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Counter Modules and Circuit Applications

PROPELLER EDUCATION KIT LAB SERIES

Introduction

Each Propeller cog has two *counter modules*, each of which can be configured to independently perform repetitive tasks. So, not only does the Propeller chip have the ability to execute code simultaneously in separate cogs, each cog can also orchestrate up to two processes with counter modules while the cog continues executing program commands.

Counters can provide a cog with a variety of services; here are some examples:

- Measure pulse and decay durations
- Count signal cycles and measure frequency
- Send numerically controlled oscillator (NCO) signals, i.e. square waves
- Send phase-locked loop (PLL) signals, which can be useful for higher frequency square waves
- Signal edge detection
- Digital to analog (D/A) conversion
- Analog to digital (A/D) conversion
- Provide internal signals for video generation

Since each counter module can be configured to perform many of these tasks in a “set it and forget it” fashion, it is possible for a single cog to execute a program and at the same time do things like generate speaker tones, control motors and/or servos, count incoming frequencies, and transmit and/or measure analog voltages.

This lab provides examples of how to use ten of the thirty-two different counter modes to perform variations of eight different tasks:

- RC decay time measurement for potentiometers and photoresistor
- D/A conversion to control LED brightness
- NCO signals to send speaker tones
- NCO signals for modulated IR for object and distance detection
- Count speaker tone cycles
- Detect a signal transition
- Pulse width modulation
- Generate high frequency signals for metal proximity detection

The majority of the code examples in this lab are top level objects that demonstrate the details and inner workings of counter modules. In several of the projects at the end of the lab, you will use these examples to write objects that make it possible to get the same job done with a simple method call.

Prerequisites

Please complete the following labs first before continuing here:

- Setup and Testing
- I/O and Timing
- Methods and Cogs
- Objects

How Counter Modules Work

Each cog has two counter modules, Counter A and Counter B. Each cog also has three 32-bit special purpose registers for each of its counter modules. The Counter A special purpose registers are **phsa**, **frqa**, **ctra**, and Counter B's are **phsb**, **frqb** and **ctrb**. Note that each counter name is also a reserved word in Spin and Propeller assembly. If this lab is referring to a register generally, but it doesn't matter whether it's for Counter A or Counter B, it will use the generic names PHS, FRQ, and CTR.

Here is how each of the three registers works in a counter module:

- PHS – the “phase” register gets updated every clock tick. A counter module can also be configured make certain PHS register bits affect certain I/O pins.
- FRQ – the “frequency” register gets conditionally added to the PHS register every clock tick. The counter module's mode determines what conditions cause FRQ to get added to PHS. Mode options include “always”, “never”, and conditional options based on I/O pin states or transitions.
- CTR – the “control” register configures both the counter module's mode and the I/O pin(s) that get monitored and/or controlled by the counter module. Each counter module has 32 different modes, and depending on the mode, can monitor and/or control up to two I/O pins.

Measuring RC Decay with Positive Detector Mode

Resistor-Capacitor (RC) decay is useful for a variety of sensor measurements. Some examples include:

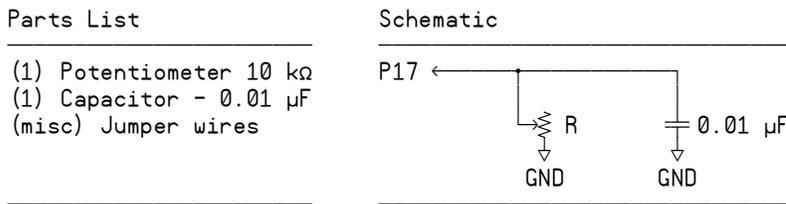
- Dial or joystick position with one or more potentiometers
- Ambient light levels with either a light-dependent resistor or a photodiode
- Surface infrared reflectivity with an infrared LED and phototransistor
- Pressure with capacitor plates and a compressible dielectric
- Liquid salinity with metal probes

RC Decay Circuit

RC decay measurements are typically performed by charging a capacitor (C) and then monitoring the time it takes the capacitor to discharge through a resistor (R). In most RC decay circuits, one of the values is fixed, and the other varies with an environmental variable. For example, the circuit in Figure 1 is used to measure a potentiometer knob's position. The value of C is fixed at 0.01 μ F, and the value of R varies with the position of the potentiometer's adjusting knob (the environmental variable).

- ✓ Build the circuit shown in Figure 1 on your PE Platform. This circuit and all others in this lab are in addition to the basic Propeller circuit built in the Setup and Testing lab.

Figure 1: RC Decay Parts and Circuit



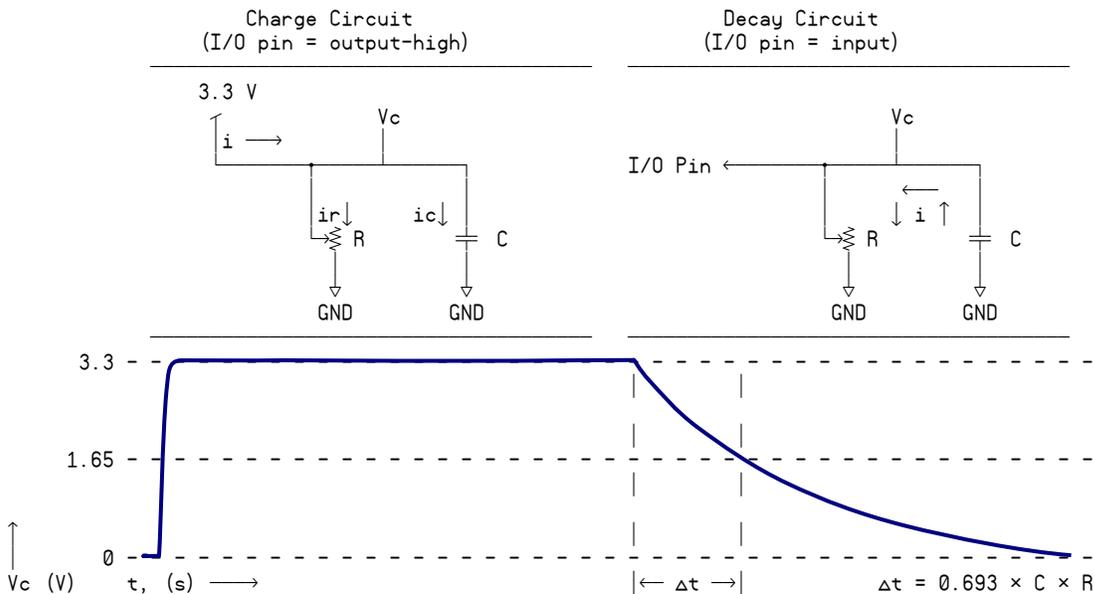
Measuring RC Decay

Before taking the RC decay time measurement, the Propeller chip needs to set the I/O pin connected to the circuit to output-high. This charges the capacitor up to 3.3 V as shown on the left side of Figure 2. Then, the Propeller chip starts the RC decay measurement by setting the I/O pin to input, as shown on the right side of Figure 2. When the I/O pin changes to input, the charge built up in the capacitor drains through the variable resistor. The time it takes the capacitor to discharge from 3.3 V down to the I/O pin's 1.65 V threshold is:

$$\Delta t = 0.693 \times C \times R$$

Since 0.693 and C are constants, the time Δt it takes for the circuit to decay is directly proportional to R, the variable resistor's resistance.

Figure 2: RC Charge and Decay Circuits and Voltages



Where is the current-limiting series resistor?

The Propeller chip's I/O pin driver circuits do not need to be protected from the sudden initial current spike that results when the I/O pin is taken from either output-low or input to output-high. The I/O pins' output capacity and current-limiting characteristics prevent any damage from occurring.



If you try to use this circuit with a different microcontroller, you will probably need to include a current-limiting resistor between the I/O pin and the RC circuit. Make sure that it is large enough to prevent the I/O pin from getting damaged. The decay time won't be linear because the voltage divider created by the second resistor causes the RC decay measurement's starting voltage to vary. Choosing an R in the RC circuit that is very large compared to the series resistor will help the decay time more closely resemble a linear behavior.

Positive Detector Mode

In positive detector mode, the Propeller chip's counter module monitors an I/O pin, and adds FRQ to PHS for every clock tick in which the pin is high. To make the PHS register accumulate the number of clock ticks in which the pin is high, simply set the counter module's FRQ register to 1. For measuring RC decay, the counter module should start counting (adding FRQ = 1 to PHS) as soon as the I/O pin is changed from output-high to input. After the signal level decays below the I/O pin's 1.65 V logic threshold, the module no longer adds FRQ to PHS, and what's stored in PHS is the decay time measurement in system clock ticks.

One significant advantage to using a counter module to measure RC decay is that the cog doesn't have to wait for the decay to finish. Since the counter automatically increments PHS with every clock tick in which the pin is high, the program is free to move on to other tasks. The program can then get the value from the PHS register whenever it's convenient.

Configuring a Counter Module for "POS detector" Mode

Figure 3 shows excerpts from the Propeller Library's CTR object's Counter Mode Table. The CTR object has counter module information and a code example that generates square waves. The CTR object's Counter Mode Table lists the 32 counter mode options, seven of which are shown below. The mode we will use for the RC decay measurement is positive detector, shown as "POS detector" in the table excerpts.

Figure 3: Excerpts from the CTR.spin's Counter Mode Table

CTRMODE	Description	Accumulate FRQ to PHS	APIN output*	BPIN output*
%00000	Counter disabled (off)	0 (never)	0 (none)	0 (none)
.
%01000	POS detector	A ¹	0	0
%01001	POS detector w/feedback	A ¹	0	!A ¹
%01010	POSEDGE detector	A ¹ & !A ²	0	0
%01011	POSEDGE detector w/feedback	A ¹ & !A ²	0	!A ¹
.
%11111	LOGIC always	1	0	0

* must set corresponding DIR bit to affect pin

A¹ = APIN input delayed by 1 clock
A² = APIN input delayed by 2 clocks
B¹ = BPIN input delayed by 1 clock

Notice how each counter mode in Figure 3 has a corresponding 5-bit CTRMODE code. For example, the code for "POS detector" is %01000. This value has to be copied to a bit field within the counter module's CTR register to make it function in "POS detector" mode. Figure 4 shows the register map for the `ctra` and `ctrb` registers. Notice how the register map names bits 31..26 CTRMODE. These are the bits that the 5 bit mode code from Figure 3 have to be copied to to make a counter module operate in a particular mode.

Like the `dira`, `outa` and `ina` registers, the `ctra` and `ctrb` registers are bit-addressable, so the procedure for setting and clearing bits in this register is the same as it would be for a group I/O pin operations with `dira`, `outa`, or `ina`. For example, here's a command to make Counter A a "POS detector":

```
ctra[30..26] := %01000
```

Figure 4: CTRA/B Register Map from CTR.spin

bits	31	30..26	25..23	22..15	14..9	8..6	5..0
Name	—	CTRMODE	PLLDIV	————	BPIN	———	APIN

 **The Counter Mode Table and CTRA/B Register Map** appear in the Propeller Library's CTR object, and also in the *Propeller Manual's* CTRA/B section, located in the Spin Reference chapter. APIN and BPIN are I/O pins that the counter module might control, monitor, or not use at all, depending on the mode.

Notice also in Figure 4 how there are bit fields for PLLDIV, BPIN, and APIN. PLLDIV is short for "phase-locked loop divider" and is only used for PLL counter modes, which can synthesize high-frequency square waves (more on this later). APIN (and BPIN for two-pin modes) have to store the I/O pin numbers that the counter module will monitor/control. In the case of the Counter A module set to positive detector mode, `frqa` gets added to `phsa` based on the state of APIN during the previous clock. (See the A¹ reference and footnote in Figure 3.) So the APIN bit field needs to store the value 17 since P17 will monitor the RC circuit's voltage decay. Here's a command that sets bits 5..0 of the `ctra` register to 17:

```
ctra[5..0] := 17
```

Remember that `frqa` gets added to `phsa` with every clock tick where APIN was high. To make the counter module track how many clock ticks the pin is high, simply set `frqa` to 1:

```
frqa := 1
```

At this point, the `phsa` register gets 1 added to it for each clock tick in which the voltage applied to P17 is above the Propeller chip's 1.65 V logic threshold. The only other thing you have to do before triggering the decay measurement is to clear the `phsa` register.

In summary, configuring the counter module to count clock ticks when an I/O pin is high takes three steps:

- 1) Store %01000 in the CTR register's mode bit field:

```
ctra[30..26] := %01000
```

- 2) Store the I/O pin number that you want monitored in the CTR register's APIN bit field:

```
ctra[5..0] := 17
```

- 3) Store 1 in the FRQ register so that the `phsa` register will get 1 added to it for every clock tick that P17 is high:

```
frqa := 1
```

1 isn't the only useful FRQ register value. Other FRQ register values can also be used to prescale the sensor input for calculations or even for actuator outputs. For example, FRQ can instead be set to `clkfreq/1_000_000` to count the decay time in microseconds.

```
frqa := clkfreq/1_000_000
```

This expression works for Propeller chip system clock frequencies that are common multiples of 1 MHz. For example, it would work fine with a 5 MHz crystal input, but not with a 4.096 MHz crystal since the resulting system clock frequency would not be an exact multiple of 1 MHz.

One disadvantage of larger FRQ values is that the program can not necessarily compensate for the number of clock ticks between clearing the PHS register and setting the I/O pin to input. A command that compensates for this source of error can easily be added after the clock tick counting is finished, and it can be followed by a second command that scales to a convenient measurement unit, such as microseconds.



Measure input or output signals. This counter mode can be used to measure the duration in which an I/O pin sends a high signal as well as the duration in which a high signal applied to the I/O pin. The only difference is the direction of the I/O pin when the measurement is taken.

“Counting” the RC Decay Measurement

Before the RC decay measurement, the capacitor should be charged. Here's a piece of code that sets P17 to output-high, then waits for 10 μ s, which is more than ample for charging the capacitor in the Figure 1 RC network.

```
dira[17] := outa[17] := 1
waitcnt(clkfreq/100_000 + cnt)
```

To start the decay measurement, clear the PHS register, and then set the I/O pin that's charging the capacitor to input:

```
phsa~
dira[17]~
```

After clearing `phsa` and `dira`, the program is free to perform other tasks during the measurement. At some later time, the program can come back and copy the `phsa` register contents to a variable. Of course, the program should make sure to wait long enough for the decay measurement to complete. This can be done by polling the clock, waiting for the decay pin to go low, or performing a task that is known to take longer than the decay measurement.

To complete the measurement, copy the `phsa` register to another variable and subtract 624 from it to account for the number of clock ticks between `phsa~` and `dira[17]~`. The result of this subtraction can also be set to a minimum of 0 with `#> 0`. This will make more sense than -624 when the resistance is so low that it pulls the I/O pin's output-high signal low.

```
time := (phsa - 624) #> 0
```



Where did 624 come from?

The number of clock ticks between `phsa~` and `dira[17]~` was determined by replacing the 0.01 μ F capacitor with a 100 pF capacitor and finding the lowest value before zero was returned. In the test program, `time := phsa` replaces `time := (phsa - 624) #> 0`, and the lowest measurable value was 625.

Example Object Measures RC Decay Time

The TestRcDecay object applies the techniques just discussed to measure RC decay in a circuit with variable resistance controlled by the position of a potentiometer's adjusting knob. The program displays a "working on other tasks" message after starting the RC decay measurement to demonstrate that the counter module automatically increments the **phsa** register until the voltage applied to P17 decays below the Propeller chip's 1.65 V I/O pin threshold. The program can then check back at a later time to find out the value stored in **phsa**.

