

See Also:

output_high(), output_low(), output_bit(), output_x(), General Purpose I/O

set_motor_pwm_duty()

Syntax:

```
set_motor_pwm_duty(pwm,group,time);
```

Parameters:

pwm- Defines the pwm module used.

group- Output pair number 1,2 or 3.

time- The value set in the duty cycle register.

Returns:

Void

Function:

Configures the motor control PWM unit duty.

Availability:

Devices that have the motor control PWM unit.

Requires:

Examples:

```
set_input_level_a(0x0);    //sets PIN_A0 input level to ST and
all other                  //PORTA pins to TTL level
```

See Also:

get_motor_pwm_count(), set_motor_pwm_event(), set_motor_unit(), setup_motor_pwm()

set_motor_pwm_event()

Syntax:

```
set_motor_pwm_event(pwm,time);
[PCD] set_motor_pwm_event(pwm,time,[postscale]);
```

Parameters:

pwm- Defines the pwm module used.

time- The value in the special event comparator register used for scheduling other events.

[PCD] postscale- Optional parameter to set the special trigger output postscale (1-16). Defaults to 1 if not specified.

Returns:

Void

Function:

Configures the PWM event on the motor control unit.

Availability:

Devices that have the motor control PWM unit.

Requires:

Examples:

```
set_motor_pwm_event(pwm,time);
```

```
[PCD] set_motor_pwm_event(1,625,2);
```

See Also:

get_motor_pwm_count(), setup_motor_pwm(), set_motor_unit(), set_motor_pwm_duty()

set_motor_unit()

Syntax:

```
set_motor_unit(pwm,unit,options, active_deadtime, inactive_deadtime);
```

Parameters:

pwm- Defines the pwm module used

Unit- This will select Unit A or Unit B

options- The mode of the power PWM module. See the devices .h file for all options

active_deadtime- Set the active deadtime for the unit

inactive_deadtime- Set the inactive deadtime for the unit

Returns:

Void

Function:

Configures the motor control PWM unit.

Availability:

Devices that have the motor control PWM unit.

Requires:

Examples:

```
set_motor_unit(pwm,unit,MPWM_INDEPENDENT | MPWM_FORCE_L_1,  
active_deadtime,  
inactive_deadtime);
```

See Also:

get motor pwm count(), set motor pwm event(), set motor pwm duty(),
setup motor pwm()

set_nco_accumulator()

Syntax:

set_nco_accumulator(**value**);

Parameters:

value - The 20-bit value to set the NCO accumulator to.

Returns:

Function:

Used to set the NCO accumulator to a specific value.

Availability:

Devices with a Numerically Controlled Oscillator (NCO) module.

Requires:

Examples:

```
set_nco_accumulator(500000);
```

See Also:

[setup_nco\(\)](#), [get_nco_accumulator\(\)](#), [set_nco_inc_value\(\)](#), [get_nco_inc_value\(\)](#)

set_nco_inc_value()

Syntax:

```
set_nco_inc_value(value);
```

Parameters:

value- *value to set the NCO increment registers*

Returns:

Undefined

Function:

Sets the value that the NCO's accumulator will be incremented by on each clock pulse. The increment registers are double buffered so the new value won't be applied until the accumulator rolls-over.

Availability:

Devices with a NCO module

Requires:

Examples:

```
set_nco_inc_value(inc_value);           //sets the new increment
value
```

See Also:

[setup_nco\(\)](#), [get_nco_accumulator\(\)](#), [get_nco_inc_value\(\)](#)

set_open_drain_x(value)

Syntax:

```
set_open_drain_a(value)
set_open_drain_b(value)
set_open_drain_c(value)
set_open_drain_d(value)
```

```
set_open_drain_e(value)
set_open_drain_f(value)
set_open_drain_g(value)
set_open_drain_h(value)
set_open_drain_j(value)
set_open_drain_k(value)
```

Parameters:

value – is an 8-bit int with each bit representing a bit of the I/O port.

[PCD] value – is a 16-bit int with each bit representing a bit of the I/O port.

Returns:

Function:

These functions allow the I/O port Open-Drain Control (ODCONx) registers to be set. Each bit in the value represents one pin. A 1 sets the corresponding pin to act as an open-drain output, and a 0 sets the corresponding pin to act as a digital output.

[PCD] Enables/Disables open-drain output capability on port pins. Not all ports or port pins have open-drain capability, refer to devices data sheet for port and pin availability.

Availability:

Devices with a NCO module

Requires:

Examples:

```
set_open_drain_a(0x01);           //makes PIN_A0 an open-drain output.
set_open_drain_b(0x001);         //enables open-drain output on PIN-B0
                                  //disable on all other port B pins
```

See Also:

[output_high\(\)](#), [output_low\(\)](#), [output_bit\(\)](#), [output_x\(\)](#), [General Purpose I/O](#)

set_power_pwm_override()

Syntax:

```
set_power_pwm_override(pwm, override, value)
```

Parameters:

pwm - is a constant between 0 and 7

Override - is true or false

Value - is 0 or 1

Returns:

Undefined

Function:

pwm - selects which module will be affected.

Override - determines whether the output is to be determined by the OVDCONS register or the PDC registers. When override is false, the PDC registers determine the output. When override is true, the output is determined by the value stored in OVDCONS.

value - determines if pin is driven to it's active staet or if pin will be inactive. I will be driven to its active state, 0 pin will be inactive.

Availability:

All devices equipped with PWM.

Requires:

Examples:

```
set_power_pwm_override(1, true, 1); //PWM1 will be overridden to
active state
set_power_pwm_override(1, false, 0); //PMW1 will not be overridden
```

See Also:

setup_power_pwm(), setup_power_pwm_pins(), set_power_pwmX_duty()

set_power_pwmX_duty()**Syntax:**

set_power_pwmX_duty(***duty***)

Parameters:

X is 0, 2, 4, or 6

Duty is an integer between 0 and 16383

Returns:

Undefined

Function:

Stores the value of duty into the appropriate PDCXL/H register. This duty value is the amount of time that the PWM output is in the active state.

Availability:

All devices equipped with PWM.

Requires:

Examples:

```
set_power_pwm_duty(4000);
```

See Also:

setup_power_pwm(), setup_power_pwm_pins(), set_power_pwm_override()

set_pulldown()**Syntax:**

set_Pulldown(state [, pin])

Parameters:

Pins are defined in the devices .h file. If no pin is provided in the function call, then all of the pins are set to the passed in state.

State is either true or false.

Returns:

Undefined

Function:

Sets the pin's pull down state to the passed in state value. If no pin is included in the function call, then all valid pins are set to the passed in state.

Availability:

All devices equipped with pull-down hardware

Requires:

Pin constants are defined in the devices .h file

Examples:

```
set_pulldown(true, PIN_B0);    //Sets pin B0's pull down state to true
    set_pullup(false);         //Sets all pin's pull down state to
false
```

set_pullup()

Syntax:

`set_pullup(state, [ pin])`

Parameters:

Pins are defined in the devices .h file. If no pin is provided in the function call, then all of the pins are set to the passed in state.

State is either true or false.

Pins are defined in the devices .h file. The actual number is a bit address. For example, port a (byte 5) bit 3 would have a value of $5 \times 8 + 3$ or 43. This is defined as follows: `#DEFINE PIN_A3 43` . The pin could also be a variable that has a value equal to one of the predefined pin constants. Note if no pin is provided in the function call, then all of the pins are set to the passed in state.

Returns:

Undefined

Function:

Sets the pin's pull up state to the passed in state value. If no pin is included in the function call, then all valid pins are set to the passed in state.

Availability:

All Devices

Requires:

Pin constants are defined in the devices .h file

Examples:

```
set_pullup(true, PIN_B0);           //Sets pin B0's pull up state to true
set_pullup(false);                  //Sets all pin's pull up state to false
```

set_pwm1_duty() set_pwm2_duty() set_pwm3_duty() **set_pwm4_duty() set_pwm5_duty()**

Syntax:

`set_pwm1_duty (value)`
`set_pwm2_duty (value)`
`set_pwm3_duty (value)`

```
set_pwm4_duty (value)
set_pwm5_duty (value)
[PCD] set_pwmX_duty (value)
```

Parameters:

value - may be an 8 or 16 bit constant or variable

Returns:

Undefined

Function:

Writes the 10-bit value to the PWM to set the duty. An 8-bit value may be used if the most significant bits are not required. The 10 bit value is then used to determine the duty cycle of the PWM signal as follows:

$$\text{duty cycle} = \text{value} / [4 * (\text{PR2} + 1)]$$

If an 8-bit value is used, the duty cycle of the PWM signal is determined as follows:

$$\text{duty cycle} = \text{value} / (\text{PR2} + 1)$$

Where PR2 is the maximum value timer 2 will count to before toggling the output pin.

[PCD] PIC24FxxKLxxx devices, writes the 10-bit value to the PWM to set the duty. An 8-bit value may be used if the most significant bits are not required. The 10-bit value is then used to determine the duty cycle of the PWM signal as follows:

$$\text{duty cycle} = \text{value} / [4 * (\text{PRx} + 1)]$$

Where PRx is the maximum value timer 2 or 4 will count to before rolling over.

PIC24FxxKMxxx devices, wires the 16-bit value to the PWM to set the duty. The 16-bit value is then used to determine the duty cycle of the PWM signal as follows:

$$\text{duty cycle} = \text{value} / (\text{CCPxPRL} + 1)$$

Where CCPxPRL is the maximum value timer 2 will count to before toggling the output pin.

Availability:

This function is only available on devices with CCP/PWM hardware.

[PCD] This function is only available on devices with MCCP and/or SCCP modules.

Requires:

Examples:

```
frequency,                                     // For a 20 mhz clock, 1.2 khz
                                              // t2DIV set to 16, PR2 set to 200
                                              // the following sets the duty to
50% (or 416 us).
```

```

long duty;

duty = 408; // [408/(4*(200+1))]=0.5=50%
set_pwm1_duty(duty);

[PIC24FxxKLxxx Devices]
// 32 MHz clock
unsigned int16 duty;
setup_timer2(T2_DIV_BY_4, 199, 1); //period=50us
setup_ccp1(CCP_PWM);

duty=400;
//duty=400/[4*(199+1)]=0.5=50%
set_pwm1_duty(duty);

[PIC24FxxKMxxx Devices]
// 32 MHz clock
unsigned int16 duty;

setup_ccp1(CCP_PWM);
set_timer_period_ccp1(799); //period=50us
duty=400; //duty=400/(799+1)=0.5=50%
set_pwm1_duty(duty);

```

Example Files:

ex_pwm.c

See Also:

setup_ccpX(), set_ccpX_compare_time(), set_timer_period_ccpX(), set_timer_ccpX(),
get_timer_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

set_pwm1_offset() set_pwm2_offset() set_pwm3_offset() set_pwm4_offset() set_pwm5_offset() set_pwm6_offset()

Syntax:

```

set_pwm1_offset(value)
set_pwm2_offset(value)
set_pwm3_offset(value)
set_pwm4_offset(value)
set_pwm5_offset(value)
set_pwm6_offset(value)

```

Parameters:

value - 16-bit constant or variable

Returns:

Undefined

Function:

Writes the 16-bit to the PWM to set the offset. The offset is used to adjust the waveform of a slave PWM module relative to the waveform of a master PWM module.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
set_pwm1_offset(0x0100);
set_pwm1_offset(offset);
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_period(), clear_pwm_interrupt(), set_pwm_phase(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

**set_pwm1_period() set_pwm2_period() set_pwm3_period()
set_pwm4_period() set_pwm5_period() set_pwm6_period()**

Syntax:

```
set_pwm1_period (value)
set_pwm2_period (value)
set_pwm3_period (value)
set_pwm4_period (value)
set_pwm5_period (value)
set_pwm6_period (value)
```

Parameters:

value - 16-bit constant or variable

Returns:

Undefined

Function:

Writes the 16-bit to the PWM to set the period. When the PWM module is set-up for standard mode it sets the period of the PWM signal. When set-up for set on match mode, it sets the maximum value at which the phase match can occur. When in toggle on match and center aligned modes it sets the maximum value the PWMxTMR will count to, the actual period of PWM signal will be twice what the period was set to.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
set_pwm1_period(0x8000);
set_pwm1_period(period);
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_phase(), clear_pwm_interrupt(), set_pwm_offset(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

set_pwm_x_phase()**Syntax:**

```
set_pwm1_phase (value)
set_pwm2_phase (value)
set_pwm3_phase (value)
set_pwm4_phase (value)
set_pwm5_phase (value)
set_pwm6_phase (value)
```

Parameters:

value - 16-bit constant or variable

Returns:

Undefined

Function:

Writes the 16-bit to the PWM to set the phase. When the PWM module is set-up for standard mode the phaes specifies the start of the duty cycle, when in set on match

mode it specifies when the output goes high, and when in toggle on match mode it specifies when the output toggles. Phase is not used when in center aligned mode.

Availability:

Devices with a 16-bit PWM module

Requires:

Examples:

```
set_pwm1_phase(0);
set_pwm1_phase(phase);
```

See Also:

setup_pwm(), set_pwm_duty(), set_pwm_period(), clear_pwm_interrupt(),
set_pwm_offset(), enable_pwm_interrupt(), disable_pwm_interrupt(),
pwm_interrupt_active()

set_timerx() set_rtcc() set_timer0() set_timer1() set_timer2() set_timer3() set_timer4() set_timer5()

Syntax:

```
set_timerX(value)
set_timer0(value)   or   set_rtcc (value)
set_timer1(value)
set_timer2(value)
set_timer3(value)
set_timer4(value)
set_timer5(value)
```

Parameters:

Timers 1 & 5 get a 16 bit int.

Timer 2 and 4 gets an 8 bit int.

Timer 0 (AKA RTCC) gets an 8 bit int except on the PIC18XXX where it needs a 16 bit int.

Timer 3 is 8 bit on PIC16 and 16 bit on PIC18

Returns:

Undefined

Function:

Sets the count value of a real time clock/counter. RTCC and Timer0 are the same. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2...)

Availability:

Timer 0 - All devices
 Timers 1 & 2 - Most but not all PCM devices
 Timer 3 - Only PIC18XXX and some pick devices
 Timer 4 - Some PCH devices
 Timer 5 - Only PIC18XX31

Requires:

Examples:

```

// 20 mhz clock, no prescaler,
//set timer 0 to overflow in 35us
// 256-(.000035/(4/20000000))

set_timer0(81);
```

Example Files:

ex_patg.c

See Also:

set_timer1(), get_timerX() Timer0 Overview, Timer1Overview, Timer2 Overview, Timer5 Overview

set_ticks()**Syntax:**

set_ticks([stream],value);

Parameters:

stream – optional parameter specifying the stream defined in #USE TIMER

value – a 8, 16 or 32 bit integer, specifying the new value of the tick timer. (int8, int16 or int32)

[PCD] value – a 8, 16, 32 or 64 bit integer, specifying the new value of the tick timer. (int8, int16, int32 or int64)

Returns:

Void

Function:

Sets the new value of the tick timer. Size passed depends on the size of the tick timer.

Availability:

All Devices

Requires:

#USE TIMER(options)

Examples:

```
#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)

void main(void) {
    unsigned int16 value = 0x1000;

    set_ticks(value);
}                                     // 256-
(.000035/(4/20000000))
```

See Also:

#USE TIMER, get_ticks()

setup_sd_adc_calibration()

Syntax:

setup_sd_adc_calibration(model);

Parameters:

mode- selects whether to enable or disable calibration mode for the SD ADC module.

The following defines are made in the device's .h file:

```
SDADC_START_CALIBRATION_MODE
SDADC_END_CALIBRATION_MODE
```

Returns:

Function:

To enable or disable calibration mode on the Sigma-Delta Analog to Digital Converter (SD ADC) module. This can be used to determine the offset error of the module, which then can be subtracted from future readings.

Availability:

Devices with a SD ADC module

Requires:

#USE TIMER(options)

Examples:

```
signed int 32 result, calibration;

set_sd_adc_calibration(SDADC_START_CALIBRATION_MODE);
calibration=read_sd_adc()
set_sd_adc_calibration(SDADC_END_CALIBRATION_MODE);

result=read_sd_adc()-calibration;
```

See Also:

setup_sd_adc(), read_sd_adc(), set_sd_adc_channel()

set_sd_adc_channel()

Syntax:

setup_sd_adc(channel);

Parameters:

channel- sets the SD ADC channel to read. Channel can be 0 to read the difference between CH0+ and CH0-, 1 to read the difference between CH1+ and CH1-, or one of the following:

```
SDADC_CH1SE_SVSS
SDADC_REFERENCE
```

Returns:

Void

Function:

To select the channel that the Sigma-Delta Analog to Digital Converter (SD ADC) performs the conversion on.

Availability:

Devices with a SD ADC module

Requires:

Examples:

```
set_sd_adc_channel(0);
```

See Also:

setup_sd_adc(), read_sd_adc(), set_sd_adc_calibration()

set_slow_slew_x()

Syntax:

```
set_slow_slew_a(value);
set_slow_slew_b(value);
set_slow_slew_c(value);
set_slow_slew_d(value);
set_slow_slew_e(value);
set_slow_slew_f(value);
set_slow_slew_g(value);
set_slow_slew_h(value);
```

Parameters:

value - may be a 1-bit constant or an 8-bit value (see the device's header file to determine which) used to enable and disable slew rating limiting on a port or port pin.

Devices that take a 1-bit constant passing a 1 to function enables slew rate limiting on entire port. Passing a 0 to function disables slew rate limiting on entire port. Devices that take an 8-bit value, each bit corresponds to a pin on the port. Setting a bit enables slew rate limiting on that port's corresponding pin and clearing a bit disables slew rate limiting on that port's corresponding pin.

Returns:

Function:

Used to enable and disable slew rate limiting on the device's ports or port pins.

Availability:

Devices that have Slew Rate Control registers for enabling and disabling slew rate limiting.

Requires:

Examples:

```
set_slow_slew_a(TRUE);
set_slow_slew_a(0x03);
```

See Also:

[set_tris_x\(\)](#), [set_input_level_x\(\)](#), [set_open_drain_x\(\)](#), [get_tris_x\(\)](#), [output_x\(\)](#), [input_x\(\)](#), [input_change_x\(\)](#), [port_x_pullups\(\)](#), [input\(\)](#), [input_state\(\)](#), [output_low\(\)](#), [output_high\(\)](#), [output_toggle\(\)](#), [output_bit\(\)](#), [output_float\(\)](#), [output_drive\(\)](#)

set_timerA()

Syntax:

```
set_timerA(value);
```

Parameters:

An 8 bit integer. Specifying the new value of the timer. (int8)

Returns:

Function:

Sets the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, ...)

Availability:

Devices with Timer A hardware

Requires:

Examples:

```

timer A                                     // 20 mhz clock, no prescaler, set
set_timerA(81);                             // to overflow in 35us
                                           // 256-(.000035/(4/20000000))
```

See Also:

[get_timerA\(\)](#), [setup_timer_A\(\)](#), [TimerA Overview](#)

set_timerB()

Syntax:

```
set_timerB(value);
```

Parameters:

An 8 bit integer. Specifying the new value of the timer. (int8)

Returns:

Function:

Sets the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, ...)

Availability:

Devices with Timer B hardware

Requires:

Examples:

```

timer B                                     // 20 mhz clock, no prescaler, set
                                           // to overflow in 35us
set_timerB(81);                           // 256-(.000035/(4/20000000))

```

See Also:

[get_timerB\(\)](#), [setup_timer_B\(\)](#), [TimerB Overview](#)

set_timerxy()

Syntax:

set_timerXY(*value*)

Parameters:

A 32 bit integer, specifying the new value of the timer. (int32)

Returns:

Function:

Retrieves the 32 bit value of the timers X and Y, specified by XY(which may be 23, 45, 67 and 89)

Availability:

This function is available on all devices that have a valid 32 bit enabled timers. Timers 2 & 3, 4 & 5, 6 & 7 and 8 & 9 may be used. The target device must have one of these timer sets. The target timers must be enabled as 32 bit.

Requires:

Examples:

```
if(get_timer45() == THRESHOLD)
    set_timer(THRESHOLD + 0x1000);           //skip those timer
values
```

See Also:

[Timer Overview](#), [setup_timerX\(\)](#), [get_timerXY\(\)](#), [set_timerX\(\)](#), [set_timerXY\(\)](#)

set_timer_ccp1() set_timer_ccp2() set_timer_ccp3() **set_timer_ccp4() set_timer_ccp5() set_timer_ccp6()**

Syntax:

```
set_timer_ccpx(time);
set_timer_ccpx(timeL, timeH);
```

Parameters:

time - may be a 32-bit constant or variable. Sets the timer value for the CCPx module when in 32-bit mode.

timeL - may be a 16-bit constant or variable to set the value of the lower timer when CCP module is set for 16-bit mode.

timeH - may be a 16-bit constant or variable to set the value of the upper timer when CCP module is set for 16-bit mode.

Returns:

Function:

This function sets the timer values for the CCP module. TimeH is optional parameter when using 16-bit mode, defaults to zero if not specified.

Availability:

Available only on PIC24FxxKMxxx family of devices with a MCCP and/or SCCP modules.

Requires:

Examples:

```

setup_ccp1(CCP_TIMER);      //set for dual timer mode
set_timer_ccp1(100,200);    //set lower timer value to 100 and upper
timer                        //value to 200

```

See Also:

set_pwmX_duty(), setup_ccpX(), set_ccpX_compare_time(), get_capture_ccpX(),
set_timer_period_ccpX(), get_timer_ccpX(), get_captures32_ccpX()

set_timer_period_ccp1() **set_timer_period_ccp2()**
set_timer_period_ccp3() **set_timer_period_ccp4()**
set_timer_period_ccp5() **set_timer_period_ccp6()**

Syntax:

```

set_timer_period_ccpx(time);
set_timer_period_ccpx(timeL, timeH);

```

Parameters:

time - may be a 32-bit constant or variable. Sets the timer value for the CCPx module when in 32-bit mode.

timeL - may be a 16-bit constant or variable to set the value of the lower timer when CCP module is set for 16-bit mode.

timeH - may be a 16-bit constant or variable to set the value of the upper timer when CCP module is set for 16-bit mode.

Returns:

Function:

This function sets the timer periods for the CCP module. When setting up CCP module in 32-bit function is only needed when using Timer mode. Period register are not used when module is setup for 32-bit compare mode, period is always 0xFFFFFFFF. TimeH is optional parameter when using 16-bit mode, default to zero if not specified.

Availability:

Available only on PIC24FxxKMxxx family of devices with a M CCP and/or S CCP modules.

Requires:

Examples:

```

setup_ccp1(CCP_TIMER);           //set for dual timer mode
set_timer_period_ccp1(800,2000); //set lower timer period to 800 and
                                   //upper timer period to 2000

```

See Also:

set_pwmX_duty(), setup_ccpX(), set_ccpX_compare_time(), set_timer_ccpX(),
get_timer_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

set_tris()**Syntax:**

```

set_tris_a(value)
set_tris_b(value)
set_tris_c(value)
set_tris_d(value)
set_tris_e(value)
set_tris_f(value)
set_tris_g(value)
set_tris_h(value)
set_tris_j(value)
set_tris_k(value)
set_tris_l(value)

```

Parameters:

value is an **8** bit int with each bit representing a bit of the I/O port.