- ✓ Open the TestRcDecay.spin object. It will call methods in FullDuplexSerialPlus.spin, so make sure they are both saved in the same folder.
- ✓ Load TestRcDecay.spin into the Propeller chip.
- ✓ Open PropellerCOM. (See Object's Lab for setup instructions.)
- ✓ Try moving the potentiometer knob to various positions and note the time values. They should vary in proportion to the potentiometer's adjusting knob across its range of motion.
- ✓ Remember to disconnect HyperTerminal before loading the next object into the propeller chip.

```
'' TestRcDecay.spin
'' Test RC Decay circuit decay measurements.

CON

  _clkmode = xtall1 + pll116x          ' System clock → 80 MHz
  _xinfreq = 5_000_000

OBJ

  Debug: "FullDuplexSerialPlus"      ' Use with HyperTerminal to display values

PUB Init

  ' Start serial communication, and wait 2 s for user to connect to HyperTerminal.

  Debug.Start(31, 30, 0, 57600)
  waitcnt(clkfreq * 2 + cnt)

  ' Configure counter module.

  ctra[30..26] := %01000              ' Set mode to "POS detector"
  ctra[5..0] := 17                    ' Set APIN to 17 (P17)
  frqa := 1                           ' Increment phsa by 1 for each clock tick

  main                                ' Call the Main method

PUB Main | time
'' Repeatedly takes and displays P17 RC decay measurements.
  repeat

    ' Charge RC circuit.

    dira[17] := outa[17] := 1         ' Set pin to output-high
    waitcnt(clkfreq/100_000 + cnt)    ' Wait for circuit to charge

    ' Start RC decay measurement. It's automatic after this...

    phsa~                             ' Clear the phsa register
    dira[17]~                          ' Pin to input stops charging circuit

    ' Optional - do other things during the measurement.
```

```

Debug.str(String(10, 10, 13, "working on other tasks"))
repeat 10
  Debug.tx(".")
  waitcnt(clkfreq/30 + cnt)

  ` Measurement has been ready for a while.  Adjust ticks between phsa~ & dira[17]~.

time := (phsa - 624) #> 0

  ` Display Result

Debug.Str(String(10, 13, "time = "))
Debug.Dec(time)
waitcnt(clkfreq/2 + cnt)

```

Two Concurrent RC Decay Measurements

Since the counter module keeps track of high time after the decay starts, it is possible to take two concurrent RC decay measurements on different pins. Let's do so with P25 and a light-dependent resistor (abbreviated LDR and also called a photoresistor) instead of a potentiometer. The second measurement will start later than the first since the `phsb~` and `dira[25]~` commands will follow `dira[17]~`. However, the decays can occur in parallel, and while the decays last, the cog continues to execute other commands.

- ✓ Build the circuit shown in Figure 5.
- ✓ Modify a copy of `TestRcDecay.spin` so that it can measure the circuits from Figure 1 and Figure 5 concurrently.

Be careful, you'll need to add commands that set the values of `ctrb`, `frqb`, and `phsb`, but the DIR register should be `dira`, not `dirb`. `dirb` is reserved for I/O pins 32..63 in a module with 64 I/O pins. Also, `phsb~` and `dira[25]~` should come immediately after `dira[17]~`.

Figure 5: Second RC Decay Parts and Circuit

Parts List	Schematic
(1) Photoresistor (1) Capacitor - 0.1 μ F (misc) Jumper wires	<p>The schematic shows a horizontal line representing a circuit trace. From the left end of this line, an arrow points to the label 'P25'. From the point where the line reaches the LDR, a vertical line goes down to a resistor symbol labeled 'LDR', which then continues down to 'GND'. From the point where the line reaches the capacitor, a vertical line goes down to a capacitor symbol labeled '0.1 μF', which then continues down to 'GND'.</p>

D/A Conversion - Controlling LED Brightness with Duty Mode

A counter module in duty mode allows you to control a signal that can be used for digital to analog conversion with the FRQ register. Although the signal switches rapidly between high and low, the average time it is high (the duty) is determined by the ratio of the FRQ register to 2^{32} .

$$\text{duty} = \frac{\text{pin high time}}{\text{time}} = \frac{\text{FRQ}}{4_294_967_296} \quad \text{Eq. 1}$$

For D/A conversion, let's say the program has to send a 0.825 V signal. That's 25% of 3.3 V, so a 25% duty signal is required. Figuring out the value to store in the FRQ register is simple. Just set duty = 0.25 and solve for FRQ.

$$0.25 = \frac{\text{FRQ}}{4_294_967_296} \quad \rightarrow \quad \text{FRQ} = 1_073_741_824$$

You can also use Eq. 1 to figure out what duty signal an object is sending. Let's say 536_870_912 is stored in a counter module's FRQ register, and its CTR register has it configured to duty mode.

$$\text{duty} = \frac{536_870_912}{4_294_967_296} = 0.125$$

On a 3.3 V scale, that would resolve to 0.375 V. Again, the great thing about counters is that they can do their jobs without tying up a cog. So, the cog will still be free to continue executing commands while the counter takes care of maintaining the D/A conversion duty signal.

How Duty Mode Works

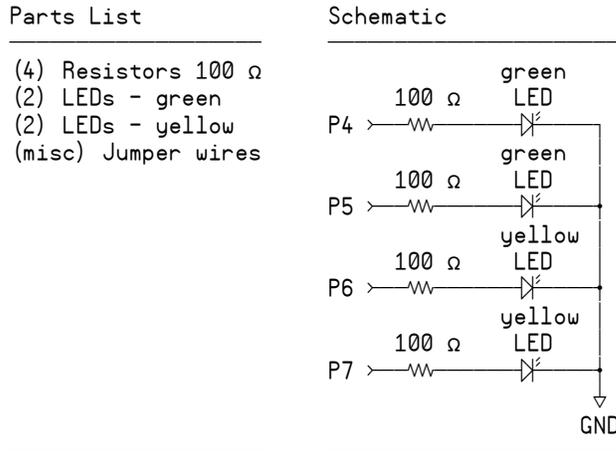
Each time FRQ gets added to PHS, the counter module's phase adder (that adds FRQ to PHS with every clock tick) either sets or clears a carry flag. This carry operation is similar to a carry operation in decimal addition. Let's say you are allowed 3 decimal places, and you try to add two values that add up to more than 999. Some value would normally be carried from the hundreds to the thousands slot. The binary version of addition-with-carry applies when the FRQ register gets added to the PHS register when the result is larger than $2^{32} - 1$. If the result exceeds this value, the PHS adder's carry flag (think of it as the PHS registers "bit 32") gets set.

The interesting thing about this carry flag is that the amount of time it is 1 is proportional to the value stored in the FRQ register divided by 2^{32} . In single-ended duty mode, the counter module's phase adder's carry bit controls an I/O pin's output state. Since the time in which the phase adder's carry bit is 1 is proportional to $\text{FRQ}/2^{32}$, so is the I/O pin's output state. The I/O pin may rapidly switch between high and low, but the average pin high time is determined by the FRQ-to- 2^{32} ratio shown in Eq. 1 above.

Parts and Circuit

Yes, it's back to LEDs for just a little while, and then we'll move on to other circuits. Previous labs used LEDs to indicate I/O pin states and timing. This portion of this lab will use duty mode for D/A conversion to control LED brightness.

Figure 6: LED Circuit for Brightness Control with Duty Signals



✓ Add the circuit shown in Figure 6 to your PE Platform, leaving the RC decay circuit in place.

Configuring a Counter for Duty Mode

Figure 7 shows more entries from the CTR object's and Propeller Manual's Counter Mode Table. There are two types of duty modes, single-ended and differential. With single-ended, the APIN mirrors the state of the phase adder's carry bit. So, if FRQ is set to the 1_073_741_824 value calculated earlier, the APIN will be high $\frac{1}{4}$ of the time. An LED circuit receiving this signal will appear to glow at $\frac{1}{4}$ of its full brightness. In differential mode, the APIN signal still matches the phase adder's carry bit, while the BPIN is the opposite value. So whenever the phase adder's carry bit (and APIN) are 1, BPIN is 0, and vice-versa. If FRQ is set to 1_073_741_824, APIN would still cause an LED to glow at $\frac{1}{4}$ brightness while BPIN will glow at $\frac{3}{4}$ brightness.

Figure 7: More Excerpts from the CTR.spin's Counter Mode Table

CTRMODE	Description	Accumulate FRQ to PHS	APIN output*	BPIN output*
%00000	Counter disabled (off)	0 (never)	0 (none)	0 (none)
.
%00110	DUTY single-ended	1	PHS-Carry	0
%00111	DUTY differential	1	PHS-Carry	!PHS-Carry
.
%11111	LOGIC always	1	0	0

* must set corresponding DIR bit to affect pin

A¹ = APIN input delayed by 1 clock
A² = APIN input delayed by 2 clocks
B¹ = BPIN input delayed by 1 clock

Figure 8 is a repeat of Figure 3. This time, the counter module will be configured to duty mode instead of positive detector mode. From Figure 7, we know that the value stored in the CTR register's CTRMODE bit field has to be either %00110 (single-ended) or %00111 (differential). Then, the APIN (and optionally BPIN) bit fields have to be set to the I/O pins that will transmit the duty signals.

Figure 8: CTRA/B Register Map from CTR.spin

bits	31	30..26	25..23	22..15	14..9	8..6	5..0
Name	—	CTRMODE	PLLDIV	—	BPIN	—	APIN

The RC decay application set the FRQ register to 1, and the result was that 1 got added to PHS for every clock tick in which the pin being monitored was high. In this application, the FRQ register gets set to values that control the high time of the duty signal applied to an I/O pin. There is no condition for adding with duty mode; FRQ gets added to PHS every clock tick.

Setting up a Duty Signal

Here are the steps for setting a duty signal with a counter:

- (1) Set the CTR register's CTRMODE bit field to choose duty mode.
- (2) Set the CTR register's APIN bit field to choose the pin.
- (3) (Optional) set the CTR register's BPIN field if CTRMODE is differential.
- (4) Set the I/O pin(s) to output.
- (5) Set the FRQ register to a value that gives you the percent duty signal you want.

Example – Send a 25% single-ended duty signal to P4 Using Counter A.

(1) Set the CTR register's CTRMODE bit field to choose duty mode. Remember that bits 30..26 of the CTR register (shown in Figure 8) have to be set to the bit pattern selected from the CTRMODE list in Figure 7. For example, here's a command that configures the counter module to operate in single-ended duty mode:

```
ctra[30..26] := %00110
```

(2) Set the CTR register's APIN bit field to choose the pin. Figure 8 indicates that APIN is bits 5..0 in the CTR register. Here's an example that sets the `ctra` register's APIN bits to 4, which will control the green LED connected to P4.

```
ctra[5..0] := 4
```

We'll skip step (3) since the counter module is getting configured to single-ended duty mode and move on to:

(4) Set the I/O pin(s) to output.

```
dira[4]~~
```

(5) set the FRQ register to a value that gives you the duty signal you want. For ¼ brightness, use 25% duty. So, set the `frqa` register to 1_073_741_824 (calculated earlier).

```
frqa := 1_073_741_824
```

Tips for Setting Duty

Since the special purpose registers initialize to zero, `frqa` is 0, so 0 is repeatedly added to the PHS register, resulting on no LED state changes. As soon as the program sets the FRQ register to some fraction of 2^{32} , the I/O pin, and the LED, will start sending the duty signal.

Having 2^{32} different LED brightness levels isn't really practical, but 256 different levels will work nicely. One simple way to accomplish that is by declaring a constant that's $2^{32} \div 256$.

CON

```
scale = 16_777_216          '  $2^{32} \div 256$ 
```

Now, the program can multiply the `scale` constant by a value from 0 to 255 to get 256 different LED brightness levels. Now, if you want $\frac{1}{4}$ brightness, multiply `scale` by $\frac{1}{4}$ of 256:

```
frqa := 64 * scale
```

i

Time Varying D/A and Filtering: When modulating the value of `frqa` to send time varying signals, an RC circuit typically filters the duty signal. It's better to use a smaller fraction of the useable duty signal range, say 25% to 75% or 12.5% to 87.5%. By keeping the duty in this middle range, the D/A will be less noisy and smaller resistor R and capacitor C values can be used for faster responses. This is especially important for signals that vary quickly, like audio signals, which will be introduced in a different lab.

```
graph LR
    A[duty signal] --> R[R]
    R --> B[voltage]
    R --> C[C]
    C --> D[GND]
```

Duty Code Example

The `LedDutySweep` object demonstrates the steps for configuring a counter for duty mode and transmitting a duty signal with an I/O pin. It also sweeps a `duty` variable from 0 to 255 repeatedly, causing the P4 LED to gradually increase in brightness and then turn off.

- ✓ Load the `LedDutySweep` object into the Propeller chip and observe the effect.

```
''LedDutySweep.spin
''Cycle P4 LED from off, gradually brighter, full brightness.

CON

scale = 16_777_216          '  $2^{32} \div 256$ 

PUB TestDuty | pin, duty, mode

'Configure counter module.

ctra[30..26] := %00110      ' Set ctra to DUTY mode
ctra[5..0] := 4             ' Set ctra's APIN
frqa := duty * scale        ' Set frqa register

'Use counter to take LED from off to gradually brighter, repeating at 2 Hz.

dira[4]~~                  ' Set P5 to output

repeat                      ' Repeat indefinitely
repeat duty from 0 to 255   ' Sweep duty from 0 to 255
frqa := duty * scale        ' Update frqa register
```

```
waitcnt(clkfreq/128 + cnt)
```

```
' Delay for 1/128th s
```

Duty – Single Ended vs. Differential Modes

The LedDutySweep object uses the single-ended version of a counter module's duty mode. Differential is a second option for duty and several other counter modes. Differential signals are useful for getting signals across longer transmission lines, and are used in wired Ethernet, RS485, and certain audio signals.

When a counter module functions in differential mode, it uses one I/O pin to transmit the same signal that single-ended transmits, along with a second I/O pin that transmits the opposite polarity signal. For example, a counter module set to duty differential mode can send the opposite signal that P4 transmits on P5 or any other I/O pin. Whenever the signal on P4 is high, the signal on P5 is low, and visa versa. Try modifying a copy of LedDutySweep.spin so that it sends the differential signal on P5. Then, as the P4 LED gets brighter, the P5 LED will get dimmer. Here are the steps:

- ✓ Save a copy of the LedDutySweep object that you will modify.
- ✓ To set the counter module for “DUTY differential” mode, change `ctra[30..26] := %00110` to `ctra[30..26] := %00111`.
- ✓ Set the `ctra` module's BPIN bit field by adding the command `ctra[14..9] := 5`
- ✓ Set P5 to output so that the signal gets transmitted by the I/O pin with the command `dira[5]~~`.

Using Both A and B Counter Modules

Using both counter modules to display different LED brightnesses is also a worthwhile exercise. To get two counter modules sending duty signals on separate pins, try these steps:

- ✓ Save another copy of the original, unmodified LedDutySweep object.
- ✓ Add `ctrb[30..26] := %00110`.
- ✓ Assuming `ctrb` will control P6, add `ctrb[5..0] := 6`.
- ✓ Also assuming `ctrb` will control P6, add `dira[6]~~`.
- ✓ In the repeat duty from 0 to 255 loop, make `frqb` twice the value of `frqa` with the command `frqb := 2 * frqa`. This will cause the P6 LED to get bright twice as fast as the P4 LED.

Inside Duty Mode

Let's take a closer look at how this works by examining the 3-bit version. Since the denominator of the fraction is 2 raised to the number of bits in the register, a 3-bit version of FRQ would be divided by $2^3 = 8$:

$$\text{duty} = \frac{\text{pin high time}}{\text{time}} = \frac{\text{frq}}{8} \quad \text{(3-bit example)}$$

Let's say the carry bit needs to be high $\frac{3}{8}$ of the time. The 3-bit version of the FRQ register would have to store 3. The example below performs eight additions of 3-bit-FRQ to 3-bit-PHS using long-hand addition. The carry bit (that would get carried into bit-4) is highlighted with the \downarrow symbol whenever it's 1. Notice that out of eight PHS = PHS + FRQ additions, three result in set carry bits. So, the carry bit is in fact set $\frac{3}{8}$ of the time.

carry flag set		\downarrow						
		1 1	1 1	1 1	1 1 1	1	1 1 1	
3-bit frq	011	011	011	011	011	011	011	011
3-bit phs (previous)	+000	+011	+110	+001	+100	+111	+010	+101
3-bit phs (result)	011	110	001	100	111	010	101	000

Binary Addition works just like decimal addition when it's done "long hand". Instead of carrying a digit from 1 to 9 when digits in a particular column add up to a value greater than 9, binary addition carries a 1 if the result in a column exceeds 1.