[PCD] ***value*** is an **16** bit int with each bit representing a bit of the I/O port.

Returns:

Undefined

Function:

These functions allow the I/O port direction (TRI-State) registers to be set.

This must be used with FAST_IO and when I/O ports are accessed as memory such as when a # BYTE directive is used to access an I/O port.

[PCD] This must be used with FAST_IO and when I/O ports are accessed as memory such as when a #word directive is used to access an I/O port.

Using the default standard I/O the built in functions set the I/O direction automatically.

Each bit in the value represents one pin. A 1 indicates the pin is input and a 0 indicates it is output.

Availability:

All devices (however not all devices have all I/O ports)

Requires:

Pin constants are defined in the devices .h file

Examples:

```
SET_TRIS_B( 0x0F );           // B7,B6,B5,B4 are outputs
                               // B3,B2,B1,B0 are inputs
                               [PCD] // B15,B14,B13,B12,B11,B10,B9,B8,
```

Example Files:

lcd.c

See Also:

#USE FAST_IO, #USE FIXED_IO, #USE STANDARD_IO, General Purpose I/O

set_uart_speed()

Syntax:

set_uart_speed (*baud*, [*stream*, *clock*])

Parameters:

baud - is a constant representing the number of bits per second.

stream - is an optional stream identifier.

clock - is an optional parameter to indicate what the current clock is if it is different from the #use delay value

Returns:

Function:

Changes the baud rate of the built-in hardware RS232 serial port at run-time.

Availability:

This function is only available on devices with a built in UART

Requires:

#USE RS232

Examples:

```
                               // Set baud rate based on setting
                               // of pins B0 and B1
switch( input_b() & 3 ) {
```

```
case 0 : set_uart_speed(2400); break;
case 1 : set_uart_speed(4800); break;
case 2 : set_uart_speed(9600); break;
case 3 : set_uart_speed(19200); break;
}
```

Example Files:

[loader.c](#)

See Also:

[#USE RS232](#), [putc\(\)](#), [getc\(\)](#), [setup_uart\(\)](#), [RS232 I/O Overview](#)

setjmp()**Syntax:**

result = setjmp (*env*)

Parameters:

env - The data object that will receive the current environment

Returns:

If the return is from a direct invocation, this function returns 0.

If the return is from a call to the longjmp function, the setjmp function returns a nonzero value and it's the same value passed to the longjmp function.

Function:

Stores information on the current calling context in a data object of type jmp_buf and which marks where you want control to pass on a corresponding longjmp call.

Availability:

All Devices

Requires:

#INCLUDE <setjmp.h>

Examples:

```
result = setjmp(jmpbuf);
```

See Also:

[longjmp\(\)](#)

setup_act()

Syntax:

```
setup_act(settings);
```

Parameters:

settings - to setup the ACT module. See the device's header file for options.

Returns:

Function:

Used to setup the Active Clock Tuning (ACT) module.

Availability:

Devices with an ACT module. See the device's header file for availability.

Requires:

Examples:

```
setup_act (ACT_ENABLED | ACT_TUNED_TO_USE);
```

See Also:

act_status()

setup_adc(mode)

[PCD] setup_adc2(mode)

Syntax:

```
setup_adc (mode, [ADCRS], [ADRPT]);
```

```
[PCD] setup_adc2(mode);
```

Parameters:

mode- Analog to digital mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include:

ADC_OFF

ADC_CLOCK_INTERNAL

ADC_CLOCK_DIV_32

[PCD] ADC_CLOCK_INTERNAL – The ADC will use an internal clock

[PCD] ADC_CLOCK_DIV_32 – The ADC will use the external clock scaled down by 32

[PCD] ADC_TAD_MUL_16 – The ADC sample time will be 16 times the ADC conversion time

ADCRS - For devices with an analog-to-digital converter with computation (ADC2) module only. Optional parameter used set how much the accumulated value is divided by (2^{ADCRS}) in Accumulate, Average and Parst Average modes, and the cut-off frequency in low-pass filter mode.

ADRPT - For devices with an ADC2 module only. Optional parameter used to set the number of samples to be done before performing a threshold comparison in Average, Bust Average and low-pass filter modes.

Returns:

Function:

Configures the analog to digital converter.

[PCD] Configures the ADC clock speed and the ADC sample time. The ADC converters have a maximum speed of operation, so ADC clock needs to be scaled accordingly. In addition, the sample time can be set by using a bitwise OR to concatenate the constant to the argument.

Availability:

Only the devices with built in analog to digital converter.

Requires:

Constants are defined in the devices .h file.

Examples:

```
setup_adc_ports( ALL_ANALOG );
setup_adc(ADC_CLOCK_INTERNAL );
set_adc_channel( 0 );
value = read_adc();
setup_adc( ADC_OFF )
```

Example Files:

[ex_admm.c](#)

See Also:

[setup_adc_ports\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#), [#DEVICE](#), [ADC Overview](#)

setup_adc_ports()

[PCD] setup_adc_ports2()

Syntax:

```

setup_adc_ports (value)
setup_adc_ports (ports, [reference])
setup_adc_ports (ports, [ports2], [reference])
setup_adc_ports (ports, [p2_ports], [reference])
[PCD] setup_adc_ports (ports, reference)

```

Parameters:

value - a constant defined in the device's .h file

ports - a constant specifying the ADC pins to use.

ports2 - an optional constant on devices with more than 32 analog pins. To specify the ADC pins to use for analog pins 32-x.

p2_ports - an optional constant specifying the ADC pins to use on a device that have more than 32 analog pins. Not an option on all devices, see the device's header file to determine if available. For devices with this option, if setting ADC reference, the reference is passed as the third parameter.

reference - is an optional constant specifying the ADC reference to use. By default, the reference voltage are Vss and Vdd

Returns:

Function:

Sets up the ADC pins to be analog, digital, or a combination and the voltage reference to use when computing the ADC value. The allowed analog pin combinations vary depending on the chip and are defined by using the bitwise OR to concatenate selected pins together. Check the device include file for a complete list of available pins and reference voltage settings. The constants ALL_ANALOG and NO_ANALOGS are valid for all chips.

Some other example pin definitions are:

```

SAN1 | SAN2 - AN1 and AN2 are analog, remaining pins are digital
SAN0 | SAN3 - AN0 and AN3 are analog, remaining pins are digital

```

Availability:

This function is only available on devices with A/D hardware.

This function is only available on devices with built-in A/D converters

Requires:

Constants are defined in the devices .h file.

Examples:

```

setup_adc_ports(ALL_ANALOG);           // All pins analog (that can
be)

setup_adc_ports(RA0_RA1_ANALOG_RA3_REF); // Pins A0 and A1 are analog.
Pin RA3 is                               // used for the reference
voltage and all                           // other pins are digital.
setup_adc_ports(ALL_ANALOG);           // Set all ADC pins to analog
mode.

setup_adc_ports(sAN0|sAN1|sAN3);        // Pins AN0, AN1 and AN3 are
analog and all                           // others pins are digital.
setup_adc_ports(sAN0|sAN1, VREF_VDD);   // Pins AN0 and AN1 are analog.
The VrefL pin                             // and Vdd are used for voltage
references.

```

Example Files:

[ex_admm.c](#)

See Also:

[setup_adc_reference\(\)](#), [set_adc_channel\(\)](#), [read_adc\(\)](#), [setup_adc\(\)](#), [set_analog_pins\(\)](#), [ADC Overview](#)

setup_adc_reference() setup_adc_reference2()

Syntax:

```
setup_adc_reference(reference)
```

Parameters:

reference - the voltage reference to set the ADC. The valid options depend on the device, see the device's .h file for all options. Typical options include:

- VSS_VDD
- VSS_VREF
- VREF_VREF
- VREF_VDD

Returns:

Undefined.

Function:

Set the positive and negative voltage reference for the Analog to Digital Converter (ADC) uses.

Availability:

Only on devices with an ADC and has ANSELx, x being the port letter; registers for setting which pins are analog or digital.

Requires:

Nothing

Examples:

```
setup_adc_reference(VSS_VREF);
```

Examples Files:

None

See Also:

set_analog_pins(), set_adc_channel(), read_adc(), setup_adc(), setup_adc_ports(),
ADC Overview

setup_adc_reference() setup_adc_reference2()**Syntax:**

```
setup_adc_reference(reference)
```

Parameters:

reference - the voltage reference to set the ADC. The valid options depend on the device, see the device's .h file for all options. Typical options include:

- VSS_VDD
- VSS_VREF
- VREF_VREF
- VREF_VDD

Returns:

Undefined.

Function:

Set the positive and negative voltage reference for the Analog to Digital Converter (ADC) uses.

Availability:

Only on devices with an ADC and has ANSELx, x being the port letter; registers for setting which pins are analog or digital.

Requires:

Nothing

Examples:

```
setup_adc_reference(VSS_VREF);
```

Examples Files:

None

See Also:

set_analog_pins(), set_adc_channel(), read_adc(), setup_adc(), setup_adc_ports(),
ADC Overview

setup_at()**Syntax:**

setup_at(**settings**)

Parameters:

settings - the setup of the AT module. See the device's header file for all options.

Some typical options include:

- at_enabled
- at_disabled
- at_multi_pulse_mode
- at_single_pulse_mode

Returns:

Function:

To setup the Angular Timer (AT) module.

Availability:

All devices with an AT module

Requires:

Constants defined in the device's .h file

Examples:

```
setup_at(AT_ENABLED|AT_MULTI_PULSE_MODE|AT_INPUT_ATIN);
```

See Also:

[at_set_resolution\(\)](#), [at_get_resolution\(\)](#), [at_set_missing_pulse_delay\(\)](#),
[at_get_missing_pulse_delay\(\)](#), [at_get_period\(\)](#), [at_get_phase_counter\(\)](#),
[at_set_set_point\(\)](#), [at_get_set_point\(\)](#), [at_get_set_point_error\(\)](#), [at_enable_interrupts\(\)](#),
[at_disable_interrupts\(\)](#), [at_clear_interrupts\(\)](#), [at_interrupt_active\(\)](#), [at_setup_cc\(\)](#),
[at_set_compare_time\(\)](#), [at_get_capture\(\)](#), [at_get_status\(\)](#)

setup_capture()

Syntax:

```
setup_capture(x, mode)
```

Parameters:

x - is 1-16 and defines which input capture module is being configured

mode - is defined by the constants in the devices .h file

Returns:

Function:

This function specifies how the input capture module is going to function based on the value of mode. The device specific options are listed in the device .h file

Availability:

Only available on devices with Input Capture modules

Requires:

Examples:

```
setup_timer3(TMR_INTERNAL | TMR_DIV_BY_8);
setup_capture(2, CAPTURE_FE | CAPTURE_TIMER3);
while(TRUE) {
    timerValue = get_capture(2, TRUE);
    printf("Capture 2 occurred at: %LU", timerValue);
}
```

See Also:

[get_capture\(\)](#), [setup_compare\(\)](#), [Input Capture Overview](#)

setup_ccp1() setup_ccp2() setup_ccp3() setup_ccp4() setup_ccp5() setup_ccp6() setup_ccp8() setup_ccp9() setup_ccp10()

Syntax:

setup_ccp1 (*mode*) or setup_ccp1 (*mode*, *pwm*)

setup_ccp2 (*mode*) or setup_ccp2 (*mode*, *pwm*)

setup_ccp3 (*mode*) or setup_ccp3 (*mode*, *pwm*)

setup_ccp5 (*mode*) or setup_ccp5 (*mode*, *pwm*)

setup_ccp6 (*mode*) or setup_ccp6 (*mode*, *pwm*)

[PCD] setup_ccpx(*mode*,[*pwm*]);//PIC24FxxKLxxx devices

[PCD] setup_ccpx(*mode1*,[*mode2*],[*mode3*],[*dead_time*]);//PIC24FxxKMxxx devices

Parameters:

mode - is a constant. Valid constants are defined in the devices .h file and refer to devices .h file for all options; some options are as follows:

Disable the CCP

CCP_CAPTURE_FE	Capture on falling edge
CCP_CAPTURE_RE	Capture on rising edge
CCP_CAPTURE_DIV_4	Capture after 4 pulses
CCP_CAPTURE_DIV_16	Capture after 16 pulses

Set CCP to Capture Mode:

CCP_CAPTURE_SET_ON_MATCH	Output high on compare
CCP_CAPTURE_CLR_ON_MATCH	Output low on compare
CCP_CAPTURE_INT	Interrupt on compare
CCP_CAPTURE_RESET_TIMER	Reset timer on compare

Set to CCP to PWM Mode:

CCP_PWM	Enable Pulse Width Modulator

Constants used for ECCP Modules:

CCP_PWM_H_H
CCP_PWM_H_L
CCP_PWM_L_H
CCP_PWM_L_L

CCP_PWM_FULL_BRIDGE
CCP_PWM_FULL_BRIDGE_REV
CCP_PWM_HALF_BRIDGE

CCP_SHUTDOWN_ON_COMP1	Shutdown on Comparator 1 change
CCP_SHUTDOWN_ON_COMP2	Shutdown on Comparator 2 change
CCP_SHUTDOWN_ON_COMP	Either Comparator 1 or 2 change
CCP_SHUTDOWN_ON_INT0	VIL on INT pin
CCP_SHUTDOWN_ON_COMP1_INT0	VIL on INT pin or Comparator 1 change
CCP_SHUTDOWN_ON_COMP2_INT0	VIL on INT pin or Comparator 2 change
CCP_SHUTDOWN_ON_COMP_INT0	VIL on INT pin or Comparator 1 or 2 change
CCP_SHUTDOWN_AC_L	Drive pins A and C high
CCP_SHUTDOWN_AC_H	Drive pins A and C low
CCP_SHUTDOWN_AC_F	Drive pins A and D tri-state
CCP_SHUTDOWN_BD_L	Drive pins B and D high
CCP_SHUTDOWN_BD_H	Drive pins B and D low
CCP_SHUTDOWN_BD_F	Drive pins B and D tri-state
CCP_SHUTDOWN_RESTART	Device restart after a shutdown event
CCP_DELAY	Use the deadband delay

pwm parameter - is an optional parameter for chips that includes ECCP module. This parameter allows setting the shutdown time. The value may be 0-255.

[PCD] mode and **mode1** - constants used for setting up the CCP module. Valid constants are defined in the device's .h file; refer to the device's .h file for all options. Some typical options are as follows:

```
CCP_OFF
CCP_COMPARE_INT_AND_TOGGLE
CCP_COMPARE_FE
CCP_COMPARE_RE
CCP_COMPARE_DIV_4
CCP_COMPARE_DIV_16
CCP_COMPARE_SET_ON_MATCH
CCP_COMPARE_CLR_ON_MATCH
CCP_COMPARE_INT
CCP_COMPARE_RESET_TIMER
CCP_PWM
```

[PCD] mode2 is an optional parameter for setting up more settings of the CCP module. Valid constants are defined in the device's .h file, refer to the device's .h file for all options.

[PCD] mode3 is an optional parameter for setting up more settings of the CCP module. Valid constants are defined in the device's .h file, refer to the device's .h file for all options.

[PCD] pwm is an optional parameter for devices that have an ECCP module. this parameter allows setting the shutdown time. The value may be 0-255.

[PCD] dead_time is an optional parameter for setting the dead time when the CCP module is operating in PWM mode with complementary outputs. The value may be 0-63, 0 is the default setting if not specified.

Returns:

Function:

Initialize the CCP. The CCP counters may be accessed using the long variables CCP_1 and CCP_2. The CCP operates in 3 modes. In capture mode it will copy the timer 1 count value to CCP_x when the input pin event occurs. In compare mode it will trigger an action when timer 1 and CCP_x are equal. In PWM mode it will generate a square wave. The PCW wizard will help to set the correct mode and timer settings for a particular application.

[PCD] Initializes the CCP module. For PIC24FxxKLxxx devices the CCP module can operate in three modes (Capture, Compare or PWM).

Capture Mode - the value of Timer 3 is copied to the CCPRxH and CCPRxL registers when an input event occurs.

Compare Mode - will trigger an action when Timer 3 and the CCPRxL and CCPRxH registers are equal.

PWM Mode - will generate a square wave, the duty cycle of the signal can be adjusted using the CCPRxL register and the DCxB bits of the CCPxCON register. The function set_pwm_duty() is provided for setting the duty cycle when in PWM mode.

PIC24FxxKMxxx devices, the CCP module can operate in four mode (Timer, Capture, Compare or PWM). IN Timer mode, it functions as a timer. The module has two basic modes, it can function as two independent 16-bit timers/counters or as a single 32-bit timer/counter. The mode it operates in is controlled by the option CCP_TIMER_32_BIT, with the previous options added, the module operates as a single 32-bit timer, and if not added, it operates as two 16-bit timers. The function set_timer_period_ccpx() is provided to set the period(s) of the timer, and the functions set_timer_ccpx() and get_timer_ccpx() are provided to set and get the current value of the timer(s).

In Capture mode, the value of the timer is captured when an input event occurs, it can operate in either 16-bit or 32-bit mode. The functions `get_capture_ccpx()` and `get_capture32_ccpx()` are provided to get the last capture value.

In Compare and PWM modes, the value of the timers is compared to one or two compare registers, depending on its mode of operation, to generate a single output transition or a train of output pulses. For signal output edge modes, `CCP_COMPARE_SET_ON_MATCH`, `CCP_COMPARE_CLR_ON_MATCH`, and `CCP_COMPARE_TOGGLE`, the module can operate in 16 or 32-bit mode, all other modes can only operate in 16-bit mode. However, when in 32-bit mode the timer source will only rollover when it reaches `0xFFFFFFFF` or when reset from an external synchronization source. Therefore, a period of less than `0xFFFFFFFF` is needed, as it requires an external synchronization source to reset the timer. The functions `set_ccpx_compare_time()` and `set_pwmX_duty()` are provided for setting the compare registers.

Availability:

This function is only available on devices with CCP hardware.

[PCD] Only on devices with the MCCP and/or SCCP modules.

Requires:

Constants are defined in the devices .h file.

Examples:

```
setup_ccp1(CCP_CAPTURE_RE);
[PCD]
setup_ccp1(CCP_CAPTURE_FE);
setup_ccp1(CCP_COMPARE_TOGGLE);
setup_ccp1(CCP_PWM);
```

Example Files:

`ex_pwm.c`, `ex_ccmp.c`, `ex_ccp1s.c`

See Also:

`set_pwmX_duty()`, `set_ccpX_compare_time()`, `set_timer_period_ccpX()`,
`set_timer_ccpX()`, `get_timer_ccpX()`, `get_capture_ccpX()`, `get_captures32_ccpX()`

setup_clc1() setup_clc2() setup_clc3() setup_clc4()

Syntax:

```
setup_clc1(mode);
setup_clc2(mode);
setup_clc3(mode);
setup_clc4(mode);_capture(x, mode)
```

Parameters:

mode – The mode to setup the Configurable Logic Cell (CLC) module into. See the device's .h file for all options. Some typical options include:

```
CLC_ENABLED
CLC_OUTPUT
CLC_MODE_AND_OR
CLC_MODE_OR_XOR
```

Returns:

Function:

Sets up the CLC module to performed the specified logic. Please refer to the device datasheet to determine what each input to the CLC module does for the select logic function

Availability:

Devices with a CLC module

Requires:

Examples:

```
setup_clc1(CLC_ENABLED | CLC_MODE_AND_OR);
```

See Also:

[clcx_setup_gate\(\)](#), [clcx_setup_input\(\)](#)

setup_comparator()

Syntax:

setup_comparator (*mode*)

[PCD] setup_comparator (**comparator**, *mode*);

[PCD] setup_comparator (**comparator**, *mode*, [blanking_period]);

Parameters:

mode is a constant. Valid constants are in the devices .h file refer to devices .h file for valid options. Some typical options are as follows:

```
A0_A3_A1_A2
A0_A2_A1_A2
NC_NC_A1_A2
NC_NC_NC_NC
```

```
A0_VR_A1_VR
A3_VR_A2_VR
A0_A2_A1_A2_OUT_ON_A3_A4
A3_A2_A1_A2
```

[PCD] comparator - constant specifying which comparator to setup.

[PCD] mode - constants specifying the settings to setup the specified comparator. See the device's .h file for all options. Some typical options include:

```
CXINB_CXINA
CXINC_CSINA
CXIND_CXINA
CXINB_VREF
CXINC_VREF
CXIND_VREF
COMP_INVERT
COMP_OUTPUT
```

[PCD] blanking_period - optional parameter available on devices with an Analog Comparator with Slope Compensation DAC peripheral. See the device's header file for availability. It sets the 10-bit blanking period for the comparator following changes to the DAC output during Change-of-State.

Returns:

Function:

Sets the analog comparator module. The above constants have four parts representing the inputs: C1-, C1+, C2-, C2+

[PCD] Configures the voltage comparator. The voltage comparators allow to compare two voltages and find the greater of them. The configuration constants for this function specify the sources for the comparator in the order Cx- and Cx+. The results of the comparator modules are stored in CxOUT. COMP_INVERT will invert the result of the comparator and COMP_OUTPUT will output the result to the comparator output pin.

Availability:

This function is only available on devices with an analog comparator.

[PCD] Devices with a comparator module.

Requires:

Constants are defined in the devices .h file

Examples:

```
//Sets up two independent
comparators (C1 and C2),
```

```

// C1 uses A0 and A3 as
inputs (- and +), and C2
// uses A1 and A2 as inputs
setup_comparator(A0_A3_A1_A2);
[PCD] setup_comparator(1,CXINB_CXINA); // setup C1
      setup_comparator(2,CXINB_CXINA); // setup C2

```

Example Files:

[ex_comp.c](#)

See Also:

[Analog Comparator Overview](#), [setup_comparator_filter\(\)](#), [setup_comparator_mask\(\)](#), [setup_comparator_dac\(\)](#), [setup_comparator_slope\(\)](#)

[PCD]setup_comparator_dac()

Syntax:

```

[PCD] setup_comparator_dac(settings);
[PCD] setup_comparator_dac(settings, [tmode_time], [ss_time]);

```

Parameters:

[PCD] settings - constants specifying the settings to setup the comparator and DAC. See the device's header file for defines that can be used with this parameter.

[PCD] tmode_time - optional 10-bit value used to set the Transition Mode Duration, value passed for this parameter should be less than the ss-time parameter.

[PCD] ss_time - optional 10-bit parameter used to set the time from Start of Transmission Mode until Steady-State filter is enabled.

Returns:

Function:

[PCD] Used to setup the common settings for the Analog Comparator with Slope Compensation DAC peripheral. Some common settings include enabling/disabling the common DAC module, DAC clock source, comparator filter clock divider, etc.

Availability:

[PCD] Devices with the High-Speed Analog Comparator with the Slope Compensation DAC peripheral. See the device's header file to determine if the function is available.

Requires:

Examples:

```
[PCD] setup_comparator_dac (COMP_COMMON_DAC_ENABLE |
    COMP_DAC_CLK_SRC_FPLLO, 85, 138);
```

See Also:

[Analog Comparator Overview](#), [setup_comparator\(\)](#), [setup_comparator_slope\(\)](#), [dac_write\(\)](#)

setup_comparator_filter()**Syntax:**

```
[PCD] setup_comparator (comparator, mode);
```

Parameters:

[PCD] **comparator** - constant specifying which comparator filter to setup.

[PCD] **mode** - constants specifying the settings to setup the specified comparator's filter.

See the device's .h file for all options. Some typical options include:

```
COMP_FILTER_ENABLE
COMP_FILTER_CLK_T3
COMP_FILTER_CLK_T2
COMP_FILTER_CLK_FOSC
COMP_FILTER_CLK_INTERNAL
COMP_FILTER_CLK_DIV_BY_4
COMP_FILTER_CLK_DIV_BY_2
COMP_FILTER_CLK_DIV_BY_1
```

Returns:

Function:

[PCD] Configures the voltage comparator's digital filter.

Availability:

[PCD] Devices with a comparator module that has a digital filter. See the device's header file to determine if the device has a digital filter as part of the comparator module.

Requires:

Constants are defined in the devices .h file

Examples:

```
[PCD]  setup_comparator_filter(1,COMP_FILTER_ENABLE|
      COMP_FILTER_CLK_FOSC|COMP_FILTER_CLK_DIV_BY_4);
```

See Also:

[Analog Comparator Overview](#), [setup_comparator\(\)](#), [setup_comparator_mask\(\)](#)

setup_comparator_mask()**Syntax:**

```
[PCD] setup_comparator_mask (comparator, mode, [input1], [input2], [input3]);
```

Parameters:

[PCD] **comparator** - constant specifying which comparator filter to setup.

[PCD] **mode** - constants specifying the settings to setup the specified comparator's mask registers. See the device's .h file for all options. Some typical options include:

```
COMP_MASK_COMP_HIGH
COMP_MASK_COMP_LOW
COMP_MASK_MAI_CONNECTED_TO_OR
COMP_MASK_INVERTED_MAI_CONNECTED_TO_OR
COMP_MASK_MAI_CONNECTED_TO_AND
COMP_MASK_INVERTED_MAI_CONNECTED_TO_AND
```

[PCD] **input1, input2, input3** - optional parameters specifying the inputs to mask. See the device's .h file for all options. Some typical options include:

```
COMP_MASK_INPUT_PWM3H
COMP_MASK_INPUT_PWM3L
COMP_MASK_INPUT_PWM2H
COMP_MASK_INPUT_PWM2L
COMP_MASK_INPUT_PWM1H
COMP_MASK_INPUT_PWM1L
```

Returns:

Function:

[PCD] Configures the voltage comparator's output blanking function.

Availability:

[PCD] Devices with a comparator module that has a output blanking function. See the device's header file to determine if the device has an output blanking function as part of the comparator module.

Requires:

Constants are defined in the devices .h file

Examples:

```
[PCD]  setup_comparator_mask(1,COMP_MASK_COMP_LOW|
      COMP_MASK_MAI_CONNECTED_TO_AND, COMP_MASK_INPUT_PWM1H;
```

See Also:

[Analog Comparator Overview](#), [setup_comparator\(\)](#), [setup_comparator_filter\(\)](#)

[PCD] setup_comparator_slope()

Syntax:

```
[PCD] setup_comparator_slope(comparator, settings, rate);
```

Parameters:

[PCD] comparator - constant specifying which comparator to setup.

[PCD] settings - constants specifying the settings to setup the comparator and DAC. See the device's header file for defines that can be used with this parameter.

[PCD] rate - 16-bit value used to set slope ramp rate, the value is in 12.4 format.

Returns:

Function:

[PCD] Used to setup the Analog Comparator with Slope Compensation DAC peripheral slope settings.

Availability:

[PCD] Devices with the High-Speed Analog Comparator with the Slope Compensation DAC peripheral. See the device's header file to determine if the function is available.

Requires:

Examples:

```
[PCD] setup_comparator_slope(1,COMP_ENABLE_SLOPE_FUNCTION |
    COMP_SLOPE_START_SIG_PWM1_TRIG_1 |
    COMP_SLOPE_STOP_B_SIG_COMP1 |
    COMP_SLOPE_STOP_A_SIG_PWM1_TRIG_1, 500000);
```

See Also:

[Analog Comparator Overview](#), [setup_comparator\(\)](#), [setup_comparator_dac\(\)](#), [dac_write\(\)](#)

setup_comparator_x()**Syntax:**

```
setup_comparator_1(mode);
setup_comparator_2(mode);
setup_comparator_3(mode);
setup_comparator_4(mode);
setup_comparator_5(mode);
setup_comparator_6(mode);
setup_comparator_7(mode);
setup_comparator_8(mode);
```

Parameters:

mode - to setup the comparator in. Valid options are device dependent. See the device's header file for all valid options.

Returns:

Function:

Used to setup one of the Analog Comparator modules.

Availability:

On most devices that have more than three Analog Comparator modules.

Requires:

Examples:

```
setup_comparator_1(CP1_A1_A0 | CP1_INVERT);
```


See Also:

[setup_comparator\(\)](#), [Analog Comparator](#)

setup_compare()

Syntax:

setup_compare(*x*, *mode*)

Parameters:

mode - is defined by the constants in the devices .h file

x - is 1-16 and specifies which OC pin to use.

Returns:

Function:

This function specifies how the output compare module is going to function based on the value of ***mode***. The device specific options are listed in the device .h file.

Availability:

Available only on devices with Output Compare Modules

Requires:

Examples:

```

// Pin OC1 will be set
when timer 2
// is equal to 0xF000
setup_timer2(TMR_INTERNAL | TIMER_DIV_BY_16);
set_compare_time(1, 0xF000);
setup_compare(1, COMPARE_SET_ON_MATCH | COMPARE_TIMER2);
```

See Also:

[set_compare_time\(\)](#), [set_pwm_duty\(\)](#), [setup_capture\(\)](#), [Output Compare / PWM Overview](#)

setup_counters()

Syntax:

setup_counters (*rtcc_state*, *ps_state*)

Parameters:

rtcc_state - may be one of the constants defined in the devices .h file.

RTCC_INTERNAL
RTCC_EXT_L_TO_H
RTCC_EXT_H_TO_L

ps_state - may be one of the constants defined in the devices .h file.

RTCC_DIV_2
RTCC_DIV_4
RTCC_DIV_8
RTCC_DIV_16
RTCC_DIV_32
RTCC_DIV_64
RTCC_DIV_128
RTCC_DIV_256
WDT_18MS
WDT_36MS
WDT_72MS
WDT_144MS
WDT_288MS
WDT_576MS
WDT_1152MS
WDT_2304MS

Returns:

Function:

Sets up the RTCC or WDT. The *rtcc_state* determines what drives the RTCC. The *PS* state sets a prescaler for either the RTCC or WDT. The prescaler will lengthen the cycle of the indicated counter. If the RTCC prescaler is set the WDT will be set to WDT_18MS. If the WDT prescaler is set the RTCC is set to RTCC_DIV_1.

This function is provided for compatibility with older versions. *setup_timer_0* and *setup_WDT* are the recommended replacements when possible. For PCB devices if an external RTCC clock is used and a WDT prescaler is used then this function must be used.

Availability:

All Devices

Requires:

Constants are defined in the devices .h file

Examples:

```
setup_counters (RTCC_INTERNAL, WDT_2304MS);
```

See Also:

[setup_wdt\(\)](#), [setup_timer 0\(\)](#), see header file for device selected

setup_crc(mode)

Syntax:

setup_crc(*polynomial terms*)

Parameters:

polynomial - This will setup the actual polynomial in the CRC engine. The power of each term is passed separated by a comma. 0 is allowed, but ignored. The following define is added to the device's header file (32-bit CRC Moduel Only), to enable little-endian shift direction:

```
CRC_LITTLE_ENDIAN
```

Returns:

Function:

Configures the CRC engine register with the polynomial.

Availability:

Devices with built in CRC module

Requires:

Examples:

```
setup_crc (12, 5);                                // CRC Polynomial is  $X^{12} + X^5 + 1$ 

setup_crc(16, 15, 3, 1);                          // CRC Polynomial is  $X^{16} + X^{15} + X^3 + X^1 + 1$ 
```

Example Files:

[ex.c](#)

See Also:

[crc_init\(\)](#); [crc_calc\(\)](#); [crc_calc8\(\)](#)

setup_cog()**setup_cog2()****setup_cog3()****setup_cog4()****Syntax:****setup_cog(mode, [shutdown]);****setup_cog(mode, [shutdown], [sterring]);****Parameters:****mode**- the setup of the COG module. See the device's .h file for all options. Some typical options include:

COG_ENABLED
 COG_DISABLED
 COG_CLOCK_HFINTOSC
 COG_CLOCK_FOSC

shutdown- the setup for the auto-shutdown feature of COG module. See the device's .h file for all the options. Some typical options include:

COG_AUTO_RESTART
 COG_SHUTDOWN_ON_C1OUT
 COG_SHUTDOWN_ON_C2OUT

steering- optional parameter for steering the PWM signal to COG output pins and/or selecting the COG pins static level. Used when COG is set for steered PWM or synchronous steered PWM modes. Not available on all devices, see the device's .h file if available and for all options. Some typical options include:

COG_PULSE_STEERING_A
 COG_PULSE_STEERING_B
 COG_PULSE_STEERING_C
 COG_PULSE_STEERING_D

Returns:

Function:

Sets up the Complementary Output Generator (COG) module, the auto-shutdown feature of the module and if available steers the signal to the different output pins.

Availability:

Devices with built in COG module

Requires:

Examples:

```
setup_cog(COG_ENABLED | COG_PWM | COG_FALLING_SOURCE_PWM3 |
COG_RISING_SOURCE_PWM3, COG_NO_AUTO_SHUTDOWN,
COG_PULSE_STEERING_A | COG_PULSE_STEERING_B);
```

See Also:

set cog dead band(), set cog phase(), set cog blanking(), cog status(), cog restart()

setup_cwg() setup_cwg2() setup_cwg3()**Syntax:**

```
setup_cwg(mode,shutdown,dead_time_rising,dead_time_falling)
```

Parameters:

mode - the setup of the CWG module. See the device's .h file for all options. Some typical options include:

```
CWG_ENABLED
CWG_DISABLED
CWG_OUTPUT_B
CWG_OUTPUT_A
```

shutdown - the setup for the auto-shutdown feature of CWG module. See the device's .h file for all the options. Some typical options include:

```
CWG_AUTO_RESTART
CWG_SHUTDOWN_ON)COMP1
CWG_SHUTDOWN_ON_FLT
CWG_SHUTDOWN_ON_CLC2
```

dead_time_rising - value specifying the dead time between A and B on the rising edge. (0-63)

dead_time_falling - value specifying the dead time between A and B on the falling edge. (0-63)

Returns:

```
-----
```

Function:

Sets up the CWG module, the auto-shutdown feature of module and the rising and falling dead times of the module.

Availability:

Devices with built in CWG module

Requires:

Examples:

```
setup_cwg(CWG_ENABLED|CWG_OUTPUT_A|CWG_OUTPUT_B|CWG_INPUT_PWM1,CWG_SHUTDOWN_ON_F
LT,60,30);
```

See Also:

cwg_status(), cwg_restart()

[PCD] setup_current_source()

Syntax:

setup_current_source(**mode**);

Parameters:

mode - setup the Constant Current Source module. Valid options are device dependent. See the device's header file for all options.

Returns:

Function:

Used to setup the Constant Current Source module.

Availability:

Devices that have a Constant Current Source module.

Requires:

Examples:

```
setup_current_source(CURRENT_SOURCE_ENABLED | CURRENT_SOURCE_D5);
```

setup_dac()

Syntax:

```
setup_dac(mode);
setup_dac2(mode);
setup_dac3(mode);
```

```

setup_dac4(mode);
setup_dac5(mode);
setup_dac6(mode);
setup_dac7(mode);
setup_dac8(mode);
[PCD] setup_dac(mode, divisor);
[PCD] setup_dac(module, mode);

```

Parameters:

mode - The mode to setup the DAC module in. The valid options vary depending on the device. See the device's header file for all options.

[PCD] **divisor** - Divides the provided clock.

[PCD] **module** - DAC module setup.

Returns:

Function:

Setup the DAC module.

Availability:

Devices with a digital-to-analog converter (DAC).

Requires:

Examples:

```

setup_dac(DAC_VSS_VDD | DAC_OUTPUT);

```

```

[PCD] setup_dac(DAC_RIGHT_ON, 5);
      setup_dac(1, DAC_ON)

```

See Also:

[dac_write](#), [DAC](#). See header file for selected device.

setup_dci()

Syntax:

```

setup_dci(configuration, data size, rx config, tx config, sample rate);

```

Parameters:

configuration - Specifies the configuration the Data Converter Interface should be initialized into, including the mode of transmission and bus properties. The following constants may be combined (OR'd) for this parameter:

```
CODEC_MULTICHANNEL
CODEC_I2S· CODEC_AC16
CODEC_AC20· JUSTIFY_DATA· DCI_MASTER
DCI_SLAVE· TRISTATE_BUS· MULTI_DEVICE_BUS
SAMPLE_FALLING_EDGE· SAMPLE_RISING_EDGE
DCI_CLOCK_INPUT· DCI_CLOCK_OUTPUT
```

data size – Specifies the size of frames and words in the transmission:

```
DCI_xBIT_WORD: x may be 4 through 16
DCI_xWORD_FRAME: x may be 1 through 16
DCI_xWORD_INTERRUPT: x may be 1 through 4
```

rx config- Specifies which words of a given frame the DCI module will receive (commonly used for a multi-channel, shared bus situation)

```
RECEIVE_SLOTx: x May be 0 through 15
RECEIVE_ALL· RECEIVE_NONE
```

tx config- Specifies which words of a given frame the DCI module will transmit on.

```
TRANSMIT_SLOTx: x May be 0 through 15
TRANSMIT_ALL
TRANSMIT_NONE
```

sample rate - The desired number of frames per second that the DCI module should produce. Use a numeric value for this parameter. Keep in mind that not all rates are achievable with a given clock. Consult the device datasheet for more information on selecting an adequate clock.

Returns:

Function:

Configures the DCI module.

Availability:

Only available on devices with DCI peripheral.

Requires:

Constants are defined in the devices .h file

Examples:

```

dci_initialize((I2S_MODE|DCI_MASTER|DCI_CLOCK_OUTPUT|SAMPLE_RISING_EDGE|UNDERFLOW_LAST|
MULTI_DEVICE_BUS,DCI_1WORD_FRAME|DCI_16BIT_WORD|DCI_2WORD_INTERRUPT,
RECEIVE_SLOT0|RECEIVE_SLOT1, TRANSMIT_SLOT0|TRANSMIT_SLOT1, 44100
);

```

See Also:

DCI Overview, [dci start\(\)](#), [dci write\(\)](#), [dci read\(\)](#), [dci transmit ready\(\)](#), [dci data received\(\)](#)

setup_dedicated_adc()

Syntax:

```
setup_dedicated_adc(core, mode);
```

Parameters:

core - the dedicated ADC core to setup

mode - the mode to setup the dedicated ADC core in. See the device's .h file all options.

Some typical options include:

```

ADC_DEDICATED_CLOCK_DIV_2
ADC_DEDICATED_CLOCK_DIV_6
ADC_DEDICATED_TAD_MUL_2
ADC_DEDICATED_TAD_MUL_3

```

Returns:

Function:

Configures one of the dedicated ADC core's clock speed and sample time.

Function should be called after the [setup_adc\(\)](#) function.

Availability:

Only available on dsPIC33EPxxGSxxx family of devices.

Requires:

Constants are defined in the devices .h file

Examples:

```

setup_dedicated_adc(0,ADC_DEDICATED_CLOCK_DIV_2|ADC_DEDICATED_TAD_MUL_1025)

```

See Also:

setup_adc(), setup_adc_ports(), set_adc_channel(), read_adc(), adc_done(),
set_dedicated_adc_channel(), ADC Overview

setup_dma()**Syntax:**

```
setup_dma(channel, start_trigger, abort_trigger);
```

```
[PCD] setup_dma(channel, peripheral, mode);
```

```
[PCD] setup_dma(channel, trigger, mode);
```

Parameters:

channel -The DMA channel to setup.

start_trigger - The trigger source to cause the DMA channel to start the transfer when HW trigger is enabled. See header file for all possible sources.

abort_trigger - The trigger source to cause the DMA channel to abort the transfer when HW abort trigger is enabled. See header file for all possible sources.

[PCD] ***peripheral*** - The peripheral that the DMA channel transfers data to and from.

Constants for setting the trigger source are defined in the device's .h file, see header file for all possible peripherals.

[PCD] ***trigger*** - The trigger source to cause the DMA channel to start the transfer.

Constants for setting the trigger source are defined in the device's header file, see header file for all possible sources.

[PCD] ***mode*** - The mode to use for the DMA transfers. Constants for setting the mode are defined in the device's header file, see header file for all possible options.

Returns:

Function:

Configures the DMA peripheral to copy data from one location to another.

Availability:

Devices that have a DMA peripheral. [PCD] The version of the function depends on the type of DMA peripheral it has. Use ***getenv("DMA")*** to determine the type the device has. It will return 0 for no DMA peripheral, 1 for Type 1 and 2 for Type 2. For devices with

Type 1 uses first version of the function and for devices with Type 2 uses second version of the function.

Requires:

Examples:

```
[PCD]
setup_dma(0, DMA_IN_UART1, DMA_BYTE);      // Type 1
setup_dma(0, DMA_TRIGGER_RDA, DMA_BYTE |
DMA_RELOAD_ADDRESS);                       // Type 2

setup_dma(1, DMA_TRIGGER_RDA, DMA_TRIGGER_NONE);
```

Example Files:

ex_dma_uart_rx.c

See Also:

dma_start(), dma_status()

setup_dmt()

Syntax:

`setup_dmt(mode, max_time, window_time);`

Parameters:

mode - This sets if whether the DMT is always enabled or can be enabled and disabled in software. The following defines are made in the device's header file for setting the following:

```
DMT_SOFTWARE  // DMT can be enabled and disabled in software.
DMT_ENABLED   // DMT is ways enabled.
```

max_time - A 32-bit constant value for setting the count that causes a DMT event to occur.

window_time - A 32-bit constant value for setting the count value at which it is possible to clear the DMT count value.

Returns:

Function:

Sets up the Deadman Timer (DMT) peripheral. This function does not generate any assembly code, it only causes the DMT configuration fuses to be set to the specified values.

Availability:

Only on devices that have the DMT peripheral.

Requires:

Examples:

```
//Setup DMT peripheral to be enabled and disabled in software
//with a max count of 50000 and can be cleared after count
//reaches 10000.
setup_dmt(DMT_SOFTWARE, 50000, 10000);
```

See Also:

[clear_dmt\(\)](#), [read_dmt\(\)](#), [disable_dmt\(\)](#), [enable_dmt\(\)](#), [dmt_status\(\)](#)

setup_dsm()

Syntax:

```
setup_dsm(enable);
setup_dsm2(enable);
setup_dsm3(enable);
setup_dsm4(enable);
setup_dsm(mode, source, carrier);
setup_dsm2(mode, source, carrier);
setup_dsm3(mode, source, carrier);
setup_dsm4(mode, source, carrier);
```

Parameters:

enable – a 1-bit constant used to enable and disable the DSM module. If 1 is passed as the parameter, the DSMx module is enabled, and if 0 is passed as the parameter, the DSM module is disabled.

mode - the mode to setup the DSM module. Valid options vary by device. See the device's header file for all options.

source - used to set the signal source for the DSM module. Valid options vary by device. See the device's header file for all options.

carrier - used to set the high and low level carriers for the DSM module. Valid options vary by device. See the device's header file for all options.

Returns:

Function:

Used to setup the DSM module.

Availability:

Devices that have a Data Signal Modulator (DSM) module

Requires:

Examples:

```
setup_dsm(DSM_ENABLED, DSM_SOURCE_U1TX, DSM_CARRIER_LOW_CCP1 |  
          DSM_CARRIER_HIGH_CCP2);
```

See Also:

[Data Signal Modulator Overview](#)

setup_external_memory()

Syntax:

```
setup_external_memory(mode);
```

Parameters:

mode - is one or more constants from the device header file OR'ed together.

Returns:

Function:

Sets the mode of the external memory bus.

Availability:

Devices that allow external memory bus.

Requires:

Constants are defined in the devices .h file

Examples:

```
setup_external_memory(EXTMEM_WORD_WRITE|EXTMEM_WAIT_0 );
setup_external_memory(EXTMEM_DISABLE);
```

See Also:

[WRITE PROGRAM EEPROM\(\)](#) , [WRITE PROGRAM MEMORY\(\)](#), [External Memory Overview](#)

setup_high_speed_adc()

Syntax:

```
setup_external_memory(mode);
```

Parameters:

mode - Analog to digital mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include:

```
ADC_OFF
ADC_CLOCK_DIV_1
ADC_HALT_IDLE      (The ADC will not run when device is idle)
```

Returns:

Function:

Configures the High-Speed ADC clock speed and other High-Speed ADC options including, when the ADC interrupts occurs, the output result format, the conversion order, whether the ADC pair is sampled sequentially or simultaneously, and whether the dedicated sample and hold is continuously sampled or samples when a trigger event occurs.

Availability:

dsPIC33FJxxGSxxx devices

Requires:

Constants are defined in the devices .h file

Examples:

```
setup_high_speed_adc_pair(0, INDIVIDUAL_SOFTWARE_TRIGGER);
setup_high_speed_adc(ADC_CLOCK_DIV_4);
read_high_speed_adc(0, START_AND_READ, result);
setup_high_speed_adc(ADC_OFF);
```

See Also:

setup_high_speed_adc_pair(), read_high_speed_adc(), high_speed_adc_done()

setup_high_speed_adc_pair()**Syntax:**

```
setup_high_speed_adc_pair(pair, mode);
```

Parameters:

pair – The High-Speed ADC pair number to setup, valid values are 0 to total number of ADC pairs. 0 sets up ADC pair AN0 and AN1, 1 sets up ADC pair AN2 and AN3, etc.

mode – ADC pair mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include:

```
INDIVIDUAL_SOFTWARE_TRIGGER
GLOBAL_SOFTWARE_TRIGGER
PWM_PRIMARY_SE_TRIGGER
PWM_GEN1_PRIMARY_TRIGGER
PWM_GEN2_PRIMARY_TRIGGER
```

Returns:

```
-----
```

Function:

Sets up the analog pins and trigger source for the specified ADC pair. Also sets up whether ADC conversion for the specified pair triggers the common ADC interrupt.

If zero is passed for the second parameter the corresponding analog pins will be set to digital pins.

Availability:

dsPIC33FJxxGSxxx devices

Requires:

Constants are defined in the devices .h file

Examples:

```
setup_high_speed_adc_pair(0, INDIVIDUAL_SOFTWARE_TRIGGER);
setup_high_speed_adc_pair(1, GLOBAL_SOFTWARE_TRIGGER);
setup_high_speed_adc_pair(2, 0)           //sets AN4 and AN5
as digital pins
```

See Also:

setup_high_speed_adc(), read_high_speed_adc(), high_speed_adc_done()

setup_hspwm() setup_hspwm_secondary()

Syntax:

```
setup_hspwm(mode, value);  
setup_hspwm_secondary(mode, value);    //if available
```

Parameters:

mode - Mode to setup the High Speed PWM module in. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include:

```
HSPWM_ENABLED  
HSPWM_HALT_WHEN_IDLE  
HSPWM_CLOCK_DIV_1
```

value - 16-bit constant or variable to specify the time bases period.