Binary Result	
0 + 0	= 0
0 + 1	= 1
1 + 0	= 1
1 + 1	= 10 (0, carry the 1)
1 + 1 + 1	= 11 (1, carry the 1)

Special Purpose Registers

Each cog has a special purpose register array whose elements can be accessed with `spr[index]`. The index value lets you pick a given special purpose register. For example, you can set the value of `ctra` by assigning a value to `spr[8]`, or `ctrb` by assigning a value to `spr[9]`. Likewise, you can assign values to `frqa` and `frqb` by assigning values to `spr[10]` and `spr[11]`, or `phsa` and `phsb` by assigning values to `spr[12]` and `spr[13]`. A full list of the `spr` array elements can be found in the Propeller Manual.

- ✓ Look up `SPR` in the Spin Language reference section of the Propeller Manual, and review the `SPR` explanation and table of `SPR` array elements.

The advantage to using `SPR` array elements is that they are accessible by index values. Also, `ctrb`, `frqb`, and `phsb` are all one array element above `ctra`, `frqa`, and `phsa`. This makes it possible to choose between A and B counter registers by simply adding 1 to (or subtracting 1 from) the index value used to access a given `SPR` register. This in turn makes it possible to eliminate condition statements for deciding which counter module to use and it also makes it possible to initialize and update counter modules within looping structures.

One drawback to special purpose registers is that they are not bit-addressable. For example, the commands `ctra[30..26] := %00110` and `ctra[5..0] := 4` have to be coded differently for `spr[8]`, which is the `ctra` special purpose array element. The most convenient way to accomplish these two commands in Spin language with the `SPR` array is like this:

```
spr[8] := (%00110 << 26) + 4
```

In the command above, the bit pattern `%00110` is shifted left by 26 bits, which accomplishes the same thing as `ctra[30..26] := %00110`, and adding 4 to it without any shifting has the same effect as `ctra[5..0] := 4`. Here is the equivalent addition:

```

%00110 << 26      %00011000000000000000000000000000
+ 4                %0000000000000000000000000000100
-----
spr[8]             %000110000000000000000000000000100

```

Let's say that the application will send duty signals on P4 and P5. A loop that could set up these I/O pins for duty signals might look like this:

```

repeat module from 0 to 1                                ' 0 is A module, 1 is B.
  spr[8 + module] := (%00110 << 26) + (4 + module)
  dira[4 + module]~~

```

The first time through the loop, `module` is 0, so the value 4 gets stored in bits 5..0 of `spr[8]` and `dira[4 + module]~~` becomes `dira[4]~~`. The second time through the loop, `module` is 1, so 5 gets stored in bits 4..0 of `spr[9]`, and `dira[4 + module]~~` becomes `dira[5]~~`.

When using counters in objects, the pins will probably get passed as parameters. If the parameters hold the pin values, they might not be contiguous or linked by some mathematical relationship. A handy way to keep a list of non-contiguous pins if you're not expecting them to come from elsewhere would be a `lookup` or `lookupz` command. Given an index value, both `lookup` and `lookupz` return an element in a list. For example the command `value := lookup(index: 7, 11, 13, 1)` will store 7 in `value` if `index` is 1, 11 in `value` if `index` is 2, and so on. If `index` exceeds the length of the lookup table, the `lookup` command stores 0 in `value`. The same command with `lookupz` will store 7 in `value` if `index` is 0, or 11 in `value` if `index` is 1, and so on. Like `lookup`, `lookupz` returns 0 if `index` exceeds the list length.

Here is a version of the `repeat` loop that uses `lookupz` to store a list of non-contiguous pins and load them into the 5..0 bits of the cog's A and B CTR special purpose registers (`spr[8]` and `spr[9]`). Notice how the `lookupz` command stores 4 and 6. The first time through the loop, `module` is 0, so 4 gets stored in `apin`, which in turn gets stored in bits 5..0 of `spr[8]` and sets bit 4 in the `dira` register. The second time through the loop, `module` is 1, so 6 gets stored in `apin`, which in turn gets stored in bits 5..0 of `spr[9]` and bit 6 of `dira` gets set.

```

repeat module from 0 to 1                                ' 0 is A module, 1 is B.
  apin := lookupz (module: 4, 6)
  spr[8 + module] := (%00110 << 26) + (apin)
  dira[apin]~~

```

The `LedSweepWithSpr` object does the same job as the `LedDutySweep` code you modified in the "Using Both A and B Counter Modules" section. The difference is that it performs all counter module operations using the SPR array instead of referring to the A and B module's CTR, FRQ and PHS registers.

- ✓ Compare your copy of `LedDutySweep` that sweeps both counters against the code in `LedSweepWithSpr`.
- ✓ Run `LedSweepWithSpr` and use the LEDs to verify that it controls two separate duty signals.

```

''LedSweepWithSpr.spin
''Cycle P4 and P5 LEDs through off, gradually brighter, brightest at different rates.

CON

  scale = 16_777_216                                ' 232 ÷ 256

PUB TestDuty | apin, duty[2], module

```

```

'Configure both counter modules with a repeat loop that indexes SPR elements.

repeat module from 0 to 1                                     ' 0 is A module, 1 is B.
  apin := lookupz (module: 4, 6)
  spr[8 + module] := (%00110 << 26) + apin
  dira[apin]~~

'Repeat duty sweep indefinitely.

repeat
  repeat duty from 0 to 255                                   ' Sweep duty from 0 to 255
    duty[1] := duty[0] * 2                                    ' duty[1] twice as fast
    repeat module from 0 to 1
      spr[10 + module] := duty[module] * scale                ' Update frqa register
      waitcnt(clkfreq/128 + cnt)                               ' Delay for 1/128th s

```

Modifying LedSweepWithSpr for Differential Signals

Try updating the LedSweepWithSpr object so that it does two differential signals, one on P4 and P5, and the other on P6 and P7.

- ✓ Make a copy of LedSweepWithSpr.spin.
- ✓ Add a bpin variable to the TestDuty method's local variable list.
- ✓ Add the command `bpin := lookupz (module: 5, 7)` just below the command that assigns the apin value with a `lookup` command.
- ✓ Change `spr[8 + module] := (%00110 << 26) + apin` to `spr[8 + module] := (%00111 << 26) + (bpin << 9) + apin`.
- ✓ Add `dira[bpin]~~` immediately after `dira[apin]~~`.
- ✓ Load the modified copy of LedSweepWithSpr.spin into the Propeller chip and verify that it sends two differential duty signals.

Generating Piezospeaker Tones with NCO Mode

NCO stands for *numerically controlled oscillator*. If a counter module is configured for the single-ended version of this mode, it will make an I/O pin send a square wave. Assuming `clkfreq` remains constant, the frequency of this square wave is “numerically controlled” by a value stored in a given cog's counter module's FRQ register.

- ✓ Assemble the parts list and build the schematic shown in Figure 9.

Figure 9: Audio Range NCO Parts List and Circuits

Parts List	Schematic
(2) Piezospeakers (misc) Jumper wires	Piezospakers

Counter Module in NCO Mode

When configured to single-ended NCO mode, the counter module does two things:

- The FRQ register gets added to the PHS register every clock tick.
- Bit 31 of the PHS register controls the state of an I/O pin.

When bit 31 of the PHS register is 1, the I/O pin it controls sends a high signal, and when it is 0, it sends a low signal. If `clkfreq` remains the same, the fact that FRQ gets added to PHS every clock tick determines the rate at which the PHS register's bit 31 toggles. This in turn determines the square wave frequency transmitted by the pin controlled by bit 31 of the PHS register.

Given the system clock frequency and an NCO frequency that you want the Propeller to transmit, you can calculate the necessary FRQ register value with this equation:

$$\text{FRQ register} = \text{PHS bit 31 frequency} \times \frac{2^{32}}{\text{clkfreq}} \quad \text{Eq. 2}$$

Example:

What value does `frqa` have to store to make the counter module transmit a 2093 Hz square wave if the system clock is running at 80 MHz? (If this were a sine wave, it would be a C7, a C note in the 7th octave.)

For the solution, start with Eq. 2. Substitute 80_000_000 for `clkfreq` and 2093 for `frequency`.

$$\begin{aligned} \text{frqa} &= 2093 \times 2^{32} \div 80\,000\,000 \\ \text{frqa} &= 2093 \times 53.687 \\ \text{frqa} &= 112\,367 \end{aligned}$$

Table 1 shows other notes in the 6th octave and their FRQ register values at 80 MHz. The sharp notes are for you to calculate. Keep in mind that these are the square wave versions. In another lab, we'll use objects that digitally synthesize sine waves for truer tones.

Table 1: Notes, Frequencies, and FRQA/B Register Values for 80 MHz					
Note	Frequency (Hz)	FRQA/B Register	Note	Frequency (Hz)	FRQA/B Register
C6	1046.5	56_184	G6	1568.0	84_181
C6#	1107.8		G6#	1661.2	
D6	1174.7	63_066	A6	1760.0	94_489
D6#	1244.5		A6#	1864.7	
E6	1318.5	70_786	B6	1975.5	105_629
F6	1396.9	74_995	C7	2093.0	112_367
F6#	1480.0				

Eq. 3 can also be rearranged to figure out what frequency gets transmitted by an object given a value the object stores in its FRQ register:

$$\text{PHS bit 31 frequency} = \frac{\text{clkfreq} \times \text{FRQ register}}{2^{\frac{32}{2}}} \quad \text{Eq. 3}$$

Example: An object has its cog's Counter B operating in single-ended NCO mode, and it stores 70_786 in its `frqb` register. The system clock runs at 80 MHz. What frequency does it transmit?

We already know the answer from Table 1, but here it is with Eq. 3

$$\text{PHS bit 31 frequency} = \frac{80_000_000 \times 70_786}{2^{\frac{32}{2}}} = 1318 \text{ Hz}$$

Configuring a Counter Module for NCO Mode

Figure 10 shows the NCO mode entries in the CTR object's Counter Mode table. Note that it is called NCO/PWM mode in the table, you may see that occasionally. PWM is actually an application of NCO mode that will be explored in the PWM section on page 35. Like DUTY mode, NCO mode has a single-ended and differential options. Single-ended causes a signal that matches bit 31 of the PHS register to be transmitted by the APIN. Differential mode sends the same signal on APIN along with an inverted version of that signal on BPIN.

Figure 10: NCO Excerpts from the CTR Object's Counter Mode Table

CTRMODE	Description	Accumulate FRQ to PHS	APIN output*	BPIN output*
%00000	Counter disabled (off)	0 (never)	0 (none)	0 (none)
.
%00100	NCO/PWM single-ended	1	PHS[31]	0
%00101	NCO/PWM differential	1	PHS[31]	!PHS[31]
.
%11111	LOGIC always	1	0	0

* must set corresponding DIR bit to affect pin

A¹ = APIN input delayed by 1 clock
A² = APIN input delayed by 2 clocks
B¹ = BPIN input delayed by 1 clock

The steps for configuring the counter module for NCO mode are similar to the steps for DUTY mode. The CTR register's CTRMODE, APIN (and BPIN in differential mode) bit fields have to be set. Then, the FRQ register gets a value that sets the NCO frequency. As with other output examples, the I/O pins used by the counter module have to be set to output.

Remember that the steps for configuring the counter module are similar to the previous two modes (POS detector and DUTY) but the functional result is again very different. In DUTY mode, the phase adder's carry flag ("bit 32" of the PHS register) determined the I/O pin's state, which in turn resulted in a duty signal that varied with the value stored by the FRQ register. In NCO mode, bit 31 of the PHS register controls the I/O pin, which results in a square wave whose frequency is determined by the value stored in the FRQ register.

Here are the steps for configuring a counter module to NCO mode.

- (1) Configure the CTRA/B register
- (2) Set the FRQA/B register
- (3) Set the I/O pin to output

1) Configure the CTRA/B register:

Here is an example that sets Counter A to "NCO single-ended" mode, with the signal transmitted on P27. To do this, set `ctra[30..26]` to `%00100`, and `ctra[5..0]` to `27`.

```
ctra[30..26] := %00100
ctra[5..0] := 27
```

2) Set the FRQA/B register:

Here is an example for the square wave version of the C7 note:

```
frqa := 112_367
```

3) Set the I/O pin to output:

Since it's P27 that's sending the signal, make it an output:

```
dira[27]~~
```

After starting the counter module, it runs independently. The code in the cog can forget about it and do other things, or monitor/control/modify the counter's behavior as needed.

Square Wave Example

The SquareWaveTest object below plays the square wave version of C in the 7th octave for 1 second.

- ✓ Examine the SquareWaveTest object and compare it to steps 1 through 4 just discussed.
- ✓ Load the SquareWaveTest object into the Propeller chip. Run it and verify that it plays a tone.
- ✓ Change `frqa := 112_367` to `frqa := 224_734`. That'll be C8, the C note in the next higher octave.
- ✓ Load the modified object into the Propeller chip. This time, the note should play at a higher pitch.

```
``SquareWaveTest.spin
``Send 2093 Hz square wave to P27 for 1 s with counter module.

CON

_clkmode = xtal1 + pll16x          ' Set up clkfreq = 80 MHz.
_xinfreq = 5_000_000
```

```

PUB TestFrequency

'Configure ctra module
ctr[30..26] := %00100          ' Set ctra for "NCO single-ended"
ctr[5..0] := 27                ' Set APIN to P27
frqa := 112_367                ' Set frqa for 2093 Hz (C7 note) using:
                                ' FRQA/B = frequency × (232 ÷ clkfreq)

'Broadcast the signal for 1 s
dira[27]~~                    ' Set P27 to output
waitcnt(clkfreq + cnt)        ' Wait for tone to play for 1 s

```

Stopping (and restarting) the Signal

In the SquareWaveTest object, the cog runs out of commands, so the tone stops because the program ends. In many cases, you will want to stop and restart the signal. The three simplest ways to stop (and resume) signal transmission are:

- (1) **Change the Direction of the I/O pin to input.** In the SquareWaveTest object, this could be done with either `dira[27] := 0` or `dira[27]~` when the program is ready to stop the signal. (To restart the signal, use either `dira[27] := 1` or `dira[27]~~`.)
- (2) **Stop the counter module by clearing CTR bits 30..26.** In the SquareWaveTest object, this can be accomplished with `ctr[30..26] := 0`. Another way to do it is by setting all the bits in the `ctr` register's CTRMODE bitfield to zero with `ctr[30..26]~`. In either case, the I/O pin is still an output, and its output state might be high or low. Later, we'll examine a way to make sure the signal ends when the I/O pin is transmitting a low signal. (To restart the signal, copy %00100 back into `ctr[30..26]`.)
- (3) **Stop adding to PHS by setting FRQ to 0.** In the SquareWaveTest object, this could be done with either `frqa := 0` or `frqa~`. The counter would keep running, but since it would add zero to `phsa` with each clock tick, bit 31 of `phsa` wouldn't change, so the I/O pin would also stop toggling. Like stopping the counter, the I/O pin would hold whatever output state it had at the instant `frqa` is cleared. (To restart the signal, use `frqa := 112_367`.)

The Staccato object toggles the I/O pin between output and input to cause the 2.093 kHz tone to start and stop at 15 Hz for 1 s. It uses approach (1) for stopping and restarting the signal. Your job will be to modify two different copies of the code to use approaches 2 and 3.

- ✓ Load Staccato.spin into the Propeller chip and verify that it chirps at 15 Hz for 1 s.
- ✓ Make two copies of the program.
- ✓ Modify one copy so that it uses approach 2 for starting and stopping the signal.
- ✓ Modify the other copy so that it uses approach 3 for starting and stopping the signal.

```

''Staccato.spin
''Send 2093 Hz beeps in rapid succession (15 Hz for 1 s).

CON

_clkmode = xtall1 + pll16x      ' System clock → 80 MHz
_xinfreq = 5_000_000

PUB TestFrequency

'Configure ctra module
ctr[30..26] := %00100          ' Set ctra for "NCO single-ended"
ctr[8..0] := 27                ' Set APIN to P27
frqa := 112_367                ' Set frqa for 2093 Hz (C7 note):

```

```

`Ten beeps on/off cycles in 1 second.
repeat 30
  !dira[27]
  waitcnt(clkfreq/30 + cnt)
  ` Set P27 to output
  ` Wait for tone to play for 1 s

`Program ends, which also stops the counter module.