Returns:

Function:

Enable the High Speed PWM module and set up the Primary and Secondary Time base of the module.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_hspwm(HSPWM_ENABLED | HSPWM_CLOCK_DIV_BY4, 0x8000);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock(), setup_hspwm_secondary()

setup_hspwm_blanking()**Syntax:**

```
setup_hspwm_blanking(unit, settings, delay);
```

Parameters:

unit - The High Speed PWM unit to set.

settings - Settings to setup the High Speed PWM Leading-Edge Blanking. The valid options vary depending on the device. See the device's header file for all options.

Some typical options include:

```
HSPWM_RE_PWMH_TRIGGERS_LE_BLANKING
HSPWM_FE_PWMH_TRIGGERS_LE_BLANKING
HSPWM_RE_PWML_TRIGGERS_LE_BLANKING
HSPWM_FE_PWML_TRIGGERS_LE_BLANKING
HSPWM_LE_BLANKING_APPLIED_TO_FAULT_INPUT
HSPWM_LE_BLANKING_APPLIED_TO_CURRENT_LIMIT_INPUT
```

delay - 16-bit constant or variable to specify the leading-edge blanking time.

Returns:

Function:

Sets up the analog pins and trigger source for the specified ADC pair. Also sets up whether ADC conversion for the specified pair triggers the common ADC interrupt.

If zero is passed for the second parameter the corresponding analog pins will be set to digital pins.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```
setup_hspwm_blanking(HSPWM_RE_PWMH_TRIGGERS_LE_BLANKING, 10);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(),
setup_hspwm_blanking(), set_hspwm_override(), get_hspwm_capture(),
setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock()
setup_hspwm(), setup_hspwm_secondary(), setup_high_speed_adc(),
read_high_speed_adc(), high_speed_adc_done()

setup_hspwm_chop_clock()

Syntax:

setup_hspwm_chop_clock(**settings**);

Parameters:

unit - The High Speed PWM unit to set.

settings - a value from 1 to 1024 to set the chop clock divider. Also one of the following can be or'd with the value:

HSPWM_CHOP_CLK_GENERATOR_ENABLED
HSPWM_CHOP_CLK_GENERATOR_DISABLED

Returns:

Function:

Setup and High Speed PWM Chop Clock Generator and divisor.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```
setup_hspwm_chop_clock(HSPWM_CHOP_CLK_GENERATOR_ENABLED|32);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(),
setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(),
get_hspwm_capture(), setup_hspwm_unit_chop_clock(), setup_hspwm(),
setup_hspwm_secondary()

setup_hspwm_current_limit()

Syntax:

`setup_hspwm_current_limit(unit, settings);`

Parameters:

unit - The High-Speed PWM unit to setup.

settings - An int32 value to setup the PWM Generator Current Limit PCI registers. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Current Limit PCI registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hswm_current_limit(1, HSPWM_PCI_SRC_MASTER_PCI10 |
HSPWM_ACCEPTANCE_QUALIFIER_PWM_TRIGGERED |
HSPWM_TERMINATION_QUALIFIER_DUTY_CYCLE |
HSPWM_PCI_ACCEPTANCE_LATCHED_ANY_EDGE);
```

See Also:

[setup_hspwm\(\)](#), [setup_hspwm_event_output_x\(\)](#), [setup_hspwm_logic_x\(\)](#),
[setup_hspwm_unit\(\)](#), [setup_hspwm_blanking\(\)](#), [setup_hspwm_event\(\)](#),
[setup_hspwm_fault\(\)](#), [setup_hspwm_feed_forward\(\)](#), [setup_hspwm_sync\(\)](#),
[set_hspwm_scaling\(\)](#), [set_hspwm_override\(\)](#), [set_hspwm_phase\(\)](#),
[set_hspwm_duty\(\)](#), [set_hspwm_period\(\)](#), [set_hspwm_duty_adjustment\(\)](#),
[set_hspwm_trigger_x\(\)](#), [get_hspwm_feedback\(\)](#), [get_hspwm_capture\(\)](#),
[get_hspwm_status\(\)](#), [hspwm_trigger_pwm\(\)](#), [hspwm_stop_pwm\(\)](#), [hspwm_do_capture\(\)](#),
[hspwm_update\(\)](#)

setup_hspwm_event()

Syntax:

`setup_hspwm_event(unit, settings_1, settings_h);`

Parameters:

unit - The High-Speed PWM unit to setup.

settings_1 - An int16 constant value to setup the PWM Generator Event low register settings. See the device's header file for valid defines that can be used with function.

settings_h - An int16 constant value to setup the PWM Generator Event high register settings. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Event registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hswm_EVENT(3, HSPWM_EVENT_TRIGGER_EOC |
HSPWM_EVENT_UPDATE_WRITE_TO_DUTY_CYCLE |
HSPWM_EVENT_ADC_TRIGGER_1_PGxTRIGB_SRC_ENABLED | 30,
HSPWM_EVENT_INTERRUPT_DISABLED |
HSPWM_EVENT_FEED_FORWARD_INTERRUPT_ENABLED | 10);
```

See Also:

setup_hspwm(), setup_hspwm_event_output_x(), setup_hspwm_logic_x(),
setup_hspwm_unit(), setup_hspwm blanking(), setup_hspwm fault(),
setup_hspwm current limit(), setup_hspwm feed forward(), setup_hspwn_sync(),
set_hspwm_scaling(), set_hspwm override(), set_hspwm phase(),
set_hspwm duty(), set_hspwm period(), set_hspwm duty adjustment(),
set_hspwm trigger x(), get_hspwm feedback(), get_hspwm capture(),
get_hspwm_status(), hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(),
hspwm_update()

setup_hspwm_fault()

Syntax:

`setup_hspwm_fault(unit, settings);`

Parameters:

unit - The High-Speed PWM unit to setup.

settings - An int32 value to setup the PWM Generator Fault PCI registers. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Fault PCI registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hspwm_fault(1, HSPWM_PCI_SRC_MASTER_PCI10 |
HSPWM_ACCEPTANCE_QUALIFIER_PWM_TRIGGERED |
HSPWM_TERMINATION_QUALIFIER_DUTY_CYCLE |
HSPWM_PCI_ACCEPTANCE_LATCHED_ANY_EDGE);
```

See Also:

[setup_hspwm\(\)](#), [setup_hspwm_logic_x\(\)](#), [setup_hspwm_unit\(\)](#), [setup_hspwm_blanking\(\)](#),
[setup_hspwm_event\(\)](#), [setup_hspwm_fault\(\)](#), [setup_hspwm_current_limit\(\)](#),
[setup_hspwm_feed_forward\(\)](#), [setup_hspwm_sync\(\)](#), [set_hspwm_scaling\(\)](#),
[set_hspwm_override\(\)](#), [set_hspwm_phase\(\)](#), [set_hspwm_duty\(\)](#), [set_hspwm_period\(\)](#),
[set_hspwm_duty_adjustment\(\)](#), [set_hspwm_trigger_x\(\)](#), [get_hspwm_feedback\(\)](#),
[get_hspwm_capture\(\)](#), [get_hspwm_status\(\)](#), [hspwm_trigger_pwm\(\)](#),
[hspwm_stop_pwm\(\)](#), [hspwm_do_capture\(\)](#), [hspwm_update\(\)](#)

setup_hspwm_feed_forward()

Syntax:

`setup_hspwm_feed_forward(unit, settings);`

Parameters:

unit - The High-Speed PWM unit to setup.

settings - An int32 value to setup the PWM Generator Feed Forward PCI registers. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Feed Forward PCI registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hswm_feed_forward(1, HSPWM_PCI_SRC_MASTER_PCI10 |
HSPWM_ACCEPTANCE_QUALIFIER_PWM_TRIGGERED |
HSPWM_TERMINATION_QUALIFIER_DUTY_CYCLE |
HSPWM_PCI_ACCEPTANCE_LATCHED_ANY_EDGE);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(),
setup_hspwm_blanking(), setup_hspwm_event(), setup_hspwm_fault(),
setup_hspwm_current_limit(),
setup_hspwm_sync(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(),
set_hspwm_duty(), set_hspwm_period(), set_hspwm_duty_adjustment(),
set_hspwm_trigger x(),
get_hspwm_feedback(), get_hspwm_capture(), get_hspwm_status(),
hspwm_trigger_pwm(),
hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update()

setup_hspwm_logic x()

Syntax:

```
setup_hspwm_logic_a(settings);
setup_hspwm_logic_b(settings);
```

```
setup_hspwm_logic_c(settings);
setup_hspwm_logic_d(settings);
setup_hspwm_logic_e(settings);
setup_hspwm_logic_f(settings);
```

Parameters:

settings - An int16 value to setup the PWM Logic control to. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Logic control registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hswm_logic_a(HSPWM_LOGIC_SRC1_PWM1H |
HSPWM_LOGIC_SRC2_PWM4H | HSPWM_LOGIC_SRC1_OR_SRC2 |
HSPWM_LOGIC_ASSIGNED_TO_PWM2);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_unit(),
setup_hspwm_blanking(), setup_hspwm_event(), setup_hspwm_fault(),
setup_hspwm_current_limit(), setup_hspwm_feed_forward(), setup_hspwm_sync(),
set_hspwm_scaling(), set_hspwm_override(), set_hspwm_phase(),
set_hspwm_duty(), set_hspwm_period(), set_hspwm_duty_adjustment(),
set_hspwm_trigger x(), get_hspwm_feedback(), get_hspwm_capture(),
get_hspwm_status(), hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(),
hspwm_update()

setup_hspwm_sync()

Syntax:

```
setup_hspwm_sync(unit, settings);
```

Parameters:

unit - The High-Speed PWM unit to setup.

settings - An int32 value to setup the PWM Generator Sync PCI registers. See the device's header file for valid defines that can be used with function.

Returns:

Function:

To setup the High-Speed PWM (HSPWM) Sync PCI registers.

Availability:

On devices that have the HSPWM peripheral with Fine Edge Placement. See the device's header file to determine if functions are available.

Requires:

Examples:

```
setup_hswm_sync(1, HSPWM_PCI_SRC_MASTER_PCI10 |
HSPWM_ACCEPTANCE_QUALIFIER_PWM_RIGGERED |
HSPWM_TERMINATION_QUALIFIER_DUTY_CYCLE |
HSPWM_PCI_ACCEPTANCE_LATCHED_ANY_EDGE);
```

See Also:

setup_hspwm(), setup_hspwm_event_output x(), setup_hspwm_logic x(),
setup_hspwm_unit(), setup_hspwm_blanking(), setup_hspwm_event(),
setup_hspwm_fault(), setup_hspwm_current_limit(),
setup_hspwm_feed_forward(), set_hspwm_scaling(), set_hspwm_override(),
set_hspwm_phase(), set_hspwm_duty(), set_hspwm_period(),
set_hspwm_duty_adjustment(), set_hspwm_trigger x(),
get_hspwm_feedback(), get_hspwm_capture(), get_hspwm_status(),
hspwm_trigger_pwm(), hspwm_stop_pwm(), hspwm_do_capture(), hspwm_update(),

setup_hspwm_trigger()

Syntax:

setup_hspwm_trigger(**unit**, [**start_delay**], [**divider**], [**trigger_value**], [**strigger_value**]);

Parameters:

unit - The High Speed PWM unit to set.

start_delay - Optional value from 0 to 63 specifying then umber of PWM cycles to wait before generating the first trigger event. For some devices, one of the following may be optional or'd in with the value:

HSPWM_COMBINE_PRIMARY_AND_SECONDARY_TRIGGER
HSPWM_SEPERATE_PRIMARY_AND_SECONDARY_TRIGGER

divider - optional value from 1 to 16 specifying the trigger event divisor.

trigger_value - optional 16-bit value specifying the primary trigger compare time.

strigger_value - optional 16-bit value specifying the secondary trigger compare time.

Returns:

Function:

Sets up the High Speed PWM Trigger event.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Examples:

```
setup_hspwm_trigger(1, 10, 1, 0x2000);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(),
setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(),
setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock(), setup_hspwm(),
setup_hspwm_secondary()

setup_hspwm_unit()

Syntax:

```
setup_hspwm_unit(unit, mode, [dead_time], [alt_dead_time]);  
set_hspwm_duty(unit, primary, [secondary]);
```

Parameters:

unit - The High Speed PWM unit to set.

mode - Mode to setup the High Speed PWM unit in. The valid option vary depending on the device. See the device's header file for all options. Some typical options include:

HSPWM_ENABLE

HSPWM_ENABLE_H
HSPWM_ENABLE_L
HSPWM_COMPLEMENTARY
HSPWM_PUSH_PULL

dead_time - Optional 16-bit constant or variable to specify the dead time for this PWM unit, defaults to 0 if not specified.

alt_dead_time - Optional 16-bit constant or variable to specify the alternate dead time for this PWM unit, default to 0 if not specified.

Returns:

Function:

Sets up the specified High Speed PWM unit.

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_hspwm_unit(1, HSPWM_ENABLE | SHPWM_COMPLEMENTARY, 100, 100);
```

See Also:

set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock(), setup_hspwm(), setup_hspwm_secondary()

setup_hspwm_unit_chop_clock()

Syntax:

```
setup_hspwm_unit_chop_clock(unit, settings);
```

Parameters:

unit - the High Speed PWM unit chop clock to setup.

settings - a settings to setup the High Speed PWM unit chop clock. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include:

```
HSPWM_PWMH_CHOPPING_ENABLED
HSPWM_PWML_CHOPPING_ENABLED
HSPWM_CHOPPING_DISABLED
HSPWM_CLOP_CLK_SOURCE_PWM2H
HSPWM_CLOP_CLK_SOURCE_PWM1H
HSPWM_CHOP_CLK_SOURCE_CHOP_CLK_GENERATOR
```

Returns:

Function:

Setup and High Speed PWM unit's Chop Clock

Availability:

Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_hspwm_unit_chop_clock(1, HSPWM_PWMH_CHOPPING_ENABLED |
                             HSPWM_PWML_CHOPPING_ENABLED |
                             HSPWM_CLOP_CLK_SOURCE_PWM2H);
```

See Also:

setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm(), setup_hspwm_secondary()

setup_lcd()

Syntax:

setup_lcd (*mode*, *prescale*, [*segments0_31*],[*segments32_47*]);

Parameters:

mode - may be any of the following constants to enable the LCD and may be or'ed with other constants in the devices *.h file:

```
LCD_DISABLED, LCD_STATIC, LCD_MUX12, LCD_MUX13, LCD_MUX14
```

prescale - may be 1-16 for the LCD clock.

segments0-31 - may be any of the following constants or'ed together when using the PIC16C92X series of chips::

SEG0_4, SEG5_8, SEG9_11, SEG12_15, SEG16_19, SEG20_26, SEG27_28, SEG29_31
ALL_LCD_PINS

When using the PIC16F/LF1xxx or PIC18F/LFxxxx series of chips, each of the segments are enabled individually. A value of 1 will enable the segment, 0 will disable it and use the pin for normal I/O operation.

segments 32-47 - when using a chip with more than 32 segments, this enables segments 32-47. A value 1 will enable the segment, 0 will disable it. Bit 0 corresponds to segment 32 and bit 15 corresponds to segment 47.

Returns:

Function:

Initialize the LCD Driver Module on the PIC16C92X and PIC16F/LF193X series of devices.

Availability:

Only on devices with built-in LCD Driver Module hardware.

Requires:

Constants are defined in the devices .h file

Examples:

```
setup_lcd(LCD_MUX14|LCD_STOP_ON_SLEEP,2,ALL_LCD_PINS);
// PIC16C92X

setup_lcd(LCD_MUX13|LCD_REF_ENABLED|LCD_B_HIGH_POWER,0,0xFF0429)
;
// PIC16F/LF193X -
//Enables Segments
//0,3,5,10,16,17,18,
19,20,21,22,23
```

Example Files:

ex_92lcd.c

See Also:

lcd_symbol(), lcd_load(), lcd_contrast(), Internal LCD Overview

setup_low_volt_detect()**Syntax:**

```
setup_low_volt_detect(mode)
```

Parameters:

mode may be one of the constants defined in the devices .h file.

```
LVD_LVDIN
LVD_45
LVD_42
LVD_40
LVD_38
LVD_36
LVD_35
LVD_33
LVD_30
LVD_28
LVD_27
LVD_25
LVD_23
LVD_21
LVD_19
```

One of the following may be or'ed(via |) with the above if high voltage detect is also available in the device

```
LVD_TRIGGER_BELOW
LVD_TRIGGER_ABOVE
```

Returns:

```
-----
```

Function:

This function controls the high/low voltage detect module in the device. The mode constants specifies the voltage trip point and a direction of change from that point (available only if high voltage detect module is included in the device). If the device experiences a change past the trip point in the specified direction the interrupt flag is set and if the interrupt is enabled the execution branches to the interrupt service routine.

Availability:

Only available with devices that have the high/low voltage detect module.

Requires:

Constants are defined in the devices .h file

Examples:

```

setup_low_volt_detect( LVD_TRIGGER_BELOW | LVD_36 ); //This
would trigger the                                     //interrupt
when the voltage                                     //is below
3.6 volts

```

setup_motor_pwm()

Syntax:

```

setup_motor_pwm(pwm,options,timebase);
setup_motor_pwm(pwm,options,prescale,postscale,timebase)

```

Parameters:

pwm - Defines the pwm module used.

Options - The mode of the power PWM module. See the devices .h file for all options

timebase - This parameter sets up the PWM time base pre-scale and post-scale.

prescale - This will select the PWM timebase prescale setting

postscale - This will select the PWM timebase postscale setting

Returns:

Function:

Configures the motor control PWM module.

Availability:

Devices that have the motor control PWM unit.

Requires:

Examples:

```

setup_motor_pwm(1,MPWM_FREE_RUN | MPWM_SYNC_OVERRIDES,
timebase);

```

See Also:

get motor pwm count(), set motor pwm event(), set motor unit(), set motor pwm duty()

setup_msi()

Syntax:

setup_msi(*settings*);

Parameters:

settings - Setting to setup the MSI peripheral in. The available options depend on whether the program is for the Master or Slave core of the device. See the device's header file for valid defines that can be used with the function.

Returns:

Function:

Sets up the Master Slave Interface (MSI).

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
//Setup MSI to enable the Slave PIC, interrupt when 1st write to
//FIFO is done by other core, enable write FIFO and enable read FIFO.
setup_msi(MSI_SLAVE_ENABLE | MSI_FIFO_DATA_VALID_INT_ON_1ST_WRITE |
MSI_WRITE_FIFO_ENABLED | MSI_READ_FIFO_ENABLED);
```

See Also:

msi_write_mailbox(), msi_read_mailbox(), msi_status(), msi_read_fifo(),
msi_mailbox_status(), msi_write_fifo(), msi_fifo_status()

setup_nco()

Syntax:

setup_nco(*settings,inc_value*)

Parameters:

settings - setup of the NCO module. See the device's .h file for all options. Some typical options include:

```
NCO_ENABLE
NCO_OUTPUT
NCO_PULSE_FREQ_MODE
NCO_FIXED_DUTY_MODE
```

inc_value - value to increment the NCO 20 bit accumulator by.

Returns:

Function:

Sets up the NCO module and sets the value to increment the 20-bit accumulator by.

Availability:

Devices with a NCO module.

Requires:

Examples:

```
setup_nco(NCO_ENABLED|NCO_OUTPUT|NCO_FIXED_DUTY_MODE|NCO_CLOCK_F
OSC,8192);
```

See Also:

get_nco_accumulator(), set_nco_inc_value(), get_nco_inc_value()

setup_opamp1() setup_opamp2() setup_opamp3() setup_opamp4()

Syntax:

```
setup_opamp1(mode)
setup_opamp2(mode)
setup_opamp3(mode)
setup_opamp4(mode)
```

Parameters:

mode - The mode of the operation amplifier. See the devices .h file for all options.

Some typical options include:

```
OPAMP_ENABLED
OPAMP_DISABLED
```

Returns:

Function:

Enables or Disables the internal operational amplifier peripheral of certain devices.

Availability:

Devices with a built-in operational amplifier (for example, PIC16F785)

Requires:

Examples:

```
setup_opamp1(OPAMP_ENABLED);
setup_opamp2(OPAMP_DISABLED);
setup_opamp3(OPAMP_ENABLED | OPAMP_I_TO_OUTPUT);
```

**setup_opamp1() setup_opamp2() setup_opamp3()
setup_opamp4()**

Syntax:

```
setup_opamp1(mode)
setup_opamp2(mode)
setup_opamp3(mode)
setup_opamp4(mode)
```

Parameters:

mode - The mode of the operation amplifier. See the devices .h file for all options.

Some typical options include:

```
OPAMP_ENABLED
OPAMP_DISABLED
```

Returns:

Function:

Enables or Disables the internal operational amplifier peripheral of certain devices.

Availability:

Devices with a built-in operational amplifier (for example, PIC16F785)

Requires:

Examples:

```
setup_opamp1(OPAMP_ENABLED);
setup_opamp2(OPAMP_DISABLED);
setup_opamp3(OPAMP_ENABLED | OPAMP_I_TO_OUTPUT);
```

setup_oscillator()

Syntax:

setup_oscillator(*mode*, *finetune*)

Parameters:

mode - is dependent on the chip. For example, some chips allow speed setting such as OSC_8MHZ or OSC_32KHZ. Other chips permit changing the source like OSC_TIMER1.

finetune - (only allowed on certain parts) is a signed int with a range of -31 to +31.

Returns:

Some devices return a state such as OSC_STATE_STABLE to indicate the oscillator is stable.

Function:

This function controls and returns the state of the internal RC oscillator on some parts. See the devices .h file for valid options for a particular device.

Note that if INTRC or INTRC_IO is specified in #fuses and a #USE DELAY is used for a valid speed option, then the compiler will do this setup automatically at the start of main().

WARNING: If the speed is changed at run time the compiler may not generate the correct delays for some built in functions. The last #USE DELAY encountered in the file is always assumed to be the correct speed. You can have multiple #USE DELAY lines to control the compilers knowledge about the speed.

Availability:

Devices with a OSCCON register.

Requires:

Constants are defined in the .h file.

Examples:

```
setup_oscillator( OSC_2MHZ );
```

See Also:

#FUSES, [Internal oscillator Overview](#)

[PCD]

Syntax:

setup_oscillator(*mode*, *target* [,*source*] [,*divide*])

Parameters:

mode - is one of:

- OSC_INTERNAL
- OSC_CRYSTAL
- OSC_CLOCK
- OSC_RC
- OSC_SECONDARY

target - is the target frequency to run the device it.

source - is optional. It specifies the external crystal/oscillator frequency. If omitted the value from the last `#USE_DELAY` is used. If mode is `OSC_INTERNAL`, source is an optional tune value for the internal oscillator for devices that support it. If omitted a tune value of zero will be used.

divide in - is optional. For devices that support it, it specifies the divide ration for the Display Module Interface Clock. A number from 0 to 64 divides the clock from 1 to 17 increasing in increments of 0.25, a number from 64 to 96 divides the clock from 17 to 33 increasing in increments of 0.5, and a number from 96 to 127 divides the clock from 33 to 64 increasing in increments of 1. If omitted zero will be used for divide by 1.

Returns:

Function:

Configures the oscillator with preset internal and external source configurations. If the device fuses are set and `#use_delay()` is specified, the compiler will configure the oscillator. Use this function for explicit configuration or programming dynamic clock switches. Please consult your target data sheets for valid configurations, especially when using the PLL multiplier, as many frequency range restrictions are specified.

Availability:

All Devices.

Requires:

Constants are defined in the `.h` file.

Examples:

```
setup_oscillator( OSC_CRYSTAL, 4000000, 16000000);
setup_oscillator( OSC_INTERNAL, 29480000);
```

See Also:

[`setup\_wdt\(\)`](#), [Internal Oscillator Overview](#)

setup_pga()

Syntax:

setup_pga(module,settings)

Parameters:

module - constant specifying the Programmable Gain Amplifier (PGA) to setup.

Returns:

Function:

This function allows for setting up one of the Programmable Gain Amplifier modules.

Availability:

Devices with a Programmable Gain Amplifier module.

Requires:

Examples:

```
setup_pga(PGA_ENABLED | PGA_POS_INPUT_PGAXP1 | PGA_GAIN_8X);
```

setup_pid()

Syntax:

setup_pid([mode],[K1],[K2],[K3]);

Parameters:

mode - the setup of the PID module. The options for setting up the module are defined in the device's header file as:

```
PID_MODE_PID
PID_MODE_SIGNED_ADD_MULTIPLY_WITH_ACCUMULATION
PID_MODE_SIGNED_ADD_MULTIPLY
PID_MODE_UNSIGNED_ADD_MULTIPLY_WITH_ACCUMULATION
PID_MODE_UNSIGNED_ADD_MULTIPLY
PID_OUTPUT_LEFT_JUSTIFIED
PID_OUTPUT_RIGHT_JUSTIFIED
```

K1 - optional parameter specifying the K1 coefficient, defaults to zero if not specified.

The K1 coefficient is used in the PID and ADD_MULTIPLY modes. When in PID mode the K1 coefficient can be calculated with the following formula:

$$K1 = Kp + Ki * T + Kd/T$$

When in one of the ADD_MULTIPLY modes K1 is the multiple value.

K2 - optional parameter specifying the K2 coefficient, defaults to zero if not specified. The K2 coefficient is used in the PID mode only and is calculated with the following formula:

$$K2 = -(Kp + 2Kd/T)$$

K3 - optional parameter specifying the K3 coefficient, defaults to zero if not specified. The K3 coefficient is used in the PID mode, only and is calculated with the following formula:

$$K3 = Kd/T$$

T - is the sampling period in the above formulas.

Returns:

Function:

Setup the Proportional Integral Derivative (PID) module, and to set the input coefficients (K1, K2 and K3).

Availability:

Devices with built in PID module

Requires:

Constants are defined in the device's .h file.

Examples:

```
setup_pid(PID_MODE_PID, 10, -3, 50);
```

See Also:

[pid_get_result\(\)](#), [pid_read\(\)](#), [pid_write\(\)](#), [pid_busy\(\)](#)

setup_pmp(option,address_mask)

Syntax:

```
setup_pmp(options,address_mask);
```

Parameters:

options - The mode of the Parallel Master Port that allows to set the Master Port mode, read-write strobe options and other functionality of the PMPort module. See the device's .h file for all options. Some typical options include:

PAR_PSP_AUTO_INC

```

PAR_CONTINUE_IN_IDLE
PAR_INTR_ON_RW           // Interrupt on read write
PAR_INC_ADDR             // Increment address by 1 every read/write
cycle
PAR_MASTER_MODE_1       // Master Mode 1
PAR_WAITE4               // 4 Tcy Wait for data hold after strobe

```

address_mask - this allows the user to setup the address enable register with a 16-bit value. This value determines which address lines are active from the available 16 address lines PMA0:PMA15.

Returns:

Function:

Configures various options in the PMP module. The options are present in the device's .h file and they are used to setup the module. The PMP module is highly configurable and this function allows users to setup configurations like the Slave module, Interrupt options, address increment/decrement options, Address enable bits, and various strobe and delay options.

Availability:

Devices with built in Parallel Master Port module.

Requires:

Constants are defined in the device's .h file.

Examples:

```

setup_psp(PAR_ENABLE |           //Sets up Master mode with address
PAR_MASTER_MODE_1 | PAR_       //lines PMA0:PMA7
STOP_IN_IDLE, 0x00FF);

```

See Also:

setup_pmp(), pmp_address(), pmp_read(), psp_read(), psp_write(), pmp_write(), psp_output_full(), psp_input_full(), psp_overflow(), pmp_output_full(), pmp_input_full(), pmp_overflow()

setup_power_pwm()

Syntax:

setup_power_pwm(*modes*, *postscale*, *time_base*, *period*, *compare*, *compare_postscale*, *dead_time*)

Parameters:

modes - values may be up to one from each group of the following:

PWM_CLOCK_DIV_4, PWM_CLOCK_DIV_16,
PWM_CLOCK_DIV_64, PWM_CLOCK_DIV_128

PWM_DISABLED, PWM_FREE_RUN, PWM_SINGLE_SHOT,
PWM_UP_DOWN, PWM_UP_DOWN_INT

PWM_OVERRIDE_SYNC

PWM_UP_TRIGGER,

PWM_DOWN_TRIGGER
PWM_UPDATE_DISABLE, PWM_UPDATE_ENABLE

PWM_DEAD_CLOCK_DIV_2,
PWM_DEAD_CLOCK_DIV_4,
PWM_DEAD_CLOCK_DIV_8,
PWM_DEAD_CLOCK_DIV_16

postscale - is an integer between 1 and 16. This value sets the PWM time base output postscale.

time_base - is an integer between 0 and 65535. This is the initial value of the PWM base

period - is an integer between 0 and 4095. The PWM time base is incremented until it reaches this number.

compare - is an integer between 0 and 255. This is the value that the PWM time base is compared to, to determine if a special event should be triggered.

compare_postsacle - is an integer between 1 and 16. This postscaler affects compare, the special events trigger.

dead_time - is an integer between 0 and 63. This value specifies the length of an off period that should be inserted between the going off of a pin and the going on of it is a complementary pin.

Returns:

Function:

Initializes and configures the motor control Pulse Width Modulation (PWM) module.

Availability:

Devices with motor control or power PWM module.

Requires:

Examples:

```
setup_power_pwm(PWM_CLOCK_DIV_4|PWM_FREE_RUN|PWM_DEAD_CLOCK_DIV_4,1,100  
00,1000,0,1,0);
```

See Also:

[set_power_pwm_override\(\)](#), [setup_power_pwm_pins\(\)](#), [set_power_pwmX_duty\(\)](#)

setup_power_pwm_faults()**Syntax:**

setup_power_pwm_faults(*mode*);

Parameters:

mode - to setup the Power PWM faults. Valid options vary by device. See the device's header file for all options.

Returns:

Function:

Used to setup the power PWM faults for the Power Control PWM module.

Availability:

Devices with a Power Control PWM module.

Requires:

Examples:

```
setup_power_pwm_faults(PWM_ENABLE_FLTA | PWM_AUTO_CLEAR_FLTA);
```

See Also:

[set_power_pwm_override\(\)](#), [setup_power_pwm_pins\(\)](#), [set_power_pwmX_duty\(\)](#),
[setup_power_pwm\(\)](#)

setup_power_pwm_pins()**Syntax:**

setup_power_pwm_pins(**module0,module1,module2,module3**)

Parameters:

For each module (two pins) specify:

PWM_PINS_DISABLED

PWM_ODD_ON

PWM_BOTH_ON'PWM_COMPLEMENTARY

Returns:

Function:

Configures the pins of the Pulse Width Modulation (PWM) device.

Availability:

Devices with motor control or power PWM module.

Requires:

Examples:

```
setup_power_pwm_pins(PWM_PINS_DISABLED, PWM_PINS_DISABLED,
PWM_PINS_DISABLED,
    PWM_PINS_DISABLED);
setup_power_pwm_pins(PWM_COMPLEMENTARY,
    PWM_COMPLEMENTARY, PWM_PINS_DISABLED, PWM_PINS_DISABLED);
```

See Also:

setup_power_pwm(), set_power_pwm_override(),set_power_pwmX_duty()

setup_prqx()**Syntax:**

setup_prq1(**mode, current, rising_source, falling_source**);

setup_prq2(**mode, current, rising_source, falling_source**);

setup_prq3(**mode, current, rising_source, falling_source**);

setup_prq4(**mode, current, rising_source, falling_source**);

Parameters:

mode - the mode to setup the PRGx module in. The valid options vary depending on the device. See the device's header file for all options.

current - the current source/sink setting to set the PRGx module to and can be a value from 0 to 31. When using a value from 0 to 15, the current is calculated as: $2 + (\text{current} / 2)$ uA. When using a value from 16 to 31, the current is calculated as: $10 + (\text{current} - 16)$ uA.

rising_source - used to set the rising timing source. The valid options vary depending on the device. See the device's header file for all options.

falling_source - used to set the falling timing source. The valid options vary depending on the device. See the device's header file for all options.

Returns:

Function:

Used to set the PRGx modules.

Availability:

Devices that have a Programmable Ramp Generator (PRG) module.

Requires:

Examples:

```
setup_prg1(PRG_ENABLED | PRG_INPUT_SOURCD_FVR, 16,
PRG_RISING_SOURCE_CCP1, PRG_RISING_SOURCE_CCP2);
```

See Also:

[prgx_status\(\)](#)

setup_psmc()**Syntax:**

```
setup_psmc(unit, mode, period, period_time, rising_edge, rise_time, falling_edge, fall_time);
```

Parameters:

unit - is the PSMC unit number 1-4

mode - is one of:

- PSMC_SINGLE
- PSMC_PUSH_PULL
- PSMC_BRIDGE_PUSH_PULL
- PSMC_PULSE_SKIPPING
- PSMC_ECCP_BRIDGE_REVERSE
- PSMC_ECCP_BRIDGE_FORWARD
- PSMC_VARIABLE_FREQ
- PSMC_3_PHASE

For complementary outputs use a bar (!) and or in **PSMC_COMPLEMENTARY**

Normally the module is not started until the **psmc_pins()** call is made. To enable immediately or in **PSMC_ENABLE_NOW**.

period - has three parts or'ed together. The clock source, the clock divisor and the events that can cause the period to start.

Sources:

- PSMC_SOURCE_FOSC
- PSMC_SOURCE_64MHZ
- PSMC_SOURCE_CLK_PIN

Divisors:

- PSMC_DIV_1
- PSMC_DIV_2
- PSMC_DIV_4
- PSMC_DIV_8

Events - Use any of the events listed below.

period_time - is the duration the period lasts in ticks. A tick is the above clock source divided by the divisor.

rising_edge - is any of the following events to trigger when the signal goes active.

rise_time - is the time in ticks that the signal goes active (after the start of the period) if the event is SMC_EVENT_TIME, otherwise unused.

falling_edge - is any of the following events to trigger when the signal goes inactive.

fall_time - is the time in ticks that the signal goes inactive (after the start of the period) if the event is PSMC_EVENT_TIME, otherwise unused.

Events:

- PSMC_EVENT_TIME

```
PSMC_EVENT_C1OUT
PSMC_EVENT_C2OUT
PSMC_EVENT_C3OUT
PSMC_EVENT_C4OUT
PSMC_EVENT_PIN_PIN
```

Returns:

Function:

Initializes a PSMC unit with the primary characteristics such as the type of PWM, the period, duty and various advanced triggers. Normally this call does not start the PSMC.

It is expected all the setup functions be called and the `psmc_pins()` be called last to start the PSMC module. These two calls are all that are required for a simple PWM. The other functions may be used for advanced settings and to dynamically change the signal.

Availability:

Devices with built in PSMC module.

Requires:

Examples:

```
//Simple PWM, 10khz out on pin C0 assuming a 20mhz crystal
// Duty is initially set to 25%

setup_psmc(1, PSMC_SINGLE, PSMC_EVENT_TIME | PSMC_SOURCE_FOSC, 100,
           PSMC_EVENT_TIME, 0, PSMC_EVENT_TIME, 25);
psmc_pins(1, PSMC_A);
```

See Also:

[psmc_deadband\(\)](#), [psmc_sync\(\)](#), [psmc_blanking\(\)](#), [psmc_modulation\(\)](#),
[psmc_shutdown\(\)](#), [psmc_duty\(\)](#), [psmc_freq_adjust\(\)](#), [psmc_pins\(\)](#)

setup_psp(option,address mask)

Syntax:

```
setup_psp (options,address_mask);
setup_psp(options);
```

Parameters:

Option - The mode of the Parallel slave port. This allows to set the slave port mode, read-write strobe options and other functionality of the PMP/EPMP module. See the devices .h file for all options. Some typical options include:

```
PAR_PSP_AUTO_INC
PAR_CONTINUE_IN_IDLE
PAR_INTR_ON_RW           // Interrupt on read write
PAR_INC_ADDR             // Increment address by 1 every read/write
cycle
PAR_WAITE4               // 4 Tcy Wait for data hold after strobe
```

address_mask - This allows the user to setup the address enable register with a 16 bit or 32 bit (EPMP) value. This value determines which address lines are active from the available 16 address lines PMA0: PMA15 or 32 address lines PMA0:PMA31 (EPMP only)

Returns:

Function:

Configures various options in the PMP/EPMP module. The options are present in the device.h file and they are used to setup the module. The PMP/EPMP module is highly configurable and this function allows users to setup configurations like the Slave mode, Interrupt options, address increment/decrement options, Address enable bits and various strobe and delay options.

Availability:

Devices with Parallel Port module or Enhanced Parallel Master Port module.

Requires:

Constants are defined in the devices .h file.

Examples:

```
setup_psp(PAR_PSP_AUTO_INC|           //Sets up legacy slave mode with
PAR_STOP_IN_IDLE,0x00FF );           //read and write buffers auto
increment
```

See Also:

psp_output_full(), psp_input_full(), psp_overflow(),
[PCD] setup_pmp(), pmp_address(), pmp_read(), psp_read(), psp_write(), pmp_write(),
pmp_output_full(), pmp_input_full(), pmp_overflow()

setup_pwm1() setup_pwm2() setup_pwm3() setup_pwm4()**Syntax:**

```
setup_pwm1(settings);
setup_pwm2(settings);
setup_pwm3(settings);
setup_pwm4(settings);
```

Parameters:

settings- setup of the PWM module. See the device's .h file for all options. Some typical options include:

```
PWM_ENABLED
PWM_OUTPUT
PWM_ACTIVE_LOW
```

Returns:

```
-----
```

Function:

Initializes the Pulse Width Modulation (PWM) device.

Availability:

Devices with PWM module.

Requires:

```
-----
```

Examples:

```
setup_pwm1(PWM_ENABLED|PWM_OUTPUT);
```

setup_qei()**Syntax:**

```
setup_qei( options, filter, maxcount );
[PCD] setup_qei( [unit,]options, filter, maxcount );
```

Parameters:

Options - The mode of the QEI module. See the devices .h file for all options. Some common options are:

```
QEI_MODE_X2
QEI_MODE_X4
```

filter - This parameter is optional, the user can enable the digital filters and specify the clock divisor.

maxcount - Specifies the value at which to reset the position counter.

[PCD] Options- The mode of the QEI module. See the devices .h file for all options. Some common options are:

```
QEI_MODE_X2
QEI_TIMER_GATED
QEI_TIMER_DIV_BY_1
```

[PCD] filter - This parameter is optional and the user can specify the digital filter clock divisor.

[PCD] maxcount - This will specify the value at which to reset the position counter.

[PCD] unit - Optional unit number, defaults to 1.

Returns:

Function:

Configures the Quadrature Encoder Interface. Various settings like mode and filters can be setup.

Availability:

Devices with QEI module.

Requires:

Examples:

```
setup_qei(QEI_MODE_X2|QEI_RESET_WHEN_MAXCOUNT,
EI_FILTER_ENABLE_QEA|QEI_FILTER_DIV_2,0x1000);
```

```
[PCD]
setup_qei(QEI_MODE_X2|QEI_TIMER_INTERNAL,QEI_FILTER_DIV_2,QEI_FORWARD)
;
```

See Also:

gei_set_count() , gei_get_count() , gei_status()

setup_rtc()

Syntax:

```
setup_rtc(options, calibration);
```

[PCD] `setup_rtc(options, period, stability_time, sample_time);` //RTCC with Timestamp

Parameters:

Options- The mode of the RTCC module. See the devices .h file for all options

Calibration- This parameter is optional and the user can specify an 8 bit value that will get written to the calibration configuration register.

[PCD] Period - RTCC with Timestamp, sets the period of the clock divider counter. Value should be set to achieve a period of 0.5 seconds.

[PCD] Stability_time - RTCC with Timestamp, sets the Power Control Stability Time (2-255). This parameter is optional.

[PCD] Sample_time - RTCC with Timestamp, sets the Power Control Sample Time Window (2-255). This parameter is optional.

Returns:

Function:

Configures the Real Time Clock and Calendar module. The module requires an external 32.768 kHz clock crystal for operation.

Availability:

Devices with RTCC module.

Requires:

Examples:

```
setup_rtc(RTC_ENABLE | RTC_OUTPUT_SECONDS, 0x00);
           // Enable RTCC module with seconds clock and no
calibration

[PCD] setup_rtc(RTC_ENABLE|RTC_CLOCK_SOSC, 16383);
           // Enable RTCC with Timestamp module from an external
32.768Khz crystal
```

See Also:

[rtc_read\(\)](#), [rtc_alarm_read\(\)](#), [rtc_alarm_write\(\)](#), [setup_rtc_alarm\(\)](#), [rtc_write\(\)](#), [setup_rtc\(\)](#)

setup_rtc_alarm()

Syntax:

`setup_rtc_alarm(options, mask, repeat);`

Parameters:

options - The mode of the RTCC module. See the devices .h file for all options

mask - specifies the alarm mask bits for the alarm configuration.

repeat - Specifies the number of times the alarm will repeat. It can have a max value of 255.

Returns:

Function:

Configures the alarm of the RTCC module.

Availability:

Devices with RTCC module.

Requires:

Examples:

```
setup_rtc_alarm(RTC_ALARM_ENABLE, RTC_ALARM_HOUR, 3);
```

See Also:

[rtc_read\(\)](#), [rtc_alarm_read\(\)](#), [rtc_alarm_write\(\)](#), [setup_rtc_alarm\(\)](#), [rtc_write\(\)](#), [setup_rtc\(\)](#)

setup_sd_adc()

Syntax:

`setup_sd_adc(settings1, settings 2, settings3);`

Parameters:

settings1 - settings for the SD1CON1 register of the SD ADC module. See the device's .h file for all options. Some options include:

- 1 SDADC_ENABLED
- 2 SDADC_NO_HALT
- 3 SDADC_GAIN_1
- 4 SDADC_NO_DITHER

- 5 SDADC_SVDD_SVSS
- 6 SDADC_BW_NORMAL

settings2 - settings for the SD1CON2 register of the SD ADC module. See the device's .h file for all options. Some options include:

- 7 SDADC_CHOPPING_ENABLED
- 8 SDADC_INT_EVERY_SAMPLE
- 9 SDADC_RES_UPDATED_EVERY_INT
- 10 SDADC_NO_ROUNDING

settings3 - settings for the SD1CON3 register of the SD ADC module. See the device's .h file for all options. Some options include:

- 11 SDADC_CLOCK_DIV_1
- 12 SDADC_OSR_1024
- 13 SDADC_CLK_SYSTEM

Returns:

Function:

Setup the Sigma-Delta Analog to Digital Converter (SD ADC) module.

Availability:

Devices with SD ADC module.

Requires:

Examples:

```
setup_sd_adc(SDADC_ENABLED | SDADC_DITHER_LOW, SDADC_CHOPPING_ENABLED |
             SDADC_INT_EVERY_5TH_SAMPLE | SDADC_RES_UPDATED_EVERY_INT,
             SDADC_CLK_SYSTEM | SDADC_CLOCK_DIV_4);
```

See Also:

set_sd_adc_channel(), read_sd_adc(), set_sd_adc_calibration()

[PCD] setup_sent()

Syntax:

```
setup_sent(module, settings, tick_time);
setup_sent(module, settings, tick_time, [frame_time]);
```

Parameters:

module - the SENT peripheral to setup, 1 or 2 for most devices.

settings - the mode to setup the SENT peripheral in. Constants for setting up the peripheral are defined in the device's header file. See the device's header file for all the possible options.

tick_time - the tick time to set the SENT peripheral to, value is a time in *us* from 3 to 90.

fame_time - optional parameter unless peripheral is set-up for transmitter mode and ***sent_uses_pause_pulse*** is used in settings parameter. It is used to set the frame time in *us* of the message.

Returns:

Function:

Used to setup the Single-Edge Nibble Transmission (SENT) peripheral.

Availability:

Devices with a SENT peripheral.

Requires:

Examples:

```
//Setup SENT1 peripheral for asynchronous transmitter
//mode with HW CRC generation enabled, pause pulse
//enabled, and to send 6 data nibbles with a tick time
//90us and a frame time of 50ms.
setup_sent(1, SENT_MODE_TRANSMITTER_ASYNCHRONOUS | SENT_ENABLE_HW_CRC |
SENT_USES_PAUSE_PULSE | SENT_DATA_NIBBLES_6, 90, 50000);
```

Example Files:

ex_sent_transmitter.c, ex_sent_receiver.c

See Also:

sent_getd(), sent_putd(), sent_status()

setup_smtx()

Syntax:

setup_smtx1(mode,[period]);

```
setup_smt2(mode,[period]);
```

Parameters:

mode - The setup of the SMT module. See the device's .h file for all options. Some typical options include:

```
SMT_ENABLED
SMT_MODE_TIMER
SMT_MODE_GATED_TIMER
SMT_MODE_PERIOD_DUTY_CYCLE_ACQ
```

period - Optional parameter for specifying the overflow value of the SMT timer, defaults to maximum value if not specified.

Returns:

Function:

Configures the Signal Measurement Timer (SMT) module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
setup_smt1(SMT_ENABLED | SMT_MODE_PERIOD_DUTY_CYCLE_ACQ |
           SMT_REPEAT_DATA_ACQ_MODE | SMT_CLK_FOSC);
```

See Also:

[smtx_status\(\)](#), [smtx_start\(\)](#), [smtx_stop\(\)](#), [smtx_update\(\)](#), [smtx_reset_timer\(\)](#), [smtx_read\(\)](#), [smtx_write\(\)](#)

setup_spi() setup_spi2() setup_spi3() setup_spi4()

Syntax:

```
setup_spi(mode)
setup_spi2(mode)
setup_spi3(mode)
setup_spi4(mode)
```

Parameters:

mode may be:

```
SPI_MASTER, SPI_SLAVE, SPI_SS_DISABLED
```

```
SPI_L_TO_H, SPI_H_TO_L
SPI_CLK_DIV_4, SPI_CLK_DIV_16,
SPI_CLK_DIV_64, SPI_CLK_T2
SPI_SAMPLE_AT_END, SPI_XMIT_L_TO_H
[PCD] SPI_MODE_16B, SPI_XMIT_L_TO_H
```

Constants from each group may be or'ed together with |

Returns:

Function:

Initializes the Serial Port Interface (SPI). This is used for 2 or 3 wire serial devices that follow a common clock/data protocol.

[PCD] Configures the hardware SPI™ module.