```



Use F10 and F11 to easily compare programs:

It is convenient to put the original `Staccato.spin` into the EEPROM with F11, then use F10 when you test your modifications. After running your new program, you can then press and release the PE Platform's reset button to get an instant audio comparison.

Playing a List of Notes

`DoReMi.spin` is an example where the counter module is used to play a series of notes. Since it isn't needed for anything else in the meantime, the I/O pin that sends the square wave signal to the piezospeaker is set to input during the $\frac{1}{4}$ stops between notes. bit 31 of the `phsa` register still toggles at a given frequency during the quarter stop, but the pseudo-note doesn't play.

The `frqa` register values are stored in a `DAT` block with the directive:

```

DAT
...
notes long 112_367, 126_127, 141_572, 149_948, 168_363, 188_979, 212_123, 224_734

```

A `repeat` loop that sweeps a variable named `index` from 0 to 7 is used to retrieve and copy each of these notes to the `frqa` register. The loop copies each successive value from the notes sequence into the `frqa` register with this command:

```

repeat index from 0 to 7
  `Set the frequency.
  frqa := long[@notes][index]
  ...

```

- ✓ Load the `DoReMi` object into the Propeller chip and observe the effect.

```

`DoReMi.spin
`Play C6, D6, E6, F6, G6, A6, B6, C7 as quarter notes quarter stops between.

CON
  _clkmode = xtall + pll16x
  _xinfreq = 5_000_000
  ` System clock → 80 MHz

PUB TestFrequency | index
  `Configure ctra module
  ctra[30..26] := %00100
  ctra[8..0] := 27
  frqa := 0
  ` Set ctra for "NCO single-ended"
  ` Set APIN to P27
  ` Don't play any notes yet

  repeat index from 0 to 7

  frqa := long[@notes][index]
  `Set the frequency.

  `Broadcast the signal for 1/4 s
  dira[27]~~
  waitcnt(clkfreq/4 + cnt)
  ` Set P27 to output
  ` Wait for tone to play for 1/4 s

```

```

dira[27]~                               '1/4 s stop
waitcnt(clkfreq/4 + cnt)

DAT
'80 MHz frqa values for square wave musical note approximations with the counter module
'configured to NCO:
      C6      D6      E6      F6      G6      A6      B6      C7
notes long 56_184, 63_066, 70_786, 74_995, 84_181, 94_489, 105_629, 112_528

```

Counter NCO Mode Example with bit 3 Instead of bit 31

In NCO mode, the I/O pin's output state is controlled by bit 31 of the PHS register. However, the on/off frequency for any bit in a variable or register can be calculated using Eq. 4 and assuming a value is repeatedly added to it at a given rate:

$$\text{frequency} = (\text{value} \times \text{rate}) \div 2^{\text{bit} + 1} \quad \text{Eq. 4}$$

Here is an example that can be done on scratch paper that may help clarify how this works.

bit 3 Example

At what frequency does bit 3 in a variable toggle if you add 4 to it eight times every second?

Value is 4, rate is 8 Hz, and bit is 3, so

$$\begin{aligned}
\text{frequency} &= (\text{value} \times \text{rate}) \div 2^{\text{bit} + 1} \\
&= (4 \times 8 \text{ Hz}) \div 2^{3 + 1} \\
&= 32 \text{ Hz} \div 16 \\
&= 2 \text{ Hz}
\end{aligned}$$

Table 2 shows how this works. Each 1/8 second, the value 4 gets added to a variable. As a result, bit 3 of the variable gets toggled twice every second, i.e. at 2 Hz.

Table 2: Bit 3 Example										
Time (s)	Value	Variable	Bit 3 in Variable							
			7	6	5	4	3	2	1	0
0.000		0	0	0	0	0	0	0	0	0
0.125	4	4	0	0	0	0	0	0	1	0
0.250	4	8	0	0	0	0	0	1	0	0
0.375	4	12	0	0	0	0	0	1	1	0
0.500	4	16	0	0	0	1	0	0	0	0
0.625	4	20	0	0	0	1	0	0	1	0
0.750	4	24	0	0	0	1	0	1	0	0
0.875	4	28	0	0	0	1	0	1	1	0
1.000	4	32	0	0	1	0	0	0	0	0
1.125	4	36	0	0	1	0	0	0	1	0
1.250	4	40	0	0	1	0	0	1	0	0
1.375	4	44	0	0	1	0	0	1	1	0
1.500	4	48	0	0	1	1	0	0	0	0
1.625	4	52	0	0	1	1	0	0	1	0
1.750	4	56	0	0	1	1	0	1	0	0
1.875	4	60	0	0	1	1	0	1	1	0

NCO FRQ Calculator Method

The HyperTerminalFrequencies object allows you to enter square wave frequencies into HyperTerminal, and it calculates and displays the FRQ register value and plays the tone on the P27 piezospeaker. The object's NcoFrqReg method is an adaptation of the Propeller Library CTR object's fraction method. Given a square wave frequency, it calculates $frqReg = frequency \times (232 \div clkfreq)$, and returns frqReg. So, for a given square wave frequency simply set the FRQ register equal to the result returned by the NcoFrqReg method call.

The NcoFrqReg method uses a binary calculation approach to come up with $frqReg = frequency \times (2^{32} \div clkfreq)$. It would also have been possible to use the FloatMath library to perform these calculations. However, the NcoFrqReg method takes much less code space than the FloatMath library. It also takes less time to complete the calculation, so it makes a good candidate for a counter math object.

- ✓ Open PropellerCOM. (See Object's Lab for setup instructions.)
- ✓ Disconnect PropellerCOM.
- ✓ Load the HyperTerminalFrequencies object into the Propeller chip.
- ✓ You will have two seconds to click PropellerCOM's connect button and follow the prompts.
- ✓ Try entering the integer portion of each frequency value (not the FRQ register values) from Table 1 on page 17. Verify that the NcoFrqReg method's calculations match the calculated FRQ register values in the table.
- ✓ Remember to click HyperTerminal's Disconnect button before loading the next program.

```

''HyperTerminalFrequencies.spin
''Enter frequencies to play on the piezospeaker and display the frq register values
''with HyperTerminal.

CON

    _clkmode = xtall + pll16x          ' System clock → 80 MHz
    _xinfreq = 5_000_000

OBJ

    Debug : "FullDuplexSerialPlus"    ' Display object to use with HyperTerminal

PUB Init

    'Configure ctra module.
    ctra[30..26] := %00100            ' Set ctra for "NCO single-ended"
    ctra[8..0] := 27                  ' Set APIN to P27
    frqa := 0                         ' Don't send a tone yet.
    dira[27]~~                        ' I/O pin to output

    'Start FullDuplexSerialPlus.
    Debug.start(31, 30, 0, 57600)
    waitcnt(clkfreq * 2 + cnt)

Main

PUB Main | frequency, temp

    repeat

        Debug.Str(String(10, 13, "Enter a frequency: "))
        frequency := Debug.getDec
        temp := NcoFrqReg(frequency)
        Debug.Str(String(10, 13, "frqa = "))
        Debug.Dec(temp)

        'Broadcast the signal for 1 s
        frqa := temp
        waitcnt(clkfreq + cnt)
        frqa~

PUB NcoFrqReg(frequency) : frqReg
{{
Returns frqReg = frequency × (232 ÷ clkfreq) calculated with binary long
division. This is faster than the floating point library, and takes less
code space. This method is an adaptation of the CTR object's fraction
method.
}}

    repeat 33
        frqReg <<= 1
        if frequency => clkfreq
            frequency -= clkfreq
            frqReg++
        frequency <<= 1

```

Use Two Counter Modules to Play Two Notes

The TwoTones object demonstrates how both counters can be used to play two different square wave tones on separate speakers. In this example, all the program does is wait for certain amounts of time to pass before adjusting the `frqa` and `frqb` register values. The program could also perform a number of other tasks before coming back and waiting for the CLK register to get to the next time increment.

- ✓ Load the TwoTones object into the Propeller chip.
- ✓ Verify that it plays the square wave approximation of C6 on the P27 piezospeaker for 1 s, then pauses for $\frac{1}{2}$ s, then plays E6 on the P2 piezospeaker, then pauses for another $\frac{1}{2}$ s, then plays both notes on both speakers at the same time.

```
``TwoTones.spin
``Play individual notes with each piezospeaker, then play notes with both at the
``same time.

CON
    _clkmode = xtall1 + pll16x          ' System clock → 80 MHz
    _xinfreq = 5_000_000

OBJ
    SqrWave : "SquareWave"

PUB PlayTones | index, pin, duration
    'Initialize counter modules
    repeat index from 0 to 1
        pin := byte[@pins][index]
        spr[8 + index] := (%00100 << 26) + pin
        dira[pin]~~

    'Look tones and durations in DAT section and play them.
    repeat index from 0 to 4
        frqa := SqrWave.NcoFrqReg(word[@Anotes][index])
        frqb := SqrWave.NcoFrqReg(word[@Bnotes][index])
        duration := clkfreq/(byte[@durations][index])
        waitcnt(duration + cnt)

DAT
pins      byte 27, 3

'index    0      1      2      3      4
durations byte 1,  2,  1,  2,  1
anotes    word 1047, 0,  0,  0,  1047
bnotes    word 0,  0,  1319, 0,  1319
```

Inside TwoTones.spin

The TwoTones object declares the SquareWave object (see Appendix A) in its `OBJ` block and gives it the nickname `SqrWave`. This object has a method with the same name and function as `NcoFrqReg` in the HyperTerminalFrequencies object, but the coding relies on methods adapted from the Propeller Library's `CTR` object to perform the calculation.

The first `repeat` loop in the `PlayTones` method initializes the counter method by setting `SPR` array elements 8 and 9, which are the `ctra` and `ctrb` registers. The `index` variable in that loop is also used

to look up the pin numbers listed in the DAT block's Pins sequence using `pin := byte[@pin][index]`. The second **repeat** loop looks up elements in the DAT block's durations, anotes and bnotes sequences. Each sequence has five elements, so the **repeat** loop indexes from 0 to 4 to fetch each element in each sequence.

Take a look at the command `frqa := SquareWave.NcoFrqReg(word[@Anotes][index])` in the TwoTones object's second **repeat** loop. First, `word[@Anotes][index]` returns the value that's index elements to the right of the anotes label. The first time through the loop, index is 0, so it returns 1047. The second, third and fourth time through the loop, index is 1, then 2, then 3. It returns 0 each time. The fifth time through the loop, index is 4, so it returns 1047 again. Each of these values returned by `word[@Anotes][index]` becomes a parameter in the `SquareWave.NcoFrqReg` method call. Finally, the value returned by `SquareWave.NcoFrqReg` gets stored in the `frqa` variable. The result? A given frequency value in the anotes sequence gets converted to the correct value for `frqa` to make the counter module play the note.

Counter Control with an Object

If you examined the `SquareWave` object, you may have noticed that has a `Freq` method that allows you to choose a counter module (0 or 1 for Counter A or Counter B), a pin, and a frequency. The `Freq` method considerably simplifies the `TwoTones` object.

- ✓ Compare `TwoTonesWithSquareWave` (below) against the `TwoTones` object (above).
- ✓ Load `TwoTonesWithObject` into the Propeller chip and verify that it behaves the same as the `TwoTones` object.

```

''TwoTonesWithSquareWave.spin
''Play individual notes with each piezospeaker, then play notes with both at the
''same time.

CON
    _clkmode = xtall1 + pll16x          ' System clock → 80 MHz
    _xinfreq = 5_000_000

OBJ

    SqrWave : "SquareWave"

PUB PlayTones | index, pin, duration

    'Look tones and durations in DAT section and play them.
    repeat index from 0 to 4
        SqrWave.Freq(0, 27, word[@Anotes][index])
        SqrWave.Freq(1, 3, word[@Bnotes][index])
        duration := clkfreq/(byte[@durations][index])
        waitcnt(duration + cnt)

DAT
    pins          byte 27, 3

    'index          0          1          2          3          4
    durations byte 1,      2,      1,      2,      1
    anotes         word 1047, 0,      0,      0,      1047
    bnotes         word 0,    0,      1319, 0,      1319

```

Applications – IR Object and Distance Detection

When you point your remote at the TV and press a button, the remote flashes an IR LED on/off rapidly to send messages to the IR receiver in the TV. The rate at which the IR LED flashes on/off is matched to a filter inside the TV's IR receiver. Common frequencies are 36.7, 38, 40, and 56.9 kHz. This frequency-and-filter system is used to distinguish IR remote messages from ambient IR such as sunlight and the 120 Hz signal that is broadcast by household lighting.



The wavelength of IR used by remotes is typically in the 800 to 940 nm range.

The remote transmits the information by modulating the IR signal. The amount of time the IR signal is sent can contain information, such as start of message, binary 1, binary 0, etc. By transmitting sequences of signal on/off time, messages for the various buttons on your remote can be completed in just a few milliseconds.

The IR LED and receiver that are used for beaming messages to entertainment system components can also be used for object detection. In this scheme, the IR LED and IR receiver are placed so that the IR LED's light will bounce off an object and return to the IR receiver. The IR LED still has to modulate its light for the IR receiver's pass frequency. If the IR LED's light does reflect off an object and return to the IR receiver, the receiver sends a signal indicating that it is receiving the IR signal. If the IR does not reflect off the object and return to the IR receiver, it sends a signal indicating that it is not receiving IR.



This detection scheme uses very inexpensive parts, and has become increasingly popular in hobby robotics.

The PE Kit's IR receiver shown on the right side of Figure 11 has a 38 kHz filter. A Propeller chip cog's counter module can be used to generate the 38 kHz signal for the IR LED to broadcast for either IR object detection or entertainment system component control. This section of the lab will simply test object detection, but the same principles will apply to remote decoding and entertainment system component control.

- ✓ Build the circuit shown in Figure 11 – Figure 13, using the photo as a parts placement guide.

Figure 11: IR Detection Parts and Schematic

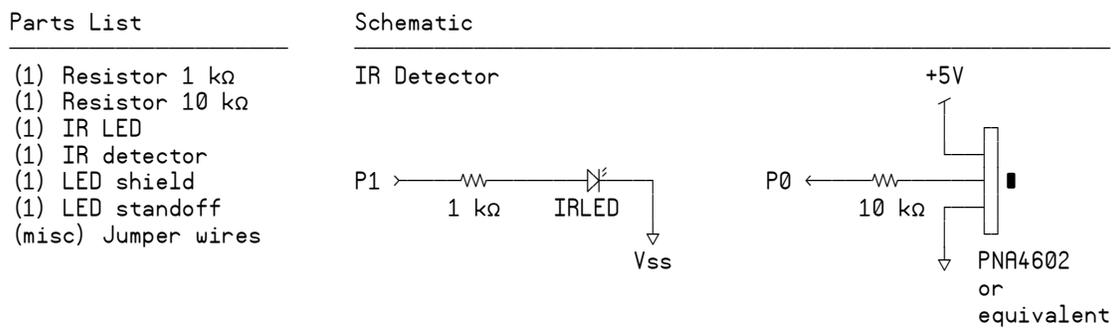


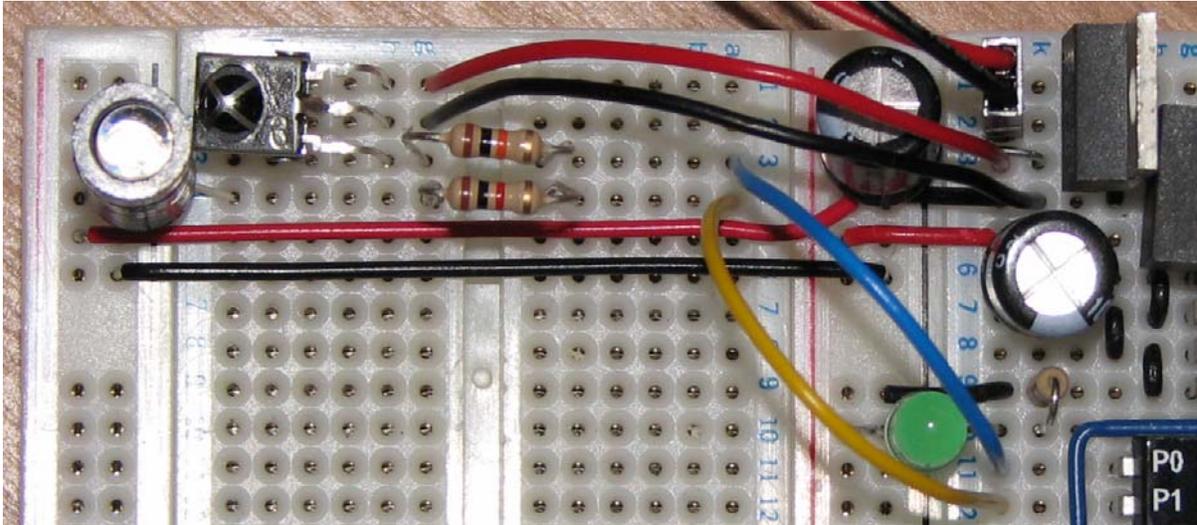
Figure 12 shows how to assemble the IR LED for object detection. First, snap the IR LED into the LED standoff. Then, attach the light shield to the standoff.