SPI_MASTER will configure the module as the bus master

SPI_SLAVE will configure the module as a slave on the SPI™ bus

SPI_SS_DISABLED will turn off the slave select pin so the slave module receives any transmission on the bus.

SPI_x_to_y will specify the clock edge on which to sample and transmit data

SPI_CLK_DIV_x will specify the divisor used to create the SCK clock from system clock.

Availability:

Devices with SPI hardware module.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_spi(spi_master | spi_l_to_h | spi_clk_div_16 );
setup_spi(SPI_MASTER | SPI_L_TO_H | SPI_DIV_BY_16);
```

Example Files:

[ex_spi.c](#)

See Also:

[spi_write\(\)](#), [spi_read\(\)](#), [spi_data_is_in\(\)](#), [spi_set_txcnt\(\)](#), [SPI Overview](#)

setup_timerx()

Syntax:

setup_timerX(*mode*)

setup_timerX(*mode*,*period*)

Parameters:

mode - is a bit-field comprised of the following configuration constants:

TMR_DISABLED: Disables the timer operation.

TMR_INTERNAL: Enables the timer operation using the system clock. Without divisions, the timer will increment on every instruction cycle. On PCD, this is half the oscillator frequency.

TMR_EXTERNAL: Uses a clock source that is connected to the SOSC/SOSCO pins

TMR_EXTERNAL_SYNC: Uses a clock source that is connected to the SOSC/SOSCO pins. The timer will increment on the rising edge of the external clock which is synchronized to the internal clock phases. This mode is available only for Timer1.

TMR_EXTERNAL_RTC: Uses a low power clock source connected to the SOSC/SOSCO pins; suitable for use as a real time clock. If this mode is used, the low power oscillator will be enabled by the setup_timer function. This mode is available only for Timer1.

TMR_DIV_BY_X: X is the number of input clock cycles to pass before the timer is incremented. X may be 1, 8, 64 or 256.

TMR_32_BIT: This configuration concatenates the timers into 32 bit mode. This constant should be used with timers 2, 4, 6 and 8 only.

Period is an optional 16 bit integer parameter that specifies the timer period. The default value is 0xFFFF.

Returns:

Function:

Sets up the timer specified by X (May be 1 – 9). X must be a valid timer on the target device.

Availability:

This function is available on all devices that have a valid timer X. Use getenv or refer to the target datasheet to determine which timers are valid.

Requires:

Constants are defined in the device's .h file

Examples:

```
/* setup a timer that increments every 64th instruction cycle with an
overflow period of 0xA010 */

setup_timer2(TMR_INTERNAL | TMR_DIV_BY_64, 0xA010);

/* Setup another timer as a 32-bit hybrid with a period of 0xFFFFFFFF
and a interrupt that will be fired when that timer overflows*/

setup_timer4(TMR_32_BIT);           //use get_timer45() to get the
timer value
enable_interrupts(int_timer5);      //use the odd number timer for
the interrupt
```

See Also:

[Timer Overview](#), [setup_timerX\(\)](#), [get_timerXY\(\)](#), [set_timerX\(\)](#), [set_timerXY\(\)](#)

setup_timerA()

Syntax:

setup_timer_A (mode);

Parameters:

mode values may be:

TA_OFF, TA_INTERNAL, TA_EXT_H_TO_L, TA_EXT_L_TO_H
 TA_DIV_1, TA_DIV_2, TA_DIV_4, TA_DIV_8, TA_DIV_16, TA_DIV_32,
 TA_DIV_64, TA_DIV_128, TA_DIV_256

Constants from different groups may be or'ed together with |.

Returns:

Function:

Sets up Timer A.

Availability:

This function is only available on devices with Timer A hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_A(TA_OFF);
```

```
setup_timer_A(TA_INTERNAL | TA_DIV_256);
setup_timer_A(TA_EXT_L_TO_H | TA_DIV_1);
```

See Also:

get_timerA(), set_timerA(), TimerA Overview

setup_timerB()

Syntax:

```
setup_timer_B (mode);
```

Parameters:

mode values may be:

```
TB_OFF, TB_INTERNAL, TB_EXT_H_TO_L, TB_EXT_L_TO_H
TB_DIV_1, TB_DIV_2, TB_DIV_4, TB_DIV_8, TB_DIV_16, TB_DIV_32,
TB_DIV_64, TB_DIV_128, TB_DIV_256
```

Constants from different groups may be or'ed together with |.

Returns:

Function:

Sets up Timer B.

Availability:

This function is only available on devices with Timer B hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_B(TB_OFF);
setup_timer_B(TB_INTERNAL | TB_DIV_256);
setup_timer_B(TA_EXT_L_TO_H | TB_DIV_1);
```

See Also:

get_timerB(), set_timerB(), TimerB Overview

setup_timer0()

Syntax:

```
setup_timer_0 (mode);
```


Parameters:

mode - constants defined in the device's .h file. Some typical defines are:

```
TO_INTERNAL
TO_EXT_L_TO_H
TO_EXT_H_TO_I
TO_DIV_2, TO_DIV_4
```

(See device's .h file for all possible defines.)

One constant may be used from each group or'ed together with the | operator.

Returns:

Function:

Sets up the timer 0 (aka RTCC).

Availability:

All Devices. (**WARNING:** On older PIC16 devices, set-up of the prescaler may undo the WDT prescaler)

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_0 (TO_INTERNAL|TO_DIV2);
```

See Also:

[get_timer0\(\)](#), [set_timer0\(\)](#), [setup_counters\(\)](#)

setup_timer1()

Syntax:

```
setup_timer_1 (mode);
```

Parameters:

mode

```
T1_DISABLED, T1_INTERNAL, T1_EXTERNAL, T1_EXTERNAL_SYNC
T1_CLK_OUT
T1_DIV_BY_1, T1_DIV_BY_2, T1_DIV_BY_4, T1_DIV_BY_8
```

One constant may be used from each group or'ed together with the | operator.

Returns:

Function:

Initializes timer 1. The timer value may be read and written to using SET_TIMER1() and GET_TIMER1(). Timer 1 is a 16 bit timer.

With an internal clock at 20mhz and with the T1_DIV_BY_8 mode, the timer will increment every 1.6us. It will overflow every 104.8576ms.

Availability:

Available only on devices with timer 1 hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_1 ( T1_DISABLED );
setup_timer_1 ( T1_INTERNAL | T1_DIV_BY_4 );
setup_timer_1 ( T1_INTERNAL | T1_DIV_BY_8 );
```

See Also:

[get_timer1\(\)](#), [set_timer1\(\)](#) , [Timer1 Overview](#)

setup_timer2()

Syntax:

setup_timer_2 (*mode*, *period*, *postscale*);

Parameters:

mode

T2_DISABLED
T2_DIV_BY_1, T2_DIV_BY_4, T2_DIV_BY_16

period - is a int 0-255 that determines when the clock value is reset

postscale - is a number 1-16 that determines how many timer overflows before an interrupt: (1 means once, 2 means twice, an so on).

Returns:

Function:

Initializes timer 2. The mode specifies the clock divisor (from the oscillator clock). The timer value may be read and written to using GET_TIMER2() and SET_TIMER2(). 2 is a 8-bit counter/timer.

Availability:

Available only on devices with timer 2 hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_2 ( T2_DIV_BY_4, 0xc0, 2)    //at 20mhz, the timer will
increment                                //every 800ns will overflow
every 154.4us,                            //and will interrupt every
308.us
```

See Also:

[get_timer2\(\)](#), [set_timer2\(\)](#) , [Timer2 Overview](#)

setup_timer3()

Syntax:

setup_timer_3 (*mode*);

Parameters:

mode - may be one of the following constants from each group or'ed (via |) together:

T3_DISABLED, T3_INTERNAL, T3_EXTERNAL, T3_EXTERNAL_SYNC
T3_DIV_BY_1, T3_DIV_BY_2, T3_DIV_BY_4, T3_DIV_BY_8

Returns:

Function:

Initializes timer 3 or 4. The mode specifies the clock divisor (from the oscillator clock). The timer value may be read and written to using GET_TIMER3() and SET_TIMER3(). Timer 3 is a 16 bit counter/timer.

Availability:

Available only on devices with timer 3 hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_3 (T3_INTERNAL | T3_DIV_BY_2);
```

See Also:

get_timer3(), set_timer3()

setup_timer4()**Syntax:**

```
setup_timer_4 (mode);
```

Parameters:

mode - may be one of:

T4_DISABLED, T4_DIV_BY_1, T4_DIV_BY_4, T4_DIV_BY_16

period - is a int 0-255 that determines when the clock value is reset

postscale - is a number 1-16 that determines how many timer overflows before an interrupt: (1 means once, 2 means twice, and so on).

Returns:

Function:

Initializes timer 4. The mode specifies the clock divisor (from the oscillator clock). The timer value may be read and written to using GET_TIMER4() and SET_TIMER4(). Timer 4 is a 8 bit counter/timer.

Availability:

Available only on devices with timer 4 hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_4 ( T4_DIV_BY_4, 0xc0, 2);    // At 20mhz, the timer will
increment                                     // every 800ns,will overflow
every 153.6us,
```

```
307.2us // and will interrupt every
```

See Also:

get_timer4(), set_timer4()

setup_timer5()

Syntax:

setup_timer_5 (*mode*);

Parameters:

mode - may be one or two of the constants defined in the devices .h file.

T5_DISABLED, T5_INTERNAL, T5_EXTERNAL, or T5_EXTERNAL_SYNC
T5_DIV_BY_1, T5_DIV_BY_2, T5_DIV_BY_4, T5_DIV_BY_8
T5_ONE_SHOT, T5_DISABLE_SE_RESET, or T5_ENABLE_DURING_SLEEP

Returns:

Function:

Initializes timer 5. The mode specifies the clock divisor (from the oscillator clock). The timer value may be read and written to using GET_TIMER5() and SET_TIMER5(). Timer 5 is a 16 bit counter/timer.

Availability:

Available only on devices with timer 5 hardware.

Requires:

Constants are defined in the device's .h file

Examples:

```
setup_timer_5 (T5_INTERNAL | T5_DIV_BY_2);
```

See Also:

get_timer5(), set_timer5(), Timer5 Overview

setup_uart()

Syntax:

setup_uart(*baud*, *stream*)
setup_uart(*baud*)

setup_uart(***baud, stream, clock***)

Parameters:

baud - is a constant representing the number of bits per second. A one or zero may also be passed to control the on/off status.

Stream - is an optional stream identifier.

Chips with the advanced UART may also use the following constants:

UART_ADDRESS UART only accepts data with 9th bit=1

UART_DATA UART accepts all data

Chips with the EUART H/W may use the following constants:

UART_AUTODETECT Waits for 0x55 character and sets the UART baud rate to match.

UART_AUTODETECT_NOWAIT Same as above function, except returns before 0x55 is received. KBHIT() will be true when the match is made. A call to GETC() will clear the character.

UART_WAKEUP_ON_RDA Wakes PIC up out of sleep when RCV goes from high to low

clock - If specified this is the clock rate this function should assume. The default comes from the #USE DELAY.

Returns:

Function:

Similar to SET_UART_SPEED. If 1 is passed as a parameter, the UART is turned on, and if 0 is passed, UART is turned off. If a BAUD rate is passed to it, the UART is also turned on, if not already on.

Availability:

Available only on devices with built in UART.

Requires:

#USE RS232

Examples:

```
setup_uart(9600);
setup_uart(9600, rsOut);
```

See Also:

#USE RS232, [putc\(\)](#), [getc\(\)](#), [RS232 I/O Overview](#)

setup_vref() setup_vref2()

Syntax:

setup_vref (*mode* | *value*)

Parameters:

mode - may be one of the following constants:

FALSE	(off)
VREF_LOW	for $VDD * VALUE / 24$
VREF_HIGH	for $VDD * VALUE / 32 + VDD / 4$

any may be or'ed with VREF_A2.

value - is an int 0-15.

[PCD] **mode** - is a bit-field comprised of the following constants:

VREF_DISABLED
VREF_LOW ($Vdd * value / 24$)
VREF_HIGH ($Vdd * value / 32 + Vdd / 4$)
VREF_ANALOG

Returns:

Function:

Establishes the voltage of the internal reference that may be used for analog compares and/or for output on pin A2.

[PCD] Configures the voltage reference circuit used by the voltage comparator.

The voltage reference circuit allows you to specify a reference voltage that the comparator module may use. You may use the Vdd and Vss voltages as your reference or you may specify VREF_ANALOG to use supplied Vdd and Vss. Voltages may also be tuned to specific values in steps, 0 through 15. That value must be or'ed to the configuration constants.

Availability:

This function is only available on devices with VREF hardware.

[PCD] Some devices, consult the device datasheet.

Requires:

[PCD] Constants are defined in the devices .h file

Examples:

```
setup_vref (VREF_HIGH | 6);
// At VDD=5, the voltage is 2.19V
```

```
[PCD] /* Use the 15th step on the course setting */
setup_vref(VREF_LOW | 14);
```

Example Files:

ex_comp.c

See Also:

Voltage Reference Overview

setup_wdt()

Syntax:

setup_wdt (*mode*)

Parameters:

Constants:

```
WDT_18MS
WDT_36MS
WDT_72MS
WDT_144MS
WDT_288MS
WDT_576MS
WDT_1152MS
WDT_2304MS
```

For some parts:

```
WDT_ON
WDT_OFF
```

[PCD] Mode is a bit-field comprised of the following constants:

```
WDT_ON
WDT_OFF
```

Specific Time Options vary between chips, some examples are:

```
WDT_2ms
WDT_64MS
WDT_1S
WDT_16S
```

Returns:

Function:

Setup-wdt is used to set the timer that is allowed between calls to restart-wdt () before the chip is reset. Some parts also allow the wdt to be enabled/disabled and to run time by this function. Some parts do not allow the time to be changed at run time. The watchdog timer is used to cause a hardware reset if the software appears to be stuck.

The timer must be enabled, the timeout time set and software must periodically restart the timer.

Note: For PCH parts and PCM parts with software controlled WDT, setup_wdt() would enable/disable watchdog timer only if NOWDT fuse is set. If WDT fuse is set, watchdog timer is always enabled.

Note: WDT_OFF should not be used with any other options.

Warning: Some chips share the same prescaler between the WDT and Timer0. In these cases a call to setup_wdt may disable the Timer0 prescaler.

[PCD] Configures the watchdog timer. The watchdog timer is used to monitor the software. If the software does not reset the watchdog timer before it overflows, the device is reset, preventing the device from hanging until a manual reset is initiated. The watchdog timer is derived from the slow internal timer.

Availability:

All Devices (**WARNING:** On older PIC16 devices, set-up of the prescaler may undo the timer0 prescaler)

Requires:

Constants are defined in the devices .h file

Examples:

```
#fuses WDT1, WDT // PIC18 example, See restart_wdt for a
PIC18 example
main() {
    setup_wdt( WDT_18MS);
    while (TRUE) {
        restart_wdt();
        perform_activity();
    }
}
```

[PCD] setup_wdt(WDT_ON);

Example Files:

[\[PCD\] ex_wdt.c](#)

See Also:

[#FUSES](#) , [restart_wdt\(\)](#) , [WDT or Watch Dog Timer Overview](#) , Internal Oscillator Overview

setup_zcd()

Syntax:

setup_zcd(mode);

Parameters:

mode- the setup of the ZCD module. The options for setting up the module include:

ZCD_ENABLED
ZCD_DISABLED
ZCD_INVERTED
ZCD_INT_L_TO_H
ZCD_INT_H_TO_L

Returns:

Function:

Set-up the Zero_Cross Detection (ZCD) module.

Availability:

Devices with a ZCD module.

Requires:

Examples:

```
setup_zcd(ZCD_ENABLE | ZCD_INT_H_TO_L);
```

See Also:

[zcd_status\(\)](#)

shift_left()

Syntax:

`shift_left (address, bytes, value)`

Parameters:

address - is a pointer to memory.

bytes - is a count of the number of bytes to work with

value - is a 0 to 1 to be shifted in.

Returns:

0 or 1 for the bit shifted out

Function:

Shifts a bit into an array or structure. The address may be an array identifier or an address to a structure (such as &data). Bit 0 of the lowest byte in RAM is treated as the LSB.

Availability:

All Devices.

Requires:

Examples:

```

byte buffer[3];
for(i=0; i<=24; ++i){
    while (!input(PIN_A2));           // Wait for clock high
    shift_left(buffer,3,input(PIN_A3)); // Wait for clock low
    while (input(PIN_A2));
}                                     // reads 24 bits from pin
A3,each bit                          //is read on a low to high on
pin A2

```

Example Files:

[ex_extee.c](#), [9356.c](#)

See Also:

[shift_right\(\)](#), [rotate_right\(\)](#), [rotate_left\(\)](#)

shift_right()

Syntax:

shift_right (*address*, *bytes*, *value*)

Parameters:

address - is a pointer to memory.

bytes - is a count of the number of bytes to work with

value - is a 0 to 1 to be shifted in.

Returns:

0 or 1 for the bit shifted out

Function:

Shifts a bit into an array or structure. The address may be an array identifier or an address to a structure (such as &data). Bit 0 of the lowest byte in RAM is treated as the LSB.

Availability:

All Devices.

Requires:

Examples:

```

//reads 16 bits from pin A1,
each bit is read
// on a low to high on pin A2

struct {
    byte time;
    byte command : 4;
    byte source  : 4;} msg;

for(i=0; i<=16; ++i) {
    while(!input(PIN_A2));
    shift_right(&msg,3,input(PIN_A1));
    while (input(PIN_A2)) ;} // This shifts 8 bits out PIN_A0,
LSB first.
for(i=0;i<8;++i)
    output_bit(PIN_A0,shift_right(&data,1,0));

```

Example Files:

ex_extee.c, 9356.c

See Also:

shift_left(), rotate_right(), rotate_left()

sleep()

Syntax:

`sleep(mode)`

Parameters:

mode - for most chips this is not used. Check the device header for special options on some chips.

[PCD] **mode** configures what sleep mode to enter, mode is optional. If mode is SLEEP_IDLE, the PIC will stop executing code but the peripherals will still be operational. If mode is SLEEP_FULL, the PIC will stop executing code and the peripherals will stop being clocked, peripherals that do not need a clock or are using an external clock will still be operational. SLEEP_FULL will reduce power consumption the most. If no parameter is specified, SLEEP_FULL will be used.

Returns:

Function:

Issues a SLEEP instruction. Details are device dependent. However, in general the part will enter low power mode and halt program execution until woken by specific external events. Depending on the cause of the wake up execution may continue after the sleep instruction. The compiler inserts a sleep() after the last statement in main().

Availability:

All Devices.

Requires:

Examples:

```
SLEEP();
[PCD]
disable_interrupts(INT_GLOBAL);
enable_interrupt(INT_EXT);
clear_interrupt();
sleep(SLEEP_FULL);           //sleep until an INT_EXT interrupt
```

```
//after INT_EXT wake-up,  
//will resume operation from this point
```

Example Files:

ex_wakup.c

See Also:

reset_cpu()

sleep_ulpwu()

Syntax:

sleep_ulpwu(*time*)

Parameters:

time - specifies how long, in us, to charge the capacitor on the ultra-low power wakeup pin (by outputting a high on PIN_A0).

[PCD] time - specifies how long, in us, to charge the capacitor on the ultra-low power wakeup pin (by outputting a high on PIN_B0).

Returns:

Function:

Charges the ultra-low power wake-up capacitor on PIN_A0 for time microseconds, and then puts the PIC to sleep. The PIC will then wake-up on an 'Interrupt-on-Change' after the charge on the cap is lost.

[PCD] Charges the ultra-low power wake-up capacitor on PIN_B0 for time microseconds, and then puts the PIC to sleep. The PIC will then wake-up on an 'Interrupt-on-Change' after the charge on the cap is lost.

Availability:

Devices with Ultra Low Power Wake-Up.

Requires:

Examples:

```
while(TRUE)  
{  
    if (input(PIN_A1))        //PCD devices use (PIN_B0)
```

```

        //do something
    else
        sleep_ulpwu(10); //cap will be charged for 10us,
                        //then goto sleep
}

```

See Also:#USE DELAY**smtx_read()****Syntax:**

```

value_smt1_read(which);
value_smt2_read(which);

```

Parameters:

which - Specifies which SMT registers to read. The following defines have been made in the device's header file to select which registers are read:

```

SMT_CAPTURED_PERIOD_REG
SMT_CAPTURED_PULSE_WIDTH_REG
SMT_TMR_REG
SMT_PERIOD_REG

```

Returns:

32-bit value

Function:

Read the Capture Period Registers, Capture Pulse Width Registers, Timer Registers or Period Registers of the Signal Measurement Timer module.

Availability:

Devices with SMT module.

Requires:

Examples:

```

unsigned int32 Period;
Period = smt1_read(SMT_CAPTURED_PERIOD_REG);

```

See Also:

smtx_status(), smtx_start(), smtx_stop(), smtx_update(), smtx_reset_timer(), setup SMTx(), smtx_write()

smtx_reset_timer()

Syntax:

```
smt1_reset_timer();
smt2_reset_timer();
```

Parameters:

Returns:

Function:

Manually reset the Timer Register of the Signal Measurement Timer module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
smt1_reset_timer();
```

See Also:

setup_smtx(), smtx_start(), smtx_stop(), smtx_update(), smtx_status(), smtx_read(), smtx_write()

smtx_start()

Syntax:

```
smt1_start();
smt2_start();
```

Parameters:

Returns:

Function:

Allow the Signal Measurement Timer (SMT) module start acquiring data.

Availability:

Devices with SMT module.

Requires:

Examples:

```
smt1_start();
```

See Also:

smtx_status(), setup_smtx(), smtx_stop(), smtx_update(), smtx_reset_timer(),
smtx_read(), smtx_write()

smtx_status()**Syntax:**

```
value = smt1_status();
```

```
value = smt2_status();
```

Parameters:

Returns:

The status of the SMT module.

Function:

Return the status of the Signal Measurement Timer (SMT) module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
status = smt1_status();
```

See Also:

setup_smtx(), stmx_start(), smtx_stop(), smtx_update(),
smtx_reset_timer(), smtx_read(), smtx_write()

smtx_stop()

Syntax:

```
smt1_stop();
smt2_stop();
```

Parameters:

Returns:

Function:

Configures the Signal Measurement Timer (SMT) module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
smt1_stop();
```

See Also:

smtx_status(), smtx_start(), setup_smtx(), smtx_update(), smtx_reset_timer(),
smtx_read(), smtx_write()

smtx_write()

Syntax:

```
smt1_write(which,value);
smt2_write(which,value);
```

Parameters:

which - Specifies which SMT registers to write. The following defines have been made in the device's header file to select which registers are written:

```
SMT_TMR_REG
SMT_PERIOD_REG
```

value - The 24-bit value to set the specified registers.

Returns:

Function:

Write the Timer Registers or Period Registers of the Signal Measurement Timer (SMT) module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
smt1_write(SMT_PERIOD_REG, 0x100000000);
```

See Also:

smtx_status(), smtx_start(), setup smtx(), smtx_update(), smtx_reset_timer(), smtx_read(), setup smtx()

smtx_update()

Syntax:

```
smt1_update(which);  
smt2_update(which);
```

Parameters:

which - Specifies which capture registers to manually update. The following defines have been made in the device's header file to select which registers are updated:

```
SMT_CAPTURED_PERIOD_REG  
SMT_CAPTURED_PULSE_WIDTH_REG
```

Returns:

Function:

Manually update the Capture Period Registers or the Capture Pulse Width Registers of the Signal Measurement Timer module.