Figure 12: IR LED Assembly



A breadboard arrangement that works well for the IR LED and receiver is shown in the upper-left side of Figure 13. Notice how the IR receiver's 5 V source is jumpered from the center breadboard's socket (l, 3) to the left breadboard's socket (g, 1). The IR receiver's ground is jumpered from the center breadboard's socket (k, 4) to the left breadboard's (g, 2) socket. The IR LED's shorter cathode pin is connected to the left vertical ground rail (black, 4). A 1 k Ω resistor is in series between the IR LED's anode and P1. A large resistor is important for connecting a 5 V output device to the Propeller chip's 3.3 V input; a 10 k Ω resistor is used between the IR receiver's 5 V output and the Propeller chip's P0 I/O pin. A 1 to 2 k Ω resistor is useful in series with the IR LED to reduce the detection range. A small resistor like 100 Ω often causes the ceiling to be detected.

Figure 13: IR LED and Detector Orientation



IR Object Detection with NCO

The `IrObjectDetection` object sets up the 38 kHz signal using NCO mode. Whenever the I/O pin connected to the IR LED is set to output, the 38 kHz transmits. In a `repeat` loop, the program allows the IR LED to transmit the 38 kHz infrared signal for 1 ms, then it saves `ina[0]` in a variable named `state` and displays it on HyperTerminal.

- ✓ Make sure `PropellerCOM.ht` is open but disconnected.
- ✓ Load `IrObjectDetection.spin` into the Propeller chip.
- ✓ Connect `PropellerCOM`.
- ✓ The state should be 1 with no obstacles visible, or 0 when you place your hand in front of the IR LED/receiver.

```
'' IrObjectDetection.spin
'' Detect objects with IR LED and receiver and display with HyperTerminal.

CON

  _clkmode = xtal1 + pll16x           ' System clock + 80 MHz
  _xinfreq = 5_000_000
```

```

OBJ

  Debug      : "FullDuplexSerialPlus"
  SqrWave    : "SquareWave"

PUB IrDetect | state

  ' Start 38 kHz square wave
  SqrWave.Freq(0, 1, 38000)           ' 38 kHz signal → P1
  dira[1]~                             ' Set I/O pin to input when no signal needed

  ' Start FullDuplexSerialPlus
  Debug.start(31, 30, 0, 57600)
  waitcnt(clkfreq * 2 + cnt)

  Debug.Str(String(10, 13, " <- IR Detection bit: "))

  repeat

    ' Detect object.
    dira[1]~~                             ' I/O pin → output to transmit 38 kHz
    waitcnt(clkfreq/1000 + cnt)           ' Wait 1 ms
    state := ina[0]                       ' Store I/R detector output
    dira[1]~                             ' I/O pin → input to stop signal

    ' Display detection (0 detected, 1 not detected)
    Debug.Dec(state)
    Debug.tx(13)
    waitcnt(clkfreq/10 + cnt)

```

IR Distance Detection with NCO and Duty Sweep

If the IR LED shines more brightly, it makes the detector more far-sighted. If it shines less brightly, it makes it more near-sighted. Recall that a counter module's Duty mode can be used to control LED brightness and even sweep the LED's brightness from dim to bright (see page 8.) This same duty sweep approach can be combined with the NCO signal from the IR object detection example to make the IR LED flash on/off at 38 kHz, sweeping from dim to bright. With each increase in brightness, the IR detector's output can be rechecked in a loop. The number of times the IR detector reported that it detected an object will then be related to the object's distance from the IR LED/detector.

Although the circuit from Figure 11 can be used for distance detection with a combination of NCO and duty signals, the circuit in Figure 14 makes it possible to get better results from the IR receiver. Instead of tying the IR LED's cathode to GND, it is connected to P2. The program can then sweep the voltage applied to IR LED's cathode from 0 to 3.3 V via P2 while the signal from P1 transmits the 38 kHz NCO signal to the anode end of the circuit. Since an LED is a 1-way valve, the low portion of the 38 kHz signal does not get transmitted since it is less than the DC voltage that the duty signal synthesizes on P2. During the high portions of the 38 kHz signal, the voltages applied to P2 reduce the voltage across the LED circuit, which in turn reduces its brightness. So, it's the same 38 kHz signal, just successively less bright.

Figure 14: IR Detection Parts and Schematic

Parts List	Schematic
(1) Resistor 220 Ω (1) Resistor 10 k Ω (1) IR LED (1) IR detector (1) LED shield (1) LED standoff (misc) Jumper wires	

The IR Detector object below performs the distance detection just discussed. The parent object has to call the `init` method to tell the object which pins are connected to the IR LED circuit's anode and cathode ends and the IR receiver's outputs. When the `distance` method gets called, it uses the duty sweep approach just discussed and the pin numbers that were passed to the `init` method to measure the object's distance.

The `IrDetector` object's `distance` method uses the `SquareWave` object to start transmitting the 38 kHz signal to the IR LED circuit's anode end using Counter B. Then, it configures Counter A to duty mode and initializes `freqa` and `phsa` to 0, which results in an initial low signal to the IR LED circuit's cathode end. Next, a `repeat` loop very rapidly sweeps duty from 0/256 to 255/256. With each iteration, the voltage to the IR LED circuit's cathode increases, making the IR LED less bright and the IR detector more nearsighted. Between each duty increment, the loop adds the IR receiver's output to the `dist` return parameter. Since the IR receiver's output is high when it doesn't see reflected IR, `dist` stores the number of times out of 256 that it did not see an object. When the object is closer, this number will be smaller; when it's further, the number will be larger. So, after the loop, when the method returns the `dist` parameter, it contains a representation of the object's distance.

Keep in mind that this distance measurement will vary with the surface reflecting the IR.

For example, if the distance method returns 175, the measured distance for a white sheet of paper might be five times the distance of a sheet of black vinyl. Reason being, the white paper readily reflects infrared, so it will be visible to the receiver much further away. In contrast, black vinyl tends to absorb it, and is only visible at very close ranges.

```

`IrDetector.spin

CON
    scale = 16_777_216          ' 232 ÷ 256

OBJ
    SquareWave : "SquareWave"  ' Import square wave cog object

VAR
    long anode, cathode, recPin, dMax, duty

PUB init(irLedAnode, irLedCathode, irReceiverPin)

    anode := irLedAnode
    cathode := irLedCathode
    recPin := irReceiverPin
    
```

```

PUB distance : dist
{{
Performs a duty sweep response test on the IR LED/receiver and returns dist, a zone value
from 0 (closest) to 256 (no object detected).
}}
' Start 38 kHz signal.
SquareWave.Freq(1, anode, 38000)          ' ctrb 38 kHz
dira[anode]~~

' Configure Duty signal.
ctra[30..26] := %00110                    ' Set ctra to DUTY mode
ctra[5..0]   := cathode                   ' Set ctra's APIN
frqa := phsa := 0                         ' Set frqa register
dira[cathode]~~                           ' Set P5 to output

dist := 0

repeat duty from 0 to 255                  ' Sweep duty from 0 to 255
  frqa := duty * scale                     ' Update frqa register
  waitcnt(clkfreq/128000 + cnt)           ' Delay for 1/128th s
  dist += ina[recPin]                     ' Object not detected? Add 1 to dist.

```

The TestIrDutyDistanceDetector object gets distance measurements from the IrDetector object and displays them in HyperTerminal. With the 220 Ω resistor in series with the LED, whether or not the system detects your ceiling from table height depends on how high and how reflective your ceiling is. If it detects no object, it will return 256. Daylight streaming in through nearby windows may introduce some noise in the detector's output, resulting in values slightly less than 256 when no object is detected. As a target object is brought closer to the IR LED/receiver, the measurements will decrease, but not typically to zero. To get the detected distance clear down to zero, it is usually necessary to point the IR detector directly into the IR receiver's phototransistor (the black bubble under the crosshairs).

- ✓ Make sure IrDetector.spin is saved to the same folder as TestIrDutyDistanceDetector.spin and FullDuplexSerialPlus.spin.
- ✓ Load the TestIrDutyDistanceDetector object into the Propeller chip.
- ✓ Experiment with a variety of targets and distance tests to get an idea of what such a system might and might not be useful for.

```

' TestIrDutyDistanceDetector.spin

CON

_xinfreq = 5_000_000
_clkmode = xtall | pll116x

OBJ

ir      : "IrDetector"
debug   : "FullDuplexSerialPlus"

PUB TestIr | dist

' Start serial communication, and wait 2 s for user to connect to HyperTerminal.
Debug.Start(31, 30, 0, 57600)
waitcnt(clkfreq * 2 + cnt)
debug.str(String("running...", 10, 13))

```

```

'Configure IR detectors.
ir.init(1, 2, 0)

repeat
'Get and display distance.
dist := ir.Distance
debug.dec(dist)
debug.str(String(10, 13))
waitcnt(clkfreq/3 + cnt)

```

Counting Transitions

Counter modules also have positive and negative edge detection modes (see Figure 15). In POSEDGE mode, a counter module will add FRQ to PHS when it detects a transition from low to high on a given I/O pin. NEGEDGE mode makes the addition when it detects a high to low transition. Either can be used for counting the cycles of signals that pass above and then back down below a Propeller I/O pin's 1.65 V logic threshold.

 These counter modes can be used to either count the transitions of a signal applied to the I/O pin or the transitions of a signal the I/O pin is transmitting.

Figure 15: Edge Detector Excerpts from the CTR Object's Counter Mode Table

CTRMODE	Description	Accumulate FRQ to PHS	APIN output*	BPIN output*
%00000	Counter disabled (off)	0 (never)	0 (none)	0 (none)
.
%01010	POSEDGE detector	A^1 & $!A^2$	0	0
.
%01110	NEGEDGE detector	$!A^1$ & A^2	0	0
.
%11111	LOGIC always	1	0	0

* must set corresponding DIR bit to affect pin

A^1 = APIN input delayed by 1 clock
 A^2 = APIN input delayed by 2 clocks
 B^1 = BPIN input delayed by 1 clock

Notice from the notes in the Counter Mode Table excerpt in Figure 15 that the addition of FRQ to PHS occurs one clock cycle after the edge. This could make a difference in some assembly language programs where the timing is tight, but does not have any significant impact on interpreted Spin language programs.

The steps for setting up a counter still involve setting the CTR register's MODE bit field (bits 30..26) and its APIN bit field (bits 5..0) along with setting the FRQ register to the value that should be added to the PHS register when an edge is detected. Before the measurement, they can be set to zero.

```

ctrb[30..26] := %01110
ctrb[8..0] := 27

```

```
frqb~
phsb~
```

Here's an example from the next program that demonstrates one way of using NEGEDGE detector to control the duration of a tone played on the piezospeaker. The Counter A module is set to transmit a 2 kHz square wave with NCO mode on the same I/O pin the Counter B register will monitor with NEGEDGE mode. The `frqb` register is set to 1, so that with each negative clock edge, 1 gets added to `frqb`. To play a 2 kHz tone for 1 second, it takes 2000 cycles. The `repeat while phsb < 2000` command only allows the program to move on and clear `frqa` to stop playing the tone after 2000 negative edges have been detected.

```
frqb := 1
frqa := SquareWave.NcoFrqReg(2000)

repeat while phsb < 2000

frqa~
```



Polling: This example polls the `phsb` register, waiting for the number of transitions to exceed a certain value, but it doesn't necessarily need to poll for the entire 2000 cycles. This will free up the cog to get a few things done while the signal is transmitting and check periodically to find out how close `phsb` is to 2000.

- ✓ Load `CountEdgeTest.spin` into the Propeller chip and verify that counting edges can be used to control the duration of the tone.

```
{{
CountEdgeTest.spin
Transmit NCO signal with Counter A
Use Counter B to keep track of the signal's negative edges and stop the signal
after 2000.
}}

CON

_clkmode = xtal1 + pll16x          'System clock → 80 MHz
_xinfreq = 5_000_000

OBJ

SqrWave      : "SquareWave"

PUB TestFrequency

' Configure counter modules.

ctra[30..26] := %00100           'ctra module to NCO mode
ctra[8..0]   := 27

ctrb[30..26] := %01110           'ctrb module to NEGEDGE detector
ctrb[8..0]   := 27
frqb~
phsb~

' Transmit signal for 2000 NCO signal cycles

outa[27]~                          ' P27 → output-low
dira[27]~~

frqb := 1                          ' Start the signal
frqa := SqrWave.NcoFrqReg(2000)
```

```

repeat while phsb < 2000          ' Wait for 2 k reps
frqa~                             ' Stop the signal

```

Faster Edge Detection

The next example program can stop frequencies up to about 43.9 kHz on the falling clock edge. For controlling the number of pulses delivered by faster signals, an assembly language program will be way more responsive, and can likely detect the falling edge and stop it within a few clock cycles.

BetterCountEdges.spin monitors a 3 kHz signal transmitted by Counter A. Instead of monitoring negative edges, it configures Counter B to monitor positive edges on P27 with `ctrb[30..26] := 01010` and `ctrb[5..0] := 27`. Next, it sets `frqb` to 1 so that 1 gets added to the PHS register with each positive edge. Instead of clearing the PHS register and waiting for 3000 positive edges, it sets `phsb` to -3000. Next, it sets bit 27 in a variable named `a` to 1 with the command `a |< 27`.

- ✓ Look up the bitwise decode `|<` operator in the Propeller Manual.

When the `frqa := SquareWave.CalcFreqReg(3000)` command executes, P27 starts sending a 3 kHz square wave. Since `phsb` is bit-addressable, the command `repeat while phsb[31]` repeats while bit 31 of the `phsb` register is 1. Recall that the highest bit of a variable or register will be 1 so long as the value is negative. So `phsb[31]` will be 1 (non zero) while `phsb` is negative. The `phsb` register will remain negative until `frqb = 1` is added to `phsb` 3000 times.

When the `repeat` loop terminates, the signal is high because it was looking for a positive edge. The goal is to stop the signal after it goes low. The command `waitpeq(0, a, 0)` waits until P27 is zero. The command `waitpeq(0, |< 27, 0)` could also have been used, but the program wouldn't respond as quickly because it would have to first calculate `|< 27`; whereas `waitpeq(0, a, 0)` already has that value calculated and stored in the `a` variable. So the `waitpeq` command allows the program to continue to `frqa~`, which clears the `frqa` register, and stops the signal at output-low after the 3000th cycle.