Availability:

Devices with SMT module.

Requires:

Examples:

```
smt1_update (SMT_CAPTURED_PERIOD_REG) ;
```

See Also:

setup_smtx(), smtx_start(), smtx_stop(), smtx_status(), smtx_reset_timer(),
smtx_read(), smtx_write()

spi_data_is_in() spi_data_is_in2()spi_data_is_in3() spi_data_is_in4()

Syntax:

```
result = spi_data_is_in()
result = spi_data_is_in2()
result = spi_data_is_in3()
result = spi_data_is_in4()
```

Parameters:

Returns:

0 (FALSE) or 1 (TRUE)

Function:

Returns TRUE if data has been received over the SPI.

Availability:

Devices with SPI hardware.

Requires:

Examples:

```
spi_data_is_in() && input(PIN_B2) );
if( spi_data_is_in() )
    data = spi_read();
```

See Also:

spi_read(), spi_write(), spi_set_txcnt(), SPI Overview

spi_init()**Syntax:**

```
spi_init(baud);
spi_init(stream, baud);
```

Parameters:

stream – is the SPI stream to use as defined in the STREAM=name option in #USE SPI.

band - the band rate to initialize the SPI module to. If FALSE it will disable the SPI module, if TRUE it will enable the SPI module to the baud rate specified in #use SPI.

Returns:

Function:

Initializes the SPI module to the settings specified in #USE SPI.

Availability:

Devices with SPI hardware.

Requires:

#USE SPI

Examples:

```
while #use spi(MATER, SPI1, baud-1000000, mode=0, stream=SPI1_MODE0)

    spi_spi_init(SPI1_MODE0, TRUE);           //initialize and
    enable                                     //SPI1 to setting in

    #USE SPI1
    spi_spi_init(FALSE);                     //disable SPI1
    spi_spi_init(250000);                     //initialize and
    enable SPI1                               //to a baud rate of

    250K
```

See Also:

#USE SPI, spi_xfer(), spi_xfer_in(), spi_prewrite(), spi_speed()

spi_prewrite()**Syntax:**

```
spi_prewrite(data);
spi_prewrite(stream, data);
```

Parameters:

stream - is the SPI stream to use as defined in the STREAM=name option in #USE SPI.

data - the variable or constant to transfer via SPI

Returns:

Function:

Writes data into the SPI buffer without waiting for transfer to be completed. Can be used in conjunction with spi_xfer() with no parameters to transfer more then 8 bits for PCM and PCH device, or more then 8 bits or 16 bits (XFER16 option) for PCD. Function is useful when using the SSP or SSP2 interrupt service routines for PCM and PCH device, or the SPIx interrupt service routines for PCD device.

Availability:

Devices with SPI hardware.

Requires:

#USE SPI

Examples:

```
spi_prewrite(data_out);
```

Example Files:

ex spi.c

See Also:

#USE SPI, spi_xfer(), spi_xfer_in(), spi_init(), spi_speed()

spi_read() spi_read2() spi_read3() spi_read4()

```
[PCD] spi_read_16( )
[PCD] spi_read2_16( )
[PCD] spi_read3_16( )
[PCD] spi_read4_16( )
[PCD] spi_read_32( )
[PCD] spi_read2_32( )
[PCD] spi_read3_32( )
[PCD] spi_read4_32( )
```

Syntax:

value = spi_read([data])

```

value = spi_read2([data])
value = spi_read3([data])
value = spi_read4([data])
[PCD] value = spi_read_16([data])
[PCD] value = spi_read2_16([data])
[PCD] value = spi_read3_16([data])
[PCD] value = spi_read4_16([data])
[PCD] value = spi_read_32([data])
[PCD] value = spi_read2_32([data])
[PCD] value = spi_read3_32([data])
[PCD] value = spi_read4_32([data])

```

Parameters:

data – optional parameter and if included is an 8 bit int.

[PCD] **data** – optional parameter and if included is an 16 bit or 32 bit int.

Returns:

An 8-bit int

[PCD] A 16-bit or 32-bit int.

Function:

Return a value read by the SPI. If a value is passed to the spi_read() the data will be clocked out and the data received will be returned. If no data is ready, spi_read() will wait for the data is a SLAVE or return the last DATA clocked in from spi_write().

If this device is the MASTER then either do a spi_write(data) followed by a spi_read() or do a spi_read(data). These both do the same thing and will generate a clock. If there is no data to send just do a spi_read(0) to get the clock.

If this device is a SLAVE then either call spi_read() to wait for the clock and data or use_spi_data_is_in() to determine if data is ready.

Availability:

Devices with SPI hardware.

Requires:

Examples:

```
data_in = spi_read(out_data);
```

Example Files:

ex_spi.c

See Also:

spi_write(), spi_data_is_in(), spi_set_txcnt(), SPI Overview

spi_set_txcnt()

Syntax:

spi_set_txcnt (*count*)

Parameters:

count - int16 value indicating number of SPI transfers that SS1 pin will be driver to active level for.

Returns:

Undefined

Function:

Used to control the number of SPI transfers that the SS1 pin is driven to the active level for when SPI peripheral is setup as SPI Master. Once the value is written, the SS1 pin will be driver to the active state. Also requires that the **#pin_select** be used to assign a pin as the SS1 output pin.

Availability:

Only on PIC18 devices with a dedicated SPI peripheral.

Requires:

Examples:

```
#pin_select SCK1OUT=PIN_C0
#pin_select SD01=PIN_C1
#pin_select SDI1=PIN_C2
#pin_select SS1OUT=PIN_C4

setup_spi(SPI_MASTER|SPI_SCK_IDLE_LOW|SPI_XMIT_L_TO_H|
SPI_CLK_FOSC,500000);

spi_set_txcnt(3);
spi_write(WRITE_COMMAND);
spi_write(Address);
spi_write(Data);
```


See Also:

[setup_spi\(\)](#), [spi_write\(\)](#), [spi_read\(\)](#), [spi_data_is_in\(\)](#), [SPI Overview](#)

spi_speed()**Syntax:**

```
spi_speed(baud);
spi_speed(stream, baud);
spi_speed(stream, baud, clock);
```

Parameters:

stream – is the SPI stream to use as defined in the STREAM=name option in #USE SPI.

band - the band rate to set the SPI module to.

clock - the current clock rate to calculate the band rate with. If not specified it uses the value specified in #use delay().

Returns:

Function:

Sets the SPI module's baud rate to the specified value.

Availability:

Devices with SPI hardware.

Requires:

#USE SPI

Examples:

```
spi_speed(250000);
spi_speed(SPI1_MODE0, 250000);
spi_speed(SPI1_MODE0, 125000, 8000000);
```

See Also:

[#USE SPI](#), [spi_xfer\(\)](#), [spi_xfer_in\(\)](#), [spi_prewrite\(\)](#), [spi_init\(\)](#)

[PCD] spi_transfer_write()**Syntax:**

```
spi_transfer_write([stream], data, count);
```

Parameters:

stream – an optional parameter specifying the SPI stream to transfer the data with.
Defaults to last used SPI stream in if not specified.

data - the pointer to an array of bytes to transfer via SPI. The pin used to transfer data is defined in the DO=option in #use SPI.

clock - the number of bytes to transfer via SPI.

Returns:

Function:

Used to transfer multiple bytes to an SPI device.

Availability:

All devices

Requires:

#USE SPI

Examples:

```
spi_transfer_write(Data, 128);
```

See Also:

#USE SPI, [spi_xfer\(\)](#),

spi_write() spi_write2() spi_write3() spi_write4()

```
[PCD] spi_write_16( )
[PCD] spi_write2_16( )
[PCD] spi_write3_16( )
[PCD] spi_write4_16( )
[PCD] spi_write_32( )
[PCD] spi_write2_32( )
[PCD] spi_write3_32( )
[PCD] spi_write4_32( )
```

Syntax:

```
spi_write([wait],value);
spi_write2([wait],value);
spi_write3([wait],value);
spi_write4([wait],value);
```

```
[PCD] spi_write_16([wait],value);
[PCD] spi_write2_16([wait],value);
[PCD] spi_write3_16([wait],value);
[PCD] spi_write4_16([wait],value);
[PCD] spi_write_32([wait],value);
[PCD] spi_write2_32([wait],value);
[PCD] spi_write3_32([wait],value);
[PCD] spi_write4_32([wait],value);
```

Parameters:

value - is an 8 bit int

[PCD] **value** - is an 16 bit or 32 bit int

wait- an optional parameter specifying whether the function will wait for the SPI transfer to complete before exiting. Default is TRUE if not specified.

Returns:

Function:

Sends data out the SPI interface. This will cause clocks to be generated. This function will write the value out to the SPI. At the same time data is clocked out data is clocked in and stored in a receive buffer. The `spi_read()` may be used to read the buffer.

Availability:

Devices with SPI hardware.

Requires:

Examples:

```
spi_write( data_out );
data_in = spi_read();
```

Example Files:

[ex_spi.c](#)

See Also:

[spi_read\(\)](#), [spi_data is in\(\)](#), [SPI Overview](#), [spi_set_txcnt\(\)](#)

spi_xfer()

Syntax:

```
spi_xfer(data)
spi_xfer(stream, data)
spi_xfer(stream, data, bits)
result = spi_xfer(data)
result = spi_xfer(stream, data)
result = spi_xfer(stream, data, bits)
```

Parameters:

data - is the variable or constant to transfer via SPI. The pin used to transfer data is defined in the DO=pin option in #USE SPI.

stream - is the SPI stream to use as defined in the STREAM=name option in #USE SPI.

bits - is how many bits of data will be transferred.

Returns:

The data read in from the SPI. The pin used to transfer result is defined in the DI=pin option in #USE SPI.

Function:

Transfers data to and reads data from an SPI device.

Availability:

Devices with SPI hardware.

Requires:

#USE SPI

Examples:

```
int i = 34;
spi_xfer(i);                      // transfers the number 34 via SPI
int trans = 34, res;
res = spi_xfer(trans);           // transfers the number 34 via SPI
                                  // also reads the number coming in from
SPI
```

See Also:

[#USE SPI](#)

spi_xfer_in()

Syntax:

```
value = spi_xfer_in();
value = spi_xfer_in(bits);
value = spi_xfer_in(stream,bits);
```

Parameters:

stream - is the SPI stream to use as defined in the STREAM=name option in #USE SPI.

bits - is how many bits of data will be received.

Returns:

The data read in from the SPI.

Function:

Reads data from the SPI, without writing data into the transmit buffer first.

Availability:

Devices with SPI hardware.

Requires:

#USE SPI, and the option SLAVE is used in #USE SPI to setup PIC as a SPI slave device.

Examples:

```
data_in = spi_xfer_in();
```

Example Files:

ex_spi.c

See Also:

#USE SPI, spi_xfer(), spi_prewrite(), spi_init(), spi_speed()

sprintf()

Syntax:

```
sprintf(string, cstring, values...);
bytes=sprintf(string, cstring, values...)
```

Parameters:

string - is an array of characters.

cstring - is a constant string or an array of characters null terminated.

values - are a list of variables separated by commas. Note that format specifies do not work in ram band strings.

Returns:

Bytes is the number of bytes written to string.

Function:

This function operates like printf() except that the output is placed into the specified string. The output string will be terminated with a null. No checking is done to ensure the string is large enough for the data. See printf() for details on formatting.

Availability:

All Devices

Requires:

See Also:

printf()

sqrt()**Syntax:**

result = sqrt (**value**)

Parameters:

value - is a float

[PCD] **value** - is any float type

Returns:

A float

[PCD] Returns a floating point value with a precision equal to **value**

Function:

Computes the non-negative square root of the float value x. If the argument is negative, the behavior is undefined.

Note on error handling:

If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Domain error occurs in the following cases: sqrt: when the argument is negative

Availability:

All Devices

Requires:

```
#INCLUDE <math.h>
```

Examples:

```
distance = sqrt( pow((x1-x2),2)+pow((y1-y2),2) );
```

srand()**Syntax:**

```
srand(n)
```

Parameters:

n - is the seed for a new sequence of pseudo-random numbers to be returned by subsequent calls to *rand*.

Returns:

Function:

The `srand()` function uses the argument as a seed for a new sequence of pseudo-random numbers to be returned by subsequent calls to `rand`. If `srand()` is then called with same seed value, the sequence of random numbers shall be repeated. If `rand` is called before any call to `srand()` have been made, the same sequence shall be generated as when `srand()` is first called with a seed value of 1.

Availability:

All Devices

Requires:

```
#INCLUDE <STDLIB.H>
```

Examples:

```
srand(10);  
I=rand();
```

See Also:

[rand\(\)](#)

STANDARD STRING FUNCTIONS() memchr() memcmp()
strcat() strchr() strcmp() strcoll() strcspn()
strerror() stricmp() strlen() strlwr() strncat()
strncmp() strncpy() strpbrk() strrchr() strspn()
strstr() strxfrm()

Syntax:

ptr=strcat (s1, s2)	Concatenate s2 onto s1
ptr=strchr (s1, c)	Find c in s1 and return &s1[i]
ptr=strrchr (s1, c)	Same but search in reverse
cresult=strcmp (s1, s2)	Compare s1 to s2
ireult=strncmp (s1, s2, n)	Compare s1 to s2 (n bytes)
ireult=stricmp (s1, s2)	Compare and ignore case
ptr=strncpy (s1, s2, n)	Copy up to n characters s2->s1
ireult=strcspn (s1, s2)	Count of initial chars in s1 not in s2
ireult=strspn (s1, s2)	Count of initial chars in s1 also in s2
ireult=strlen (s1)	Number of characters in s1
ptr=strlwr (s1)	Convert string to lower case
ptr=strpbrk (s1, s2)	Search s1 for first char also in s2
ptr=strstr (s1, s2)	Search for s2 in s1
ptr=strncat(s1,s2, n)	Concatenates up to n bytes of s2 onto s1
ireult=strcoll(s1,s2)	Compares s1 to s2, both interpreted as appropriate to the current locale.
res=strxfrm(s1,s2,n)	Transforms maximum of n characters of s2 and places them in s1, such that strcmp(s1,s2) will give the same result as strcoll(s1,s2)
ireult=memcmp(m1,m2,n)	Compare m1 to m2 (n bytes)
ptr=memchr(m1,c,n)	Find c in first n characters of m1 and return &m1[i]
ptr=strerror(errno)	Maps the error number in errno to an error message string. The parameters 'errno' is an unsigned 8 bit int. Returns a pointer to the string.

Parameters:

s1 and **s2** are pointers to an array of characters (or the name of an array).
 Note that s1 and s2 MAY NOT BE A CONSTANT (like "hi").

n - is a count of the maximum number of character to operate on.

c - is a 8 bit character

m1 and **m2** are pointers to memory.

Returns & Functions:

ptr is a copy of the s1 pointer

ireresult is an 8 bit int

result is -1 (less than), 0 (equal) or 1 (greater than)

res is an integer.

Availability:

All Devices

Requires:

#include <string.h>

Examples:

```
char string1[10], string2[10];

strcpy(string1, "hi ");
strcpy(string2, "there");
strcat(string1, string2);
printf("Length is %u\r\n", strlen(string1));           // Will print 8
```

Example Files:

ex_str.c

See Also:

strcpy(), strtok()

strcpy() strcpy()**Syntax:**

strcpy (*dest*, *src*)

strcpy (*dest*, *src*)

Parameters:

dest - is a pointer to a RAM array of characters.

src - may be either a pointer to a RAM array of characters or it may be a constant string.

Returns:

Function:

Copies a constant or RAM string to a RAM string. Strings are terminated with a 0.

Availability:

All Devices

Requires:

Examples:

```

    schar string[10], string2[10];
    .
    .
    .
    strcpy (string, "Hi There");

    strcpy(string2, string);

```

Example Files:ex_str.c**See Also:**strxxxx()**strtod()****[PCD] strtod()** **[PCD] strtod48()****Syntax:**result=strtod(*nptr*,& *endptr*)**[PCD]** result=strtod(*nptr*,& *endptr*)**[PCD]** result=strtod48(*nptr*,& *endptr*)**Parameters:***nptr* and *endptr* are strings**Returns:**

result is a float.

[PCD]

strtod returns a double precision floating point number.

strtod returns a single precision floating point number.

strtod48 returns a extended precision floating point number.

Returns the converted value in result, if any. If no conversion could be performed, zero is returned.

Function:

The strtod function converts the initial portion of the string pointed to by *nptr* to a float representation. The part of the string after conversion is stored in the object pointed to *endptr*, provided that *endptr* is not a null pointer. If *nptr* is empty or does not have the

expected form, no conversion is performed and the value of `nptr` is stored in the object pointed to by `endptr`, provided `endptr` is not a null pointer.

Availability:

All Devices

Requires:

`#INCLUDE <stdlib.h>`

Examples:

```
float result;                                //PCD devices, replace "float"
with "double"
char str[12]="123.45hello";
char *ptr;
result=strtod(str, &ptr);                    //result is 123.45 and ptr is
"hello"
```

See Also:

[strtol\(\)](#), [strtoul\(\)](#)

strtok()**Syntax:**

`ptr = strtok(s1, s2)`

Parameters:

s1 and **s2** are pointers to an array of characters (or the name of an array).

Note that **s1** and **s2** MAY NOT BE A CONSTANT (like "hi"). **s1** may be 0 to indicate a continue operation.

Returns:

ptr points to a character in **s1** or is 0

Function:

Finds next token in **s1** delimited by a character from separator string **s2** (which can be different from call to call), and returns pointer to it.

First call starts at beginning of **s1** searching for the first character NOT contained in **s2** and returns null if there is none are found.

If none are found, it is the start of first token (return value). Function then searches from there for a character contained in **s2**.

If none are found, current token extends to the end of s1, and subsequent searches for a token will return null.

If one is found, it is overwritten by '\0', which terminates current token. Function saves pointer to following character from which next search will start.

Each subsequent call, with 0 as first argument, starts searching from the saved pointer.

Availability:

All Devices

Requires:

#INCLUDE <string.h>

Examples:

```
char string[30], term[3], *ptr;

strcpy(string, "one,two,three;");
strcpy(term, ",;");

ptr = strtok(string, term);
while(ptr!=0) {
    puts(ptr);
    ptr = strtok(0, term);
}                                     // Prints: one, two, three
```

Example Files:

ex_str.c

See Also:

strxxx(), strcpy()

strtol()**Syntax:**

result=strtol(*nptr*, &*endptr*, *base*)

Parameters:

nptr and *endptr* are strings and *base* is an integer

Returns:

Result is a signed long *int*.

Returns the converted value in result , if any. If no conversion could be performed, zero is returned.

Function:

The **strtol** function converts the initial portion of the string pointed to by **nptr** to a signed long **int** representation in some radix determined by the value of base. The part of the string after conversion is stored in the object pointed to **endptr**, provided that **endptr** is not a null pointer. If **nptr** is empty or does not have the expected form, no conversion is performed and the value of **nptr** is stored in the object pointed to by **endptr**, provided **endptr** is not a null pointer.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
signed long result;
char str[9]="123hello";
char *ptr;
result=strtol(str,&ptr,10);           //result is 123 and ptr is "hello"
```

See Also:

[strtod\(\)](#), [strtoul\(\)](#)

strtoul()**Syntax:**

result=strtoul(**nptr**,**endptr**, **base**)

Parameters:

nptr and **endptr** are strings pointers and **base** is an integer 2-36.

Returns:

Result is a signed long **int**.

Returns the converted value in result , if any. If no conversion could be performed, zero is returned.

Function:

The **strtoul** function converts the initial portion of the string pointed to by **nptr** to a long **int** representation in some radix determined by the value of base. The part of the string after conversion is stored in the object pointed to **endptr**, provided that **endptr** is not a null pointer. If **nptr** is empty or does not have the expected form, no conversion is performed and the value of **nptr** is stored in the object pointed to by **endptr**, provided **endptr** is not a null pointer.

Availability:

All Devices

Requires:

#INCLUDE <stdlib.h>

Examples:

```
long result;
char str[9]="123hello";
char *ptr;
result=strtoul(str,&ptr,10);           //result is 123 and ptr is "hello"
```

See Also:

[strtol\(\)](#), [strtod\(\)](#)

swap()

Syntax:

swap (*lvalue*)

[PCD] result = swap(*lvalue*)

Parameters:

lvalue - is a byte variable

Returns:

undefined - WARNING: this function does not return the result

[PCD] A byte

Function:

Swaps the upper nibble with the lower nibble of the specified byte. This is the same as:

byte = (byte << 4) | (byte >> 4);

Availability:

All Devices

Requires:

Examples:

```
x=0x45;
swap(x);           //x now is 0x54

[PCD]
int x = 0x42;
int result;
```

```
result = swap(x);      // result is 0x24;
```

See Also:

rotate_right(), rotate_left()

tolower() toupper()**Syntax:**

result = tolower (*cvalue*)

result = toupper (*cvalue*)

Parameters:

cvalue - is a character

Returns:

An 8 bit character

Function:

These functions change the case of letters in the alphabet.

TOLOWER(X) will return 'a'..'z' for X in 'A'..'Z' and all other characters are unchanged.

TOUPPER(X) will return 'A'..'Z' for X in 'a'..'z' and all other characters are unchanged.

Availability:

All Devices

Requires:

Examples:

```
switch( toupper(getc()) ) {
    case 'R' : read_cmd(); break;
    case 'W' : write_cmd(); break;
    case 'Q' : done=TRUE; break;
}
```

Example Files:

ex_str.c

touchpad_getc()**Syntax:**

input = TOUCHPAD_GETC();

Parameters:

Returns:

char (returns corresponding ASCII number is “input” declared as *int*)

Function:

Actively waits for firmware to signal that a pre-declared Capacitive Sensing Module (CSM) or charge time measurement unit (CTMU) pin is active, then stores the pre-declared character value of that pin in “input”.

Note: Until a CSM or CTMU pin is read by firmware as active, this instruction will cause the microcontroller to stall.

Availability:

Devices with CSM or CTMU Module.

Requires:

#USE TOUCHPAD (options)

Examples:

```
//When the pad connected to PIN_B0 is activated, store the letter 'A'

#USE TOUCHPAD (PIN_B0='A')
void main(void) {
    char c;
    enable_interrupts(GLOBAL);

    c = TOUCHPAD_GETC();           //will wait until one of declared pins
is detected                       //if PIN_B0 is pressed, c will get
value 'A'
}
```

See Also:

#USE TOUCHPAD, [touchpad_state\(\)](#)

touchpad_hit()

Syntax:

value = TOUCHPAD_HIT()

Parameters:

Returns:

TRUE or FALSE

Function:

Returns TRUE if a Capacitive Sensing Module (CSM) or Charge Time Measurement Unit (CTMU) key has been pressed. If TRUE, then a call to `touchpad_getc()` will not cause the program to wait for a key press.

Availability:

Devices with CSM or CTMU Module.

Requires:

#USE TOUCHPAD (options)

Examples:

```
//When the pad connected to PIN_B0 is activated, store the letter 'A'

#USE TOUCHPAD (PIN_B0='A')
void main(void){
    char c;
    enable_interrupts(GLOBAL);
    while (TRUE) {
        if ( TOUCHPAD_HIT() )           //wait until key on PIN_B0 is
pressed                                pressed
        c = TOUCHPAD_GETC();             //get key that was pressed
    }                                    //c will get value 'A'
}
```

See Also:

#USE TOUCHPAD, [touchpad_state\(\)](#), [touchpad_getc\(\)](#)

touchpad_state()

Syntax:

TOUCHPAD_STATE (**state**);

Parameters:

state - is a literal 0, 1, or 2.

Returns:

Function:

Sets the current state of the touchpad connected to the Capacitive Sensing Module (CSM). The state can be one of the following three values:

0 : Normal state

1 : Calibrates, then enters normal state

2 : Test mode, data from each key is collected in the int16 array TOUCHDATA

Note: If the state is set to 1 while a key is being pressed, the touchpad will not calibrate properly.

Availability:

Devices with CSM or CTMU Module.

Requires:

#USE TOUCHPAD (options)

Examples:

```
#USE TOUCHPAD (THRESHOLD=5, PIN_D5='5', PIN_B0='C')
void main(void){
    char c;
    TOUCHPAD_STATE(1);           //calibrates, then enters normal
    state
    enable_interrupts(GLOBAL);
    while(1){
        c = TOUCHPAD_GETC();      //will wait until one of declared pins
        is detected               //if PIN_B0 is pressed, c will get
        value 'C'
    }                             //if PIN_D5 is pressed, c will get
    value '5'
```

See Also:

#USE TOUCHPAD, [touchpad_getc\(\)](#), [touchpad_hit\(\)](#)

tx_buffer_available()

Syntax:

value = tx_buffer_available([stream]);

Parameters:

stream – optional parameter specifying the stream defined in #USE RS232.

Returns:

Number of bytes that can still be put into transmit buffer.

Function:

Function to determine the number of bytes that can still be put into transmit buffer before it overflows. Transmit buffer is implemented has a circular buffer, so be sure to check to make sure there is room for at least one more then what is actually needed.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50)
void main(void) {
    unsigned int8 Count = 0;

    while(TRUE) {
        if(tx_buffer_available()>13)
            printf("/r/nCount=%3u",Count++);
    }
}
```

See Also:

USE_RS232(), tx_buffer_full(), rcv_buffer_bytes(), rcv_buffer_full(), get(), putc(), printf(), setup_uart(), putc_send()

tx_buffer_bytes()**Syntax:**

value = tx_buffer_bytes([stream]);

Parameters:

stream – optional parameter specifying the stream defined in #USE RS232.