- ✓ Look up and read about `waitpeq` in the Propeller Manual.
- ✓ Load BetterCountEdges.spin into the Propeller chip and verify that it plays the 3 kHz signal for 1 s.
- ✓ If you have an oscilloscope, set the signal for ten cycles instead of 3000. Then, try increasing the frequency, and look for the maximum frequency that will still deliver only 10 cycles.

```

' BetterCountEdges.spin

CON
  _clkmode = xtall + pll16x          ' System clock + 80 MHz
  _xinfreq = 5_000_000

OBJ
  SquareWave      : "SquareWave"

PUB TestFrequency | a, b, c
  ' Configure counter modules.
  ctra[30..26] := %00100          ' ctra module to NCO mode

```

```

ctra[8..0] := 27
outa[27]~
dira[27]~~

ctrb[30..26] := %01010
ctrb[8..0] := 27
frqb := 1
phsb := -3000

a := |< 27

frqa := SquareWave.NcoFrqReg(3000)
repeat while phsb[31]
waitpeq(0, a, 0)
frqa~

```

'P27 → output-low
'ctrb module to POSEDGE detector
'Add 1 for each cycle
'Start the count at -3000
'Set up a pin mask for the waitpeq command
'Start the square wave
'Wait for 3000th low→high transition
'Wait for low signal
'Stop the signal

PWM

PWM stands for pulse width modulation, which can be useful for both servo and motor control. A counter module operating in NCO mode can be used to generate precise duration pulses, and a **repeat** loop with a **waitcnt** command can be used to maintain the signal's cycle time.

Let's first take a look at sending a single pulse with a counter module. This is a very precise method is good down to the duration of a Propeller chip's system clock tick. After setting up the counter in NCO mode, simply set the PHS register to the duration you want the pulse to last by loading it with a negative value. For example, the command **phsa := -clkfreq** in the next example program sets the **phsa** register to **-80_000_000**. Remember that bit 31 of a register will be 1 so long as it's negative, and also remember that in NCO mode bit 31 of the PHS register controls an I/O pin's output state. So, when the PHS register is set to a negative value (and FRQ to 1), the I/O pin will send a high signal for the same number of clock ticks as the negative number stored in PHS.

Sending a Single Pulse

The SinglePulseWithCounter object uses this technique to send a 1 second pulse to the LED on P4. Even though the program can move on as soon as it has set the PHS register to **-clkfreq**, it can't ignore the PHS register indefinitely. Why? Because, $2^{31} - 1 = 2_147_483_647$ clock ticks later, the PHS register will roll over from a large positive number to a large negative number and start counting down again. Since bit 31 of the PHS register will change from 0 to 1 at that point, the I/O pin will transition from low to high for no apparent reason.

- ✓ Load SinglePulseWithCounter.spin into the Propeller chip and verify that it sends a 1 second pulse. This pulse will last exactly 80_000_000 clock ticks.
- ✓ With the Propeller chip's clock running at 80 MHz, the pin will go high again about 26.84 seconds later. Verify this with a calculator and by waiting 27 seconds after the 1 s high signal ended.
- ✓ If you have an oscilloscope, try setting the PHS register to -1 and see if you can detect the 12.5 ns pulse the propeller I/O pin transmits. Also try setting **phsa** to **clkfreq/1_000_000** for a 1 μs pulse.

```

'' SinglePulseWithCounter.spin
'' Send a high pulse to the P4 LED that lasts exactly 80_000_000 clock ticks.

CON

  _clkmode = xtall + pll16x
  _xinfreq = 5_000_000

```

' System clock → 80 MHz

```

PUB TestPwm | tc, tHa, tHb, ti, t

    ctra[30..26] := %00100          ' Configure Counter A to NCO
    ctra[8..0] := 4
    frqa := 1
    dira[4]~~

    phsa := - clkfreq              ' Send the pulse

    ' Keep the program running so the pulse has time to finish.
    repeat

```

Pulse Width Modulation

For a repeating PWM signal, the program has to establish the cycle time using `waitcnt`. Then, the pulse duration is determined each time through the loop by setting the PHS register to a negative value at the beginning of the cycle.

The `1Hz25PercentDutyCycle` object blinks the P4 LED every second for 0.25 seconds. The `repeat` loop repeats once every second, and the counter sends a high signal to the P4 LED for $\frac{1}{4}$ s with each repetition. The command `tC := clkfreq` sets the variable that holds the cycle time to the number of clock ticks in one second. The command `tHa := clkfreq/4` sets the high time for the A counter module to $\frac{1}{4}$ s. The command `t := cnt` records the `cnt` register at an initial time.

Next, a `repeat` loop manages the pulse train. It starts by setting `phsa` equal to `-tHa`, which starts the pulse that will last exactly `clkfreq/4` ticks. Then, it adds `tC`, the cycle time of `clkfreq` ticks, to `t`, the target time for the next cycle to start. The `waitcnt(t)` command waits for the number of ticks in 1 s before repeating the loop.

- ✓ Run the program and verify the $\frac{1}{4}$ s high time signal every 1 s with the LED connected to P4.
- ✓ If you have an oscilloscope, try a signal that lasts 1.5 ms, repeated every 20 ms. This would be good to make a servo hold its center position.

```

'' 1Hz25PercentDutyCycle.spin
'' Send 1 Hz signal at 25 % duty cycle to P4 LED.

CON

    _clkmode = xtall1 + pll116x      ' System clock → 80 MHz
    _xinfreq = 5_000_000

PUB TestPwm | tc, tHa, t

    ctra[30..26] := %00100          ' Configure Counter A to NCO
    ctra[8..0] := 4
    frqa := 1
    dira[4]~~

    tC := clkfreq                    ' Set up cycle and high times
    tHa := clkfreq/4
    t := cnt                          ' Mark counter time

    repeat                            ' Repeat PWM signal
        phsa := -tHa                 ' Set up the pulse
        t += tC                       ' Calculate next cycle repeat
        waitcnt(t)                   ' Wait for next cycle

```

This is another good place to examine differential signals. The only differences between this example program and the previous one are:

- The mode is set to NCO differential using `ctra[30..26] := %00101` (differential) instead of `ctra[30..26] := %00100` (single-ended)
 - A second I/O pin is selected for differential signals with `ctra[14..9] := 5`
 - Both P4 and P5 are set to output with `dira[4..5]~~` instead of just `dira[4]~~`
- ✓ Try the program and verify that P5 is on whenever P4 is off.

```

''1Hz25PercentDutyCycleDiffSig.spin
''Differential version of 1Hz25PercentDutyCycle.spin

CON

  _clkmode = xtal1 + pll16x           ' clock → 80 MHz
  _xinfreq = 5_000_000

PUB TestPwm | tc, tHa, t

  ctra[30..26] := %00101             ' Counter A → NCO (differential)
  ctra[8..0] := 4                    ' Select I/O pins
  ctra[14..9] := 5
  frqa := 1                          ' Add 1 to pbs with each clock tick

  dira[4..5]~~                       ' Set both differential pins to output

  ' The rest is the same as 1Hz25PercentDutyCycle.spin

  tC := clkfreq                      ' Set up cycle and high times
  tHa := clkfreq/4
  t := cnt                            ' Mark counter time

  repeat                              ' Repeat PWM signal
    phsa := -tHa                     ' Set up the pulse
    t += tC                          ' Calculate next cycle repeat
    waitcnt(t)                       ' Wait for next cycle

```

The TestDualPwm object uses both counters to transmit PWM signals that have the same cycle time but independent high times (1/2 s high time with Counter A and 1/5 s with Counter B). The duty cycle signals are transmitted on P4 and P6.

- ✓ Try making both signals differential, using I/O pins P4..P7.
- ✓ Again, if you have an oscilloscope, try making one signal 1.3 ms and the other 1.7 ms. This could cause a robot with two continuous rotation drive servos to either go straight forward or straight backwards.

```

{{
TestDualPWM.spin
Demonstrates using two counter modules to send a dual PWM signal.
The cycle time is the same for both signals, but the high times are independent of
each other.
}}

CON

  _clkmode = xtal1 + pll16x           ' System clock → 80 MHz
  _xinfreq = 5_000_000

```

```

PUB TestPwm | tc, tHa, tHb, t

  ctra[30..26] := ctrb[30..26] := %00100      ' Counters A and B → NCO single-ended
  ctra[8..0] := 4                               ' Set pins for counters to control
  ctrb[8..0] := 6
  frqa := frqb := 1                             ' Add 1 to phs with each clock tick

  dira[4] := dira[6] := 1                       ' Set I/O pins to output

  tC := clkfreq                                 ' Set up cycle time
  tHa := clkfreq/2                              ' Set up high times for both signals
  tHb := clkfreq/5
  t := cnt                                       ' Mark current time.

  repeat                                         ' Repeat PWM signal
    phsa := -tHa                                 ' Define and start the A pulse
    phsb := -tHb                                 ' Define and start the B pulse
    t += tC                                       ' Calculate next cycle repeat
    waitcnt(t)                                    ' Wait for next cycle

```

A variable or constant can be used to store a time increment for pulse and cycle times. In the example below, the `tInc` variable stores `clkfreq/1_000_000`. When `tC` is set to `500_000 * tInc`, it means that the cycle time will be `500_000 μs`. Likewise, `tHa` will be `100_000 μs`.

```

''SinglePwm with Time Increments.spin
CON
  _clkmode = xtall1 + pll16x                    ' System clock → 80 MHz
  _xinfreq = 5_000_000

PUB TestPwm | tc, tHa, t, tInc

  ctra[30..26] := %00100                       ' Configure Counter A to NCO
  ctra[8..0] := 4                               ' Set counter output signal to P4
  frqa := 1                                     ' Add 1 to phsa with each clock cycle
  dira[4]~~~                                   ' P4 → output

  tInc := clkfreq/1_000_000                    ' Determine time increment
  tC := 500_000 * tInc                          ' Use time increment to set up cycle time
  tHa := 100_000 * tInc                        ' Use time increment to set up high time

  ' The rest is the same as 1Hz25PercentDutyCycle.spin

  t := cnt                                       ' Mark counter time

  repeat                                         ' Repeat PWM signal
    phsa := -tHa                                 ' Set up the pulse
    t += tC                                       ' Calculate next cycle repeat
    waitcnt(t)                                    ' Wait for next cycle

```

PLL for High Frequency

Up to this point, we have used NCO mode for generating square waves in the audible (20 to 20 kHz) and IR detector (38 kHz) range. The NCO mode can be used to generate signals up to `clkfreq/2`. So, with the version of the Propeller chip used in these labs, the ceiling frequency for this mode is 40 MHz.

For signals faster than `clkfreq/2`, you can use the counter's PLL (phase-locked loop) mode. Instead of sending bit 31 of the PHS register straight to an I/O pin, PLL mode passes the signal through two

additional subsystems before transmitting it. These subsystems are not only capable of sending frequencies from 500 kHz to 128 MHz, they also diminish the jitter inherent to NCO signals. The first subsystem (counter PLL) takes the frequency that bit 31 of the PHS register toggles at and multiplies it by 16 using a voltage-controlled oscillator (VCO) circuit. The Propeller Manual and CTR object call this the VCO frequency. The second subsystem (divider) divides the resulting frequency by a power of 2 ranging from 1 to 128.

The PLL is designed to accept PHS bit 31 frequencies from 4 to 8 MHz. The PLL subsystem multiplies this input frequency by 16, for a counter PLL frequency ranging from 64 to 128 MHz. The divider subsystem then divides this frequency by a power of two from 128 to 1, so the final output for PLL signals can range from 500 kHz to 128 MHz.

Configuring the Counter Module for PLL Mode

Figure 16 is the now-familiar excerpt from the Propeller Library’s CTR object, this time with the PLL modes listed. “PLL internal” is used for synchronizing video signals. Although not discussed in this lab, you can see it applied in the Propeller Library’s TV object. The CTRMODE values for routing the PLL signal to I/O pins are %00010 for single-ended, and %00011 for differential.

Figure 16: NCO Excerpts from the CTR Object’s Counter Mode Table

CTRMODE	Description	Accumulate FRQ to PHS	APIN output*	BPIN output*
%00000	Counter disabled (off)	0 (never)	0 (none)	0 (none)
.
%00001	PLL internal (video mode)	1 (always)	0	0
%00010	PLL single-ended	1	PLL	0
%00011	PLL differential	1	PLL	!PLL
.
%11111	LOGIC always	1	0	0

* must set corresponding DIR bit to affect pin

- A¹ = APIN input delayed by 1 clock
- A² = APIN input delayed by 2 clocks
- B¹ = BPIN input delayed by 1 clock

The CTR Register’s PLLDIV bit Field

With NCO mode, setting I/O pin frequencies was done directly through the FRQ register. The value in FRQ was added to PHS every clock tick, and that determined the toggle rate of PHS bit31, which directly controlled the I/O pin. While setting I/O pin frequencies with PLL mode still uses PHS bit 31, there are some extra steps.

In PLL mode, the toggle rate of PHS bit31 is still determined by the value of FRQ, but before the I/O pin transmits the signal, the PHS bit 31 signal gets multiplied by 16 and then divided down by a power of two of your choosing ($2^0 = 1$, $2^1 = 2$, $2^2 = 4$, ... $2^6 = 64$, $2^7 = 128$). The power of 2 is selected by a value stored in the CTR register’s PLLDIV bit field, (bits 25..23) in Figure 17.

Figure 17: CTRA/B Register Map from CTR.spin

bits	31	30..26	25..23	22..15	14..9	8..6	5..0
Name	—	CTRMODE	PLLDIV	—	BPIN	—	APIN

Calculating PLL Frequency Given FRQ and PLLDIV

Let's say you are examining a code example or object that's generating a certain PLL frequency. You can figure out what frequency it's generating using the values of `clkfreq`, the FRQ register, and the value in the CTR register's PLLDIV bit field. Just follow these three steps:

- a. Calculate the PHS bit 31 frequency:

$$\text{PHS bit 31 frequency} = \frac{\text{clkfreq} \times \text{FRQ register}}{2^{\frac{32}{2}}}$$

- b. Use the PHS bit 31 frequency to calculate the VCO frequency:

$$\text{VCO frequency} = 16 \times \text{PHS bit 31 frequency}$$

- c. Divide the PLLDIV result, which is $2^{7-\text{PLLDIV}}$ into the VCO frequency:

$$\text{PLL frequency} = \frac{\text{VCO frequency}}{2^{7-\text{PLLDIV}}}$$

Example: Given a system clock frequency (`clkfreq`) of 80 MHz and the code below, calculate the PLL frequency transmitted on I/O Pin P15.

```
'Configure ctra module
ctra[30..26] := %00010
frqa := 322_122_547
ctra[25..23] := 2
ctra[5..0] := 15
dira[15]~~
```

- 1) Calculate the PHS bit 31 frequency:

$$\begin{aligned} \text{PHS bit 31 frequency} &= \frac{80_000_000 \times 322_122_547}{2^{\frac{32}{2}}} \\ &= 5_999_999 \end{aligned}$$

- 2) Use the PHS bit 31 frequency to calculate the VCO frequency:

$$\begin{aligned} \text{VCO frequency} &= 16 \times 5_999_999 \\ &= 95_999_984 \end{aligned}$$

- 3) Divide the PLLDIV result ($2^{7-\text{PLLDIV}}$) into the VCO frequency:

$$\text{PLL frequency} = \frac{95_999_984}{2^{7-\text{PLLDIV}}}$$

$$\frac{2^{7-2}}{2}$$

$$= 2_999_999 \text{ MHz}$$

$$\approx 3 \text{ MHz}$$

Calculating FRQ and PLLDIV Given a PLL Frequency

Figuring out the PLL frequency given some pre-written code is well and good, but what if you want to calculate FRQ register and PLLDIV bit fields values to generate a frequency with your own code? Here are four steps you can use to figure it out:

- 1) Use the table below to figure out which value to put in the CTR register's PLLDIV bit field based on the frequency you want to transmit.

MHz	PLLDIV	MHz	PLLDIV
0.5 to 1	0	8 to 16	4
1 to 2	1	16 to 32	5
2 to 4	2	32 to 64	6
4 to 8	3	64 to 128	7

- 2) Calculate the VCO frequency with the PLL frequency you want to transmit and the PLL divider, and round down to the next lowest integer.

$$\text{VCO frequency} = \text{PLL frequency} \times 2^{(7-\text{PLLDIV})}$$

- 3) Calculate the PHS bit 31 frequency you'll need for the VCO frequency. It's the VCO frequency divided by 16.

$$\text{PHS bit 31 frequency} = \text{VCO frequency} \div 16$$

- 4) Use the NCO frequency calculations to figure out the FRQ register value for the PHS bit 31 frequency.

$$\text{FRQ register} = \text{PHS bit 31 frequency} \times \frac{2^{32}}{\text{clkfreq}}$$

Example: `clkfreq` is running at 80 MHz, and you want to generate a 12 MHz signal with PLL. Figure out the FRQ register and PLLDIV bit fields.