Returns:

Number of bytes in transmit buffer that still need to be sent.

Function:

Function to determine the number of bytes in transmit buffer that still need to be sent.

Availability:

All Devices

Requires:

#USE RS232

Examples:

```
#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50)
```

```
void main(void) {  
    char string[] = "Hello";  
    if(tx_buffer_bytes() <= 45)  
        printf("%s",string);  
}
```

See Also:

USE_RS232(), tx_buffer_full(), rcv_buffer_bytes(), rcv_buffer_full(), get(), putc(), printf(), setup_uart(), putc_send()

tx_buffer_full()**Syntax:**

value = tx_buffer_full([stream])

Parameters:

stream – optional parameter specifying the stream defined in #USE_RS232

Returns:

TRUE if transmit buffer is full, FALSE otherwise.

Function:

Function to determine if there is room in transmit buffer for another character.

Availability:

All Devices

Requires:

#USE_RS232

Examples:

```
#USE_RS232 (UART1,BAUD=9600,TRANSMIT_BUFFER=50)  
void main(void) {  
    char c;  
    if(!tx_buffer_full())  
        putc(c);  
}
```

See Also:

USE_RS232(), tx_buffer_bytes(), rcv_buffer_bytes(), rcv_buffer_full(), get(), putc(), printf(), setup_uart(), putc_send()

va_arg()

Syntax:

va_arg(argptr, type)

Parameters:

argptr - is a special argument pointer of type `va_list`

type - This is data type like `int` or `char`.

Returns:

The first call to `va_arg` after `va_start` return the value of the parameters after that specified by the last parameter. Successive invocations return the values of the remaining arguments in succession.

Function:

The function will return the next argument every time it is called.

Availability:

All Devices

Requires:

`#INCLUDE <stdarg.h>`

Examples:

```

int foo(int num, ...)
{
    int sum = 0;
    int i;
    va_list argptr;                // create special argument
    pointer
    va_start(argptr,num);          // initialize argptr
    for(i=0; i<num; i++)
        sum = sum + va_arg(argptr, int);
    va_end(argptr);               // end variable processing
    return sum;
}

```

See Also:

[nargs\(\)](#), [va_end\(\)](#), [va_start\(\)](#)

va_end()

Syntax:

va_end(argptr)

Parameters:

argptr - is a special argument pointer of type `va_list`

Returns:

Function:

A call to the macro will end variable processing. This will facilitate a normal return from the function whose variable argument list was referred to by the expansion of `va_start()`.

Availability:

All Devices

Requires:

`#INCLUDE <stdarg.h>`

Examples:

```
int foo(int num, ...)
{
    int sum = 0;
    int i;
    va_list argptr;                // create special argument pointer
    va_start(argptr,num);          // initialize argptr
    for(i=0; i<num; i++)
        sum = sum + va_arg(argptr, int);
    va_end(argptr);                // end variable processing
    return sum;
}
```

See Also:

`nargs()`, `va_start()`, `va_arg()`

va_start()**Syntax:**

`va_start(argptr, variable)`

Parameters:

argptr - is a special argument pointer of type `va_list`

variable – The second parameter to ***va_start()*** is the name of the last parameter before the variable-argument list.

Returns:

Function:

The function will initialize the **argptr** using a call to the macro **va_start()**.

Availability:

All Devices

Requires:

#INCLUDE <stdarg.h>

Examples:

```
int foo(int num, ...)
{
    int sum = 0;
    int i;
    va_list argptr;                // create special argument
    pointer
    va_start(argptr,num);          // initialize argptr
    for(i=0; i<num; i++)
        sum = sum + va_arg(argptr, int);
    va_end(argptr);                // end variable processing
    return sum;
}
```

See Also:

[nargs\(\)](#), [va_start\(\)](#), [va_arg\(\)](#)

verify_slave_program()

Syntax:

result = verify_slave_program(address, instructions);

Parameters:

address - The address in the Master's program memory that the Slave program is stored at. Because of how the data is stored and written the address must be a multiple of 4.

Instructions - The number of instructions to copy from the Master's Flash to the Slave's PRAM, because of how the data is written the number of instructions must be a multiple of 2.

Returns:

An int16 value indicating the number of errors, mis-matched instruction pairs, it found. If the return value is 0, then program loaded in the Slave's PRAM matches what is in the Master's Flash, i.e. the Slave program was verified.

Function:

Verify that the program loaded into the Slave's PRAM matched what is stored in the Master's Flash.

Availability:

Only available on Dual Core devices.

Requires:

Examples:

```
Result = verify_slave_program(0x10000, 512);  
if(Result ==0)  
    setup_msi_(MSI_SLAVE_ENABLED);
```

See Also:

load_slave_program()

write_bank()**Syntax:**

write_bank (*bank*, *offset*, *value*)

Parameters:

bank - is the physical RAM bank 1-3 (depending on the device)

offset - is the offset into user RAM for that bank (starts at 0)

value - is the 8 bit data to write

Returns:

Function:

Write a data byte to the user RAM area of the specified memory bank. This function may be used on some devices where full RAM access by auto variables is not efficient. For example on the PIC16C57 chip setting the pointer size to 5 bits will generate the most efficient ROM code however auto variables can not be above 1Fh. Instead of going to 8 bit pointers you can save ROM by using this function to write to the hard to reach banks. In this case the bank may be 1-3 and the offset may be 0-15.

Availability:

All devices but only useful on PCB parts with memory over 1Fh and PCM parts with memory over FFh.

Requires:

Examples:

```
i=0;                                // Uses bank 1 as a RS232 buffer
do {
    c=getc();
    write_bank(1,i++,c);
} while (c!=0x13);
```

Example Files:

ex_psp.c

write_configuration_memory()

Syntax:

write_configuration_memory ([**offset**], **dataptr**,**count**)

Parameters:

dataptr - pointer to one or more bytes

count -: a 8 bit integer

offset - is an optional parameter specifying the offset into configuration memory to start writing to, offset defaults to zero if not used.

Returns:

Function:

Erases all fuses and writes count bytes from the **dataptr** to the configuration memory.
For Enhanced16 devices - erases and write User ID memory.

Availability:

All PIC18 Flash and Enhanced16 devices

All PIC24 Flash devices

Requires:

Examples:

```
int data[6];
write_configuration_memory(data,6
```

See Also:

[WRITE_PROGRAM_MEMORY\(\)](#), [Configuration Memory Overview](#)

write_eeprom()**Syntax:**

`write_eeprom (address, value)`

[PCD] `write_eeprom ( address , pointer , N )`

Parameters:

address - is a (8 bit or 16 bit depending on the part) int, the range is device dependent

value - is an 8 bit int

[PCD] ***address*** - is the 0 based starting location of the EEPROM write

[PCD] ***N*** - specifies the number of EEPROM bytes to write

[PCD] ***value*** - is a constant or variable to write to EEPROM

[PCD] ***pointer*** - is a pointer to location to data to be written to EEPROM

Returns:

Function:

Write a byte to the specified data EEPROM address. This function may take several milliseconds to execute. This works only on devices with EEPROM built into the core of the device.

For devices with external EEPROM or with a separate EEPROM in the same package (like the 12CE671) see EX_EXTEE.c with CE51X.c, CE61X.c or CE67X.c.

[PCD] This function will write the specified value to the given address of EEPROM. If pointers are used than the function will write n bytes of data from the pointer to EEPROM starting at the value of address.

In order to allow interrupts to occur while using the write operation, use the #DEVICE option `WRITE_EEPROM = NOINT`. This will allow interrupts to occur while the `write_eeprom()` operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.

Availability:

Devices with supporting hardware on chip.

Requires:

Examples:

```
#define LAST_VOLUME 10    // Location in EEPROM

volume++;
write_eeprom(LAST_VOLUME, volume);
```

Example Files:

[ex_intee.c](#), [ex_extee.c](#), [ce51x.c](#), [ce62x.c](#), [ce67x.c](#)

See Also:

[read_eeprom\(\)](#), [erase_eeprom\(\)](#), [Data EEPROM Overview](#)

write_external_memory()

Syntax:

`write_external_memory( address, dataptr, count )`

Parameters:

address - is 16 bits on PCM parts and 32 bits on PCH parts

dataptr - is a pointer to one or more bytes

count - is a 8 bit integer

Returns:

Function:

Writes count bytes to program memory from ***dataptr*** to address. Unlike ***write_program_eeprom()*** and ***read_program_eeprom()*** this function does not use any special EEPROM/FLASH write algorithm. The data is simply copied from register address space to program memory address space. This is useful for external RAM or to implement an algorithm for external flash.

Availability:

PIC18 Devices Only

Requires:

Examples:

```
for (i=0x1000; i<=0x1fff; i++) {  
    value=read_adc();  
    write_external_memory(i, value, 2);  
    delay_ms(1000);  
}
```

Example Files:

ex_load.c, loader.c

See Also:

write_program_eeprom(), erase_program_eeprom(), Program Eeprom Overview

write_extended_ram()**Syntax:**

`write_extended_ram (page,address,data,count);`

Parameters:

page – the page in extended RAM to write to

address – the address on the selected page to start writing to

data – pointer to the data to be written

count – the number of bytes to write (0-32768)

Returns:

Function:

Write data to the extended RAM of the microcontroller.

Availability:

Devices with more than 30K of RAM.

Requires:

Examples:

```
unsigned int8 data[8] = {0x01,0x02,0x03,0x04,0x05,0x06,0x07,0x08};  
  
write_extended_ram(1,0x0000,data,8);
```

See Also:

[read_extended_ram\(\)](#), [Extended RAM Overview](#)

write_program_eeprom()**Syntax:**

write_program_eeprom (***address***, ***data***)

Parameters:

address - is 16 bits on PCM parts and 32 bits on PCH parts, data is 16 bits. The least significant bit should always be 0 in PCH.

Returns:

Function:

Writes to the specified program EEPROM area.

See write_program_memory() for more information on this function.

Availability:

Devices that allow writes to program memory.

Requires:

Examples:

```
write_program_eeprom(0,0x2800);    //disables program
```

Example Files:

[ex_load.c](#), [loader.c](#)

See Also:

[read_program_eeprom\(\)](#), [read_eeprom\(\)](#), [write_eeprom\(\)](#), [write_program_memory\(\)](#), [erase_program_eeprom\(\)](#), [Program Eeprom Overview](#)

write_program_memory()

Syntax:

write_program_memory(*address*, *dataptr*, *count*);

Parameters:

address - is 16 bits on PCM parts and 32 bits on PCH parts

[PCD] **address** - is 32 bits

dataptr - is a pointer to one or more bytes

count - is a 8 bit integer on PIC16 and 16-bit for PIC18

[PCD] **count** - is a 16 bit integer

Returns:

Function:

Writes count bytes to program memory from dataptr to address. This function is most effective when count is a multiple of FLASH_WRITE_SIZE. Whenever this function is about to write to a location that is a multiple of FLASH_ERASE_SIZE then an erase is performed on the whole block.

NOTES: Clarification about the functions to write to program memory:

In order to get the desired results while using write_program_memory(), the block of memory being written to needs to first be read in order to save any other variables currently stored there, then erased to clear all values in the block before the new values can be written. This is because the write_program_memory() function does not save any values in memory and will only erase the block if the first location is written to. If this process is not followed, when new values are written to the block, they will appear as garbage values.

For chips where getenv("FLASH_ERASE_SIZE") > getenv("FLASH_WRITE_SIZE")

write_program_eeprom() - Writes 2 bytes, does not erase (use erase_program_eeprom())

write_program_memory() - Writes any number of bytes, will erase a block whenever the first (lowest) byte in a block is written to. If the first address is not the start of a block that block is not erased.

erase_program_eeprom() - Will erase a block. The lowest address bits are not used.

For chips where getenv("FLASH_ERASE_SIZE") = getenv("FLASH_WRITE_SIZE")

`write_program_eeprom()` - Writes 2 bytes, no erase is needed.

`write_program_memory()` - Writes any number of bytes, bytes outside the range of the write block are not changed. No erase is needed.

`erase_program_eeprom()` - Not available

[PCD] Writes count bytes to program memory from dataptr to address. This function is most effective when count is a multiple of FLASH_WRITE_SIZE, but count needs to be a multiple of MIN_FLASH_WRITE. Whenever this function is about to write to a location that is a multiple of FLASH_ERASE_SIZE then an erase is performed on the whole block. Due to the 24 bit instruction length on PCD parts, every fourth byte of data is ignored. Fill the ignored bytes with 0x00.

See Program EEPROM Overview for more information on program memory access

Availability:

Devices that allow writes to program memory.

Requires:

Examples:

```
wfor(i=0x1000;i<=0x1fff;i++) {
    value=read_adc();
    write_program_memory(i, value, 2);
    delay_ms(1000);
}
```

```
[PCD]
for(i=0x1000;i<=0x1fff;i++) {
    value=read_adc();
    write_program_memory(i, &value, 4);
    delay_ms(1000);
}
```

```
int8 write_data[4] = {0x10,0x20,0x30,0x00};
write_program_memory (0x2000, write_data, 4);
```

Example Files:

[loader.c](#)

See Also:

[write_program_eepro](#), [erase_program_eeprom](#), [Program Eeprom Overview](#)

write_program_memory8()**Syntax:**

```
write_PROGRAM_MEMORY8 (address, dataptr, count );
```

Parameters:

address is 16 bits to start writing data to the program memory.

dataptr is a pointer to an array of bytes containing data to write to program memory.

count is the number of bytes to write to program memory.

Returns:

Undefined

Function:

Write ***count*** bytes to program memory. This function only writes the least significant byte to each address in program memory. See **write_program_memory()** for a function that can write all the data to each address in program memory.

Availability:

Only on PCM devices with the ability to Read program memory.

Requires:

Examples:

```
write_program_memory8(Address, Data, 128);
```

See Also:

read_program_memory(), write_program_memory(), read_program_memory8(),
Program Eeprom Overview

zcd_status()**Syntax:**

```
value=zcd_status()
```

Parameters:**Returns:**

value - the status of the ZCD module. The following defines are made in the device's header file and are as follows:

```
ZCD_IS_SINKING
```


ZCD_IS_SOURCING

Function:

Determine if the Zero-Cross Detection (ZCD) module is currently sinking or sourcing current.

If the ZCD module is setup to have the output polarity inverted, the value return will be reversed.

Availability:

All devices with a ZCD module.

Requires:

Examples:

```
value=zcd_status():
```

See Also:

setup_zcd()

STANDARD C INCLUDE FILES

errno.h

EDOM	Domain error value
ERANGE	Range error value
errno	error value

float.h

FLT_RADIX:	Radix of the exponent representation
FLT_MANT_DIG:	Number of base digits in the floating point significant
FLT_DIG:	Number of decimal digits, q, such that any floating point number with q decimal digits can be rounded into a floating point number with p radix b digits and back again without change to the q decimal digits.
FLT_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating-point number.
FLT_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating-point numbers.
FLT_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating-point number.
FLT_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range representable finite floating-point numbers.
FLT_MAX:	Maximum representable finite floating point number.
FLT_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
FLT_MIN:	Minimum normalized positive floating point number
DBL_MANT_DIG:	Number of base digits in the floating point significant [PCD] double significant
DBL_DIG:	Number of decimal digits, q, such that any floating point number or [PCD] double number with q decimal digits can be rounded into a floating point number or [PCD] double number with p radix b digits and back again without change to the q decimal digits.
DBL_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating point number or [PCD] double number.
DBL_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating point number or [PCD] double number.
DBL_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating point number or [PCD] double number.

DBL_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range of representable finite floating point number or [PCD] double number.
DBL_MAX:	Maximum representable finite floating point number.
DBL_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
DBL_MIN:	Minimum normalized positive floating point number or [PCD] double number.
LDBL_MANT_DIG:	Number of base digits in the floating point significant
LDBL_DIG:	Number of decimal digits, q, such that any floating point number with q decimal digits can be rounded into a floating point number with p radix b digits and back again without change to the q decimal digits.
LDBL_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating-point number.
LDBL_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating-point numbers.
LDBL_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating-point number.
LDBL_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range of representable finite floating-point numbers.
LDBL_MAX:	Maximum representable finite floating point number.
LDBL_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
LDBL_MIN:	Minimum normalized positive floating point number.

limits.h

CHAR_BIT:	Number of bits for the smallest object that is not a bit_field.
SCHAR_MIN:	Minimum value for an object of type signed char
SCHAR_MAX:	Maximum value for an object of type signed char
UCHAR_MAX:	Maximum value for an object of type unsigned char
CHAR_MIN:	Minimum value for an object of type char(unsigned)
CHAR_MAX:	Maximum value for an object of type char(unsigned)
MB_LEN_MAX:	Maximum number of bytes in a multibyte character.
SHRT_MIN:	Minimum value for an object of type short int
SHRT_MAX:	Maximum value for an object of type short int
USHRT_MAX:	Maximum value for an object of type unsigned short int
INT_MIN:	Minimum value for an object of type signed int
INT_MAX:	Maximum value for an object of type signed int
UINT_MAX:	Maximum value for an object of type unsigned int
LONG_MIN:	Minimum value for an object of type signed long int
LONG_MAX:	Maximum value for an object of type signed long int

ULONG_MAX:	Maximum value for an object of type unsigned long int

locale.h

locale.h	(Localization not supported)
lconv	localization structure
SETLOCALE()	returns null
LOCALCONV()	returns clocale

setjmp.h

jmp_buf:	An array used by the following functions
setjmp:	Marks a return point for the next longjmp
longjmp:	Jumps to the last marked point

stddef.h

ptrdiff_t:	The basic type of a pointer
size_t:	The type of the sizeof operator (int)
wchar_t	The type of the largest character set supported (char) (8 bits)
NULL	A null pointer (0)

stdio.h

stderr	The standard error s stream (USE RS232 specified as stream or the first USE RS232)
stdout	The standard output stream (USE RS232 specified as stream last USE RS232)
stdin	The standard input s stream (USE RS232 specified as stream last USE RS232)

stdlib.h

div_t	structure type that contains two signed integers (quot and rem).
ldiv_t	structure type that contains two signed longs (quot and rem)
EXIT_FAILURE	returns 1
EXIT_SUCCESS	returns 0

RAND_MAX-	
MBCUR_MAX-	1
SYSTEM()	Returns 0(not supported)
Multibyte character and string functions:Multibyte characters not supported	
MBLEN()	Returns the length of the string.
MBTOWC()	Returns 1.
WCTOMB()	Returns 1.
MBSTOWCS()	Returns length of string.
WBSTOMBS()	Returns length of string.

Stdlib.h functions included just for compliance with ANSI C.

SOFTWARE LICENSE AGREEMENT

**Carefully read this Agreement prior to opening this package. By opening this package, you agree to abide by the following provisions.
If you choose not to accept these provisions, promptly return the unopened package for a refund.**

All materials supplied herein are owned by Custom Computer Services, Inc. ("CCS") and is protected by copyright law and international copyright treaty. Software shall include, but not limited to, associated media, printed materials, and electronic documentation.

These license terms are an agreement between You ("Licensee") and CCS for use of the Software ("Software"). By installation, copy, download, or otherwise use of the Software, you agree to be bound by all the provisions of this License Agreement.

1. **LICENSE** - CCS grants Licensee a license to use in one of the two following options:
 - 1) Software may be used solely by single-user on multiple computer systems;
 - 2) Software may be installed on single-computer system for use by multiple users. Use of Software by additional users or on a network requires payment of additional fees.

Licensee may transfer the Software and license to a third party; and such third party will be held to the terms of this Agreement. All copies of Software must be transferred to the third party or destroyed. Written notification must be sent to CCS for the transfer to be valid.

2. **APPLICATIONS SOFTWARE** - Use of this Software and derivative programs created by Licensee shall be identified as Applications Software, are not subject to this Agreement. Royalties are not be associated with derivative programs.
3. **WARRANTY** - CCS warrants the media to be free from defects in material and workmanship, and that the Software will substantially conform to the related documentation for a period of thirty (30) days after the date of purchase. CCS does not warrant that the Software will be free from error or will meet your specific requirements. If a breach in warranty has occurred, CCS will refund the purchase price or substitution of Software without the defect.
4. **LIMITATION OF LIABILITY AND DISCLAIMER OF WARRANTIES** – CCS and its suppliers disclaim any expressed warranties (other than the warranty contained in Section 3 herein), all implied warranties, including, but not limited to, the implied warranties of merchantability, of satisfactory quality, and of fitness for a particular purpose, regarding the Software.

Neither CCS, nor its suppliers, will be liable for personal injury, or any incidental, special, indirect or consequential damages whatsoever, including, without limitation, damages for loss of profits, loss of data, business interruption, or any other commercial damages or losses, arising out of or related to your use or inability to use the Software.

Licensee is responsible for determining whether Software is suitable for Applications.

©1994-2019 Custom Computer Services, Inc.
ALL RIGHTS RESERVED WORLDWIDE
PO BOX 2452
BROOKFIELD, WI 53008 U.S.A.