- 1) Use the table to figure out which value to put in the CTR register's PLLDIV bit field:

Since 12 MHz falls in the 4 to 16 MHz range, PLLDIV is 4.7. Round down, and use 4.

- 2) Calculate the VCO frequency with the final PLL frequency and the PLL divider:

$$\begin{aligned} \text{VCO frequency} &= 12 \text{ MHz} \times 2^{(7-4)} \\ &= 12 \text{ MHz} \times 8 \\ &= 96 \text{ MHz} \end{aligned}$$

- 3) Calculate the PHS bit 31 frequency you'll need for the VCO frequency. It's the VCO frequency divided by 16:

$$\text{PHS bit 31 frequency} = 96 \text{ MHz} \div 16$$

= 6 MHz

- 4) Use the NCO frequency calculations to figure out the FRQ register value for the PHS bit 31 frequency:

$$\text{FRQ register} = 6 \text{ MHz} \frac{2^{32}}{80 \text{ MHz}}$$
$$= 322_122_547$$

Testing PLL Frequencies

The TestPllParameters object lets you control Counter A's PLL output frequency by hand-entering values for `frqa` and also `ctra`'s PLLDIV bit field into HyperTerminal. It transmits the frequency you entered for 1 s, counting the cycles with Counter B set to NEGEDGE detection mode.

Although the PLL can generate frequencies up to 128 MHz, the Propeller chip's counters can only detect frequencies up to 40 MHz with counter modules. This concurs with the Nyquist sampling rate, which must be twice as fast as the highest frequency it could possibly measure. Also, if you consider that the edge detection mode adds FRQ to PHS when it detects a high signal during one clock tick and a low signal during the next, it needs at least two clock ticks to detect a signal's full cycle.

- ✓ Load TestPllParameters into the Propeller chip.
- ✓ Calculate FRQ register and PLLDIV bit field values for various frequencies in the 500 kHz to 40 MHz range.
- ✓ Enter the FRQ and PLLDIV values at the HyperTerminal prompts and verify that the measured frequency is in the same neighborhood as your calculations.

```
{{
TestPllParameters.spin

Tests PLL frequencies up to 40 MHz. PHS register and PLLDIV bit field values
are entered into HyperTerminal. The Program uses these to synthesize square wave
with PLL mode using counter module A. Counter module B counts the cycles in 1 s
and reports it.
}}

CON

  _clkmode = xtall1 + pll16x           ' System clock → 80 MHz
  _xinfreq = 5_000_000

OBJ

  SqrWave : "SquareWave"
  debug   : "FullDuplexSerialPlus"

PUB TestFrequency | delay, cycles

  Debug.Start(31, 30, 0, 57600)
  waitcnt(clkfreq * 2 + cnt)

  ' Configure counter modules.
  ctra[30..26] := %00010           ' ctra module to PLL single-ended mode
  'frqa := 322_122_547
  'ctra[25..23] := 2
  ctra[5..0] := 15

  ctrb[30..26] := %01110           ' ctrb module to NEGEDGE detector
  ctrb[5..0] := 15
```

```

frqb:= 1

repeat

  Debug.str(String(10, 13, "Enter frqa: ")) 'frqa and PLLDIV are user input
  frqa := Debug.GetDec

  Debug.str(String(10, 13, "Enter PLLDIV: "))
  ctra[25..23] := Debug.GetDec

  delay := clkfreq + cnt 'Precalculate delay ticks
  dira[15]~~ 'P15 → output
  phsb~ 'Wait 1 s.
  waitcnt(delay)
  cycles := phsb 'Store cycles
  dira[15]~ 'P15 → input

  Debug.str(String(10, 13, "f = ")) 'Display cycles as frequency
  debug.dec(cycles)
  debug.str(String(" Hz", 10, 13))

```

Metal Detection with PLL and Positive Detector Modes and an LC Circuit

Inductors are coils that when placed in a circuit have the capacity to store energy. They get used in many types of applications, one of which is metal detection. There are lots of different kinds of metal detection instruments aside from the ones you may have seen passed over the sands on just about any beach on any given weekend. Other examples include instruments that identify the type of metal, check for stress fractures in metal surfaces, and precisely measure the distance of a metal surface from an instrument.

Even though there aren't any inductors in the PE kit, there are lots of wires that can be shaped into metal loops. When current passes through a metal loop, it becomes a small inductor. This portion of the lab demonstrates how a cog can use two counters, one in PLL mode and the other in POS detector mode, to send high-frequency signals into an LC (inductor-capacitor) circuit's input, and infer the presence or absence of metal by examining the circuit's output signal.

Figure 18 shows a parts list and circuit for the PE Kit's metal detector. Because of the small part sizes and high frequencies involved, this circuit can be finicky. So, for best results, wire it exactly like the breadboard photo shown in Figure 19. The capacitor and resistors should all be sticking straight up off the board, and the two wires should be on the same plane as the board.

This circuit will also require some tuning. Figure 18 starts with R1 at 100 Ω , and R2 (100 Ω) and R3 (470 Ω) are in parallel. The notation these labs will use for parallel resistor combinations is R2 || R3. Your particular circuit may require a larger or smaller resistor in parallel with either R1 or R2, but for now, start with R1 = 100 Ω and R2 = 100 Ω || 470 Ω .

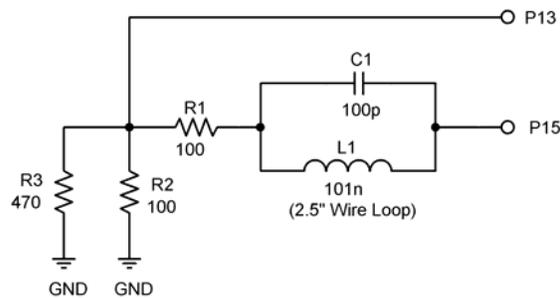
- ✓ Build the circuit in Figure 18 on your PE Platform exactly as shown in Figure 19.

Figure 18: Metal Detector Parts and Schematic

Parts List

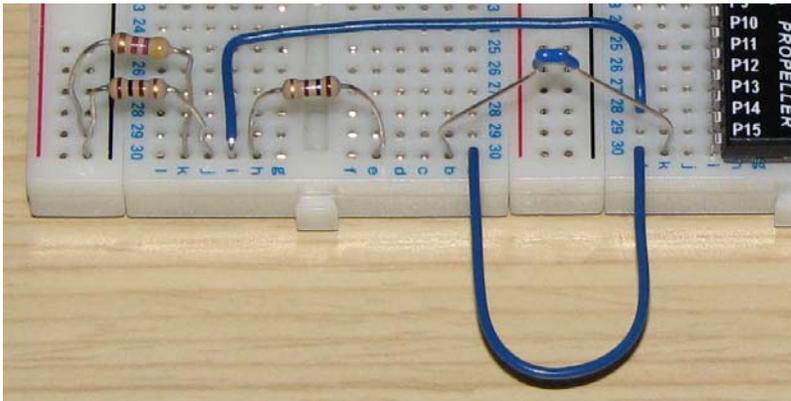
- (1) Capacitor 10 pF
- (2) Jumper Wires
- (2) Resistors 100 Ω
- (misc) resistors:
220, 470, 1000,
2000, 10k

Schematic



Make sure the wire loop you are using for an inductor is parallel to the surface of the board while the other parts are perpendicular.

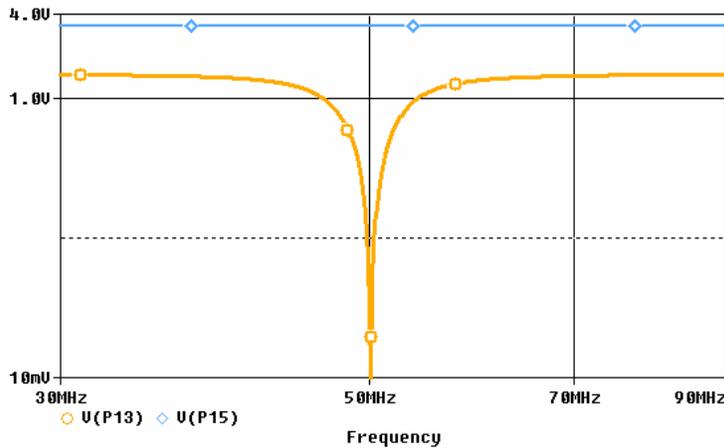
Figure 19: Metal Detector Wiring



Detecting Resonant Frequency

The LC circuit shown in Figure 18 is commonly called a *bandreject*, *bandstop*, or *notch* filter. The filter attenuates a certain frequency sine wave component from an input signal, ideally down to nothing at a certain frequency. The frequency that gets filtered is called the filter's *center frequency* as well as the LC circuit's *resonant frequency*. Figure 20 shows a simulated plot of how the filter responds to a range of input (P15) sine wave frequencies from 30 to 90 MHz. Notice that the filter's center frequency is 50 MHz. So, if the input were a sine wave, its amplitude would be attenuated almost to nothing; whereas at frequencies well outside the filter's center frequency, the output sine wave amplitude would instead be in the 1.6 V neighborhood.

Figure 20: Simulated P13 Output Vs. P15 Input for Sine Waves Frequencies



More about filters and simulation software:



If you swap R and C || L, you will have a bandpass filter. The frequency response is the upside-down version of what's shown in Figure 20. For more information on LC filters, look up terms *frequency selective circuits*, *filters*, *low-pass*, *high-pass*, *bandpass* and *bandreject* in an electronics textbook.

The simulations in this section were performed with OrCAD Demo Software, which is available for free download from www.cadence.com.

Regardless of whether it's a bandreject or bandpass filter, the circuit's resonant frequency (f_R) can be calculated with this equation. L is the inductor's inductance, measured in henrys (H), and C is the capacitor's capacitance, measured in farads (F). Of course, the L and C in Figure 18 are minute fractions of henrys and farads, respectively.

$$f_R = \frac{1}{2\pi\sqrt{LC}} \tag{Eq. 5}$$

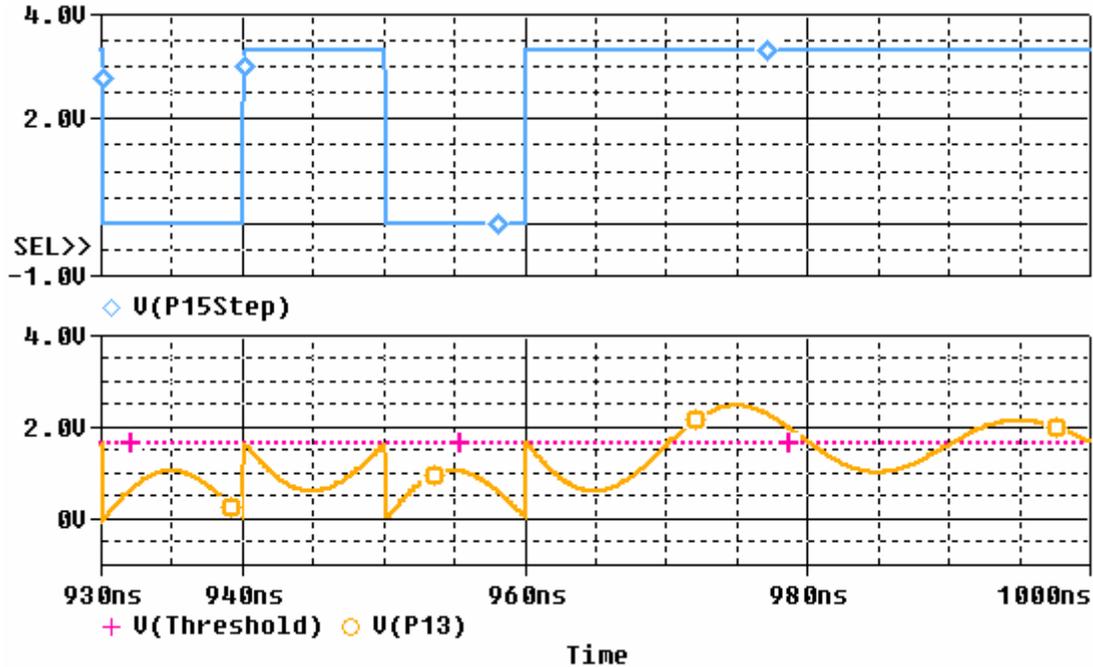
Rearranging terms makes it possible to calculate the inductance (L) based on frequency response tests.

$$L = \frac{1}{(2\pi f_R)^2 C} \tag{Eq. 6}$$

In this lab, the LC circuit's input will be a square wave from P15. Although the output is still related to the circuit's filtering characteristics, its behavior will make a lot more sense if examined from the *step response* standpoint. A circuit's step response is especially important to digital circuits, and the typical goal is to make the circuit's output quickly and accurately respond to the input and settle at its new value. The most desirable step response is called *critically damped* because it reaches the target value as quickly as possible without overshooting it. Some designs can get quicker responses with an *underdamped* circuit, but at a penalty of some oscillation above and below the new target voltage before the signal settles down. Other designs need an *overdamped* step response, which is slower to reach its target voltage, but ensures that no overshoot or ringing will occur.

The simulated step response shown in Figure 21 is a fairly drastic case of an underdamped step response. $V(P15Step)$ in the upper plot is the LC circuit's input signal. $V(P13)$ is the output signal, and $V(Threshold)$ is a DC signal at the Propeller chip's 1.65 V threshold. The simulation is not really a typical step response because a 50 MHz square wave was applied for 960 ns before the so-called step (high signal) was applied. The result was that the inductor and capacitor both accumulated some stored energy, which makes $V(P13)$'s pseudo-step response to the right of the 960 ns mark more pronounced than it would otherwise be. The important thing to notice about $V(P13)$ to the right of the 960 ns mark is that it's a sine wave that decays gradually. This sine wave occurs at the LC circuit's 50 MHz resonant frequency.

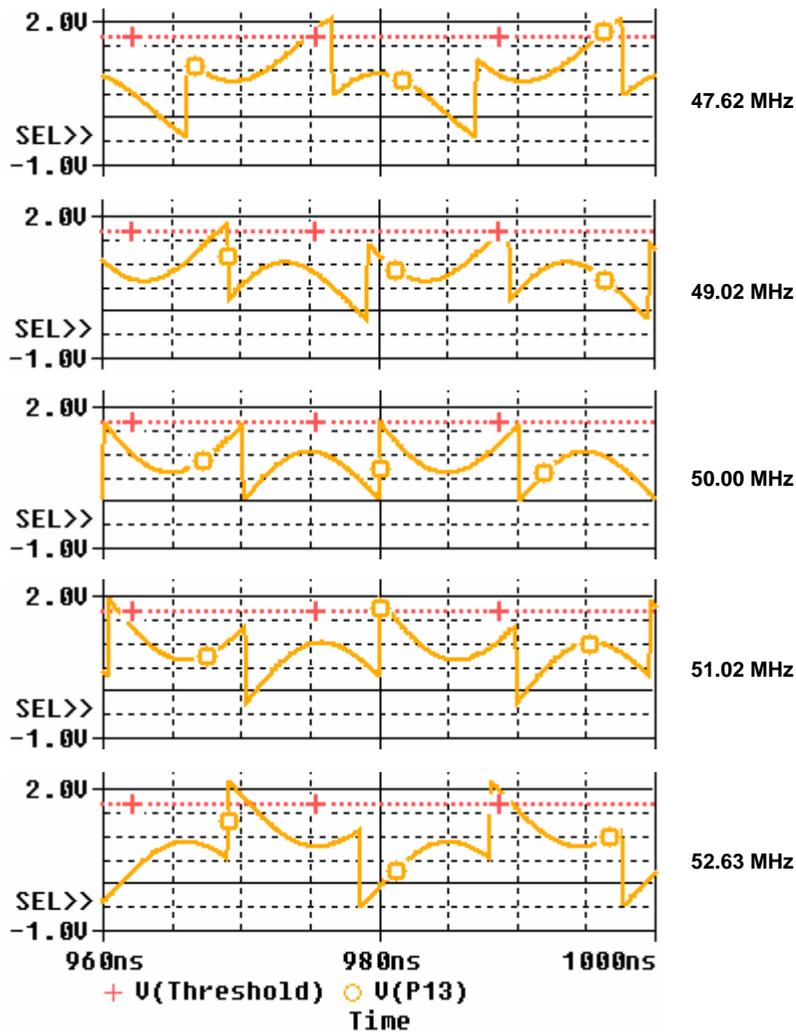
Figure 21: P13 Response to Resonant Frequency at P15



Also, take a look at the $V(P13)$ trace between 930 and 960 ns. With each transition of the 50 MHz $V(P15Step)$ signal, $V(P13)$ starts a sine wave reaction that initially opposes the $V(P15Step)$ input signal. Since the $V(P13)$ signal only gets through half of its 50 MHz sine wave response before the $V(P15Step)$ signal changes, the portions of those sine wave responses never make it above the Propeller chip's 1.65 V threshold.

Next, compare the $V(P13)$ response to square wave frequencies slightly above and below the circuit's 50 MHz resonant frequency, shown in Figure 22. At 47.62 MHz, the sine wave completes slightly more than $\frac{1}{2}$ of its cycle, part of which has climbed above the 1.65 V threshold voltage (designated by the line with the + characters). At 49.02 MHz, the sine wave is still repeating more than a full cycle, but not as much, so the signal spends less time above the threshold voltage. At 50 MHz, the input frequency matches the sinusoidal response, and since only half the sine wave repeats, the signal doesn't spend any time above the threshold voltage. At 51.02 and 52.63 MHz, the signal again spends some time above the 1.65 V I/O pin threshold, this time because the input signal changes before the sine wave has completed its cycle.

Figure 22: LC Circuit P13 Output Responses at Various Frequencies



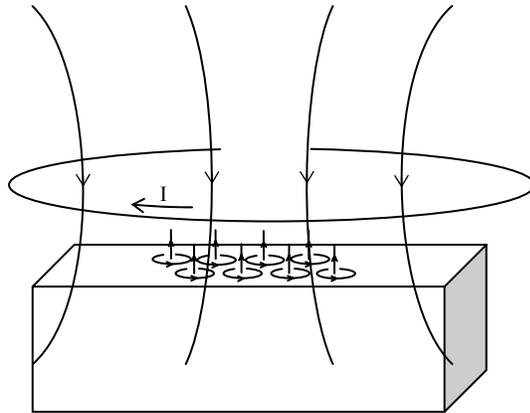
The most important thing Figure 22 indicates is that the output signal, which can be monitored by P13, will spend more time above the I/O pin's logic threshold when the P15 input signal is further away from the circuit's resonant frequency, either above or below. The Propeller can use a counter in PLL mode to generate square waves in the range of frequencies shown in Figure 22, and it can use another counter on POS detector mode to track how long the circuit's output signal spends above the P13 I/O pin's threshold voltage.

So, the Propeller chip can use two counter modules and a small amount of code to sweep the P15 PWM frequency through a range of values to find the resonant frequency of the Figure 18 circuit, but how does that make it possible to detect metal? The answer is that a nearby metal object electromagnetically interacts with the Figure 18 circuit's wire loop inductor in such a way that it changes its inductance, and also adds a small amount of resistance. When the circuit's inductance changes, its resonant frequency also changes, and the Propeller chip can detect that by sweeping P15 PLL frequencies and measuring P13 high times, which will reach a minimum at a different resonant frequency as a result of a nearby metal object.

How Eddy Currents in a nearby Metal Object Affect the Loop's Resonant Frequency

Figure 23 illustrates the electromagnetic interaction between a nearby metal object and the wire's loop inductance. The alternating currents through the loop cause alternating electromagnetic fields. These alternating magnetic fields cause groups of electrons in the conductive metal to travel in alternating circular paths. These magnetically induced circular paths are called *eddy currents*. The alternating eddy currents generate magnetic fields that oppose the fields generated by the wire loop.

Figure 23: Eddy Currents Causing Opposing Magnetic Fields



The eddy currents shown in Figure 23 provide a very small, high-frequency example of how power is transferred in AC lines. A coil connected to the power line is typically magnetically coupled with a coil of fewer turns. The alternating current in the primary induces an alternating magnetic field that induces AC current in the secondary winding. Figure 24 shows how the secondary winding and load affect the primary. The secondary winding's inductance and any resistive load can be seen in the primary, and can be accounted for as $L2'$ and R' .

Figure 24: Eddy Currents Effects on the Loop's Inductance

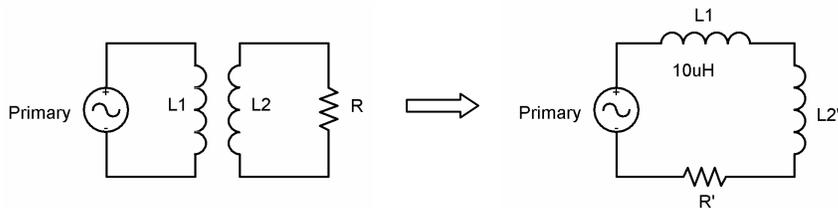


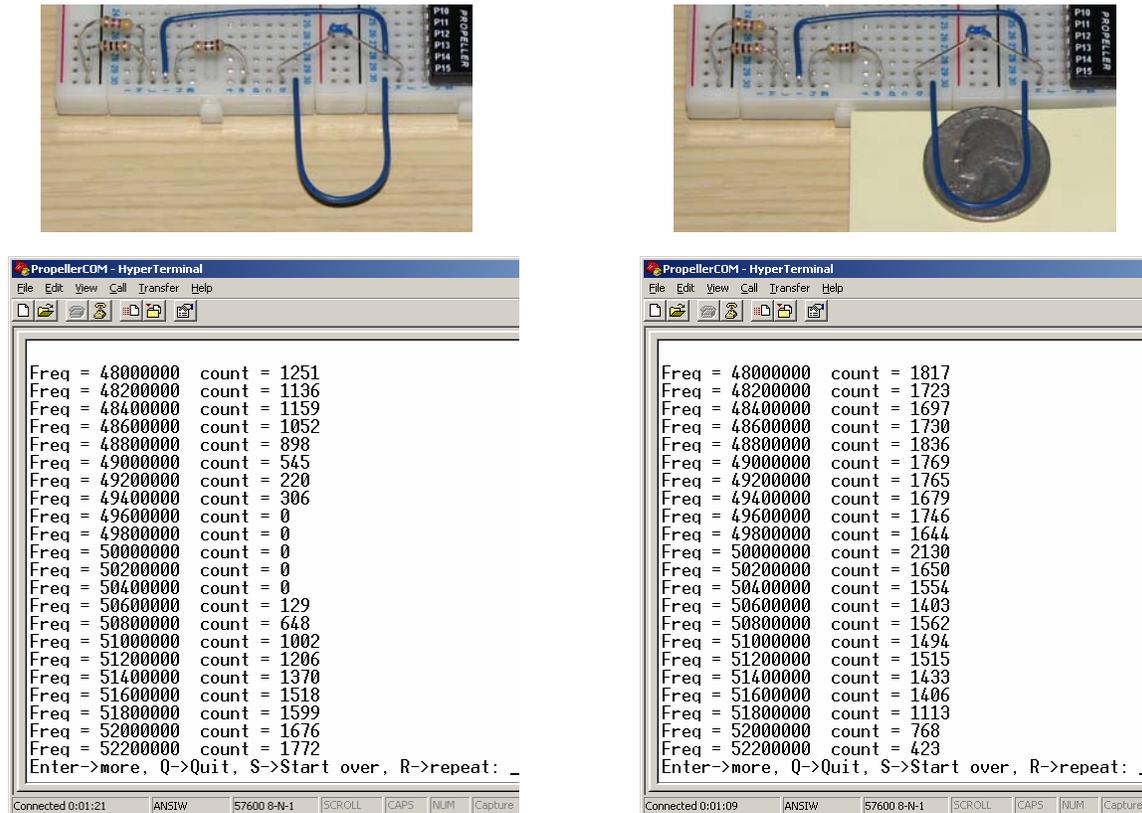
Figure 24 also represents how eddy currents, which have a certain inductance due to the fact that eddies (circular electron currents) are induced in the metal, affect the primary circuit's inductance and resistance. So, eddy currents in the nearby metal object affect the metal loop's inductance. Since the loop's inductance is measured by L in the resonance equation, it will change the LC circuit's resonant frequency. Also, since the Propeller chip can detect the circuit's resonant frequency by sweeping PLL square wave frequencies on one pin while measuring the number of ticks the circuit's output signal is above the threshold on another, the application can detect the presence or absence of nearby metals.

Testing for Resonant Frequency

The Calibrate Metal Detector object below provides an interface for testing the LC circuit's frequency response with the Propeller chip. As mentioned earlier, the small values and relatively high frequencies used with this circuit make it a little finicky. For example, if the capacitor is more than 90° from the loop, the resonant frequency drops, if it is less than 90° , the resonant frequency increases. Also, the various parts will have slightly different characteristics, so it will take some tinkering to set up the circuit so that the resistor divider will cause the LC circuit's output signal to stay below the I/O pin threshold at resonant frequency and creep above it as the frequency sweep gets either further above or below it.

Figure 25 shows Calibrate Metal Detector.spin's output after the circuit has been calibrated. The high tick counts on the left actually resemble Figure 20's frequency response plot. On the other hand, the tick counts on the right show that there is still a resonant frequency, but it's up in the 52+ MHz range. Because the circuit inductive loop also experiences increased resistance, it may prevent the circuit from attenuating the signal so that the high ticks never quite make it to zero.

Figure 25: Calibrated Metal Detector Response – without metal (left) and with metal (right)



Here is how to manually calibrate your metal detector circuit. Automatic detection is left for the Projects section.

- ✓ Load CalibrateMetalDetector.spin into the Propeller Chip.
- ✓ Connect with PropellerCOM.ht.
- ✓ Press/release the PE Platform's Reset button to restart the program.
- ✓ When prompted, enter a starting frequency, try 48_000_000.
- ✓ When prompted, enter a frequency step, try 200_000.

- ✓ Compare your display to the left sweep shown in Figure 25, looking not so much for your values to match but that the overall profile is similar, which clearly indicates a resonant frequency centered where the count = 0.
- ✓ If your display is showing a clear resonant frequency, try placing a quarter coin directly under the metal loop, and press R to repeat the same frequency sweep.
- ✓ If your display changes significantly, like the right sweep shown in Figure 25, your metal detector apparently doesn't need any further calibration.
- ✓ If you are not seeing clear resonant frequencies, try refining the frequency start and frequency step values so that the sweep clearly indicates the presence and absence of metal.
- ✓ If there is no apparent filter response, either all zeros, or values that are larger without an apparent dip, try the suggestions below.

The circuit may instead need some tuning before it displays responses similar to those in Figure 25. If you instead see numbers that are either too high to show zeros or too low (all zeros), the voltage divider likely needs to be adjusted. It is designed to make the output just under the threshold voltage.

- ✓ If you see all zeros, the voltage divider needs to take less away from the signal. First, try successively larger resistors in place of R3. Try 1 k Ω , then 2 k Ω , then 10 k Ω .
- ✓ If the voltage divider is still taking too much away from the signal, disconnect R3 entirely, and instead add an R4 in parallel with R1. Start with a large resistor like 10 k Ω , and work downward again, 2 k Ω , 1 k Ω , and so on. Repeat the frequency sweep between each adjustment until you find a voltage divider that works for your circuit and Propeller chip's threshold voltage.
- ✓ If there is no apparent filter response, in other words, no cluster of low values like in Figure 25, you may need to search lower or higher frequencies after adjusting the voltage divider. This involves starting the sweep at lower values, like 46 MHz instead of 48, and using smaller increments, like 100_000 instead of 200_000, and selecting "M" or enter when prompted by HyperTerminal.
- ✓ Once you are getting good resonant frequencies, can you also discern the metal object's distance, say between 1 mm, 5 mm and 10 mm?

```

{{
CalibrateMetalDetector.spin
}}

CON

_clkmode = xtall1 + pll16x          ' Set up 80 MHz internal clock
_xinfreq = 5_000_000

OBJ

Debug   : "FullDuplexSerialPlus"
freq    : "SquareWave"

PUB Init | count, f, fstart, fstep, c

' Start FullDuplexSerialPlus
Debug.start(31, 30, 0, 57600)
waitcnt(clkfreq*2 + cnt)

' Configure ctra module for 50 MHz square wave
ctra[30..26] := %00010

```

```

ctra[25..23] := %110
ctra[8..0] := 15
frq.Freq(0, 15, 50_000_000)
dira[15]~~

'Configure ctrb module for negative edge counting
ctrb[30..26] := %01000
ctrb[8..0] := 13
frqb := 1

c := "S"

repeat' until c == "Q" or c == "q"

case c
  "S", "s":
    Debug.Str(String(10, 13, "Starting Frequency: "))
    f := Debug.GetDec
    Debug.Str(String(10, 13, "Step size: "))
    fstep := Debug.GetDec
    Debug.Str(String(10, 13))

case c
  "S", "s", 13, 10, "M", "m":
    repeat 22
      frq.Freq(0, 15, f)
      count := phsb
      waitcnt(clkfreq/10000 + cnt)
      count := phsb - count
      Debug.Str(String(10, 13, "Freq = "))
      Debug.Dec(f)
      Debug.Str(String("  count = "))
      Debug.Dec(count)
      waitcnt(clkfreq/20 + cnt)
      f += fstep

    Debug.str(String(10,13,"Enter->more, Q->Quit, S->Start over, R->repeat: "))
    c := Debug.rx
    Debug.str(String(10, 13))

  "R", "r":
    f -= (22 * fstep)
    c := "m"

  "Q", "q": quit

Debug.str(String(10, 13, "Bye!"))

```

Questions/Exercise/Projects/Solutions

Coming soon

Appendix A – SquareWave Object

```
`` SquareWave.spin
PUB Freq(Module, Pin, Frequency) | s, d, ctr
`` Determine CTR settings for synthesis of 0..128 MHz in 1 Hz steps
``
`` in:   Pin = pin to output frequency on
``       Freq = actual Hz to synthesize
``
`` out:  ctr and frq hold ctra/ctrb and frqa/frqb values
``
`` Uses NCO mode %00100 for 0..499_999 Hz
`` Uses PLL mode %00010 for 500_000..128_000_000 Hz

Frequency := Frequency #> 0 <# 128_000_000    'limit frequency range

if Frequency < 500_000                        'if 0 to 499_999 Hz,
  ctr := constant(%00100 << 26)              '..set NCO mode
  s := 1                                       '..shift = 1
else                                           'if 500_000 to 128_000_000 Hz,
  ctr := constant(%00010 << 26)              '..set PLL mode
  d := >|((Frequency - 1) / 1_000_000)        'determine PLLDIV
  s := 4 - d                                  'determine shift
  ctr |= d << 23                              'set PLLDIV

spr[10 + module] := fraction(Frequency, CLKFREQ, s)    'Compute frqa/frqb value
ctr |= Pin                                             'set PINA to complete ctra/ctrb value
spr[8 + module] := ctr

dira[Pin]~~

PUB NcoFrqReg(frequency) : frqReg
{{
Returns frqReg = frequency × (232 ÷ clkfreq) calculated with binary long
division. This is faster than the floating point library, and takes less
code space. This method is an adaptation of the CTR object's fraction
method.
}}
frqReg := fraction(frequency, clkfreq, 1)

PRI fraction(a, b, shift) : f

if shift > 0                                     'if shift, pre-shift a or b left
  a <<= shift                                     'to maintain significant bits while
if shift < 0                                     'insuring proper result
  b <<= -shift

repeat 32                                       'perform long division of a/b
  f <<= 1
  if a => b
    a -= b
    f++
  a <<= 1
```