

# **SN8P2522**

## **USER'S MANUAL**

Version 1.2

**SN8P2522**

**SN8P2521**

# **SONiX 8-Bit Micro-Controller**

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## AMENDENT HISTORY

Version	Date	Description
VER 0.1	Dec. 2008	Preliminary first issue.
VER 0.2	Mar. 2009	Major modification: 1. IHRC frequency is modified to 16MHz and related sections. 2. Fcpu is modified to Fhosc/2~Fhosc/16 and related sections. 3. OTP programming pin chapter.
VER 1.0	Apr. 2011	1. Modify comparator de-bounce configuration. 2. Modify SN8P2522 EV-Kit section. 3. Modify "DEVELOPMENT TOOL" description. 4. Modify "MARKING EXAMPLE" description. 5. "Chapter 6.12" : Modify "the comparator interrupt trigger edge direction depend on CM0G[1:0]" description. 6. "Chapter 9.3" : Modify CMP0M1 register's description (CM0G[1:0]). 7. Add "Chapter 2.5" LVD_MAX code option description. 8. Modify "Chapter 12.3 CHARACTERISTIC GRAPHS"
VER 1.1	Jan. 2012	1. Add "SN8P2521" part number. 2. Add PDIP14 and SOP14 package types.
VER 1.2	Sep. 2012	Modify "ELECTRICAL CHARACTERICS" chapter operating temperature from 0~70°C to -20~85°C and others.

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# 1 PRODUCT OVERVIEW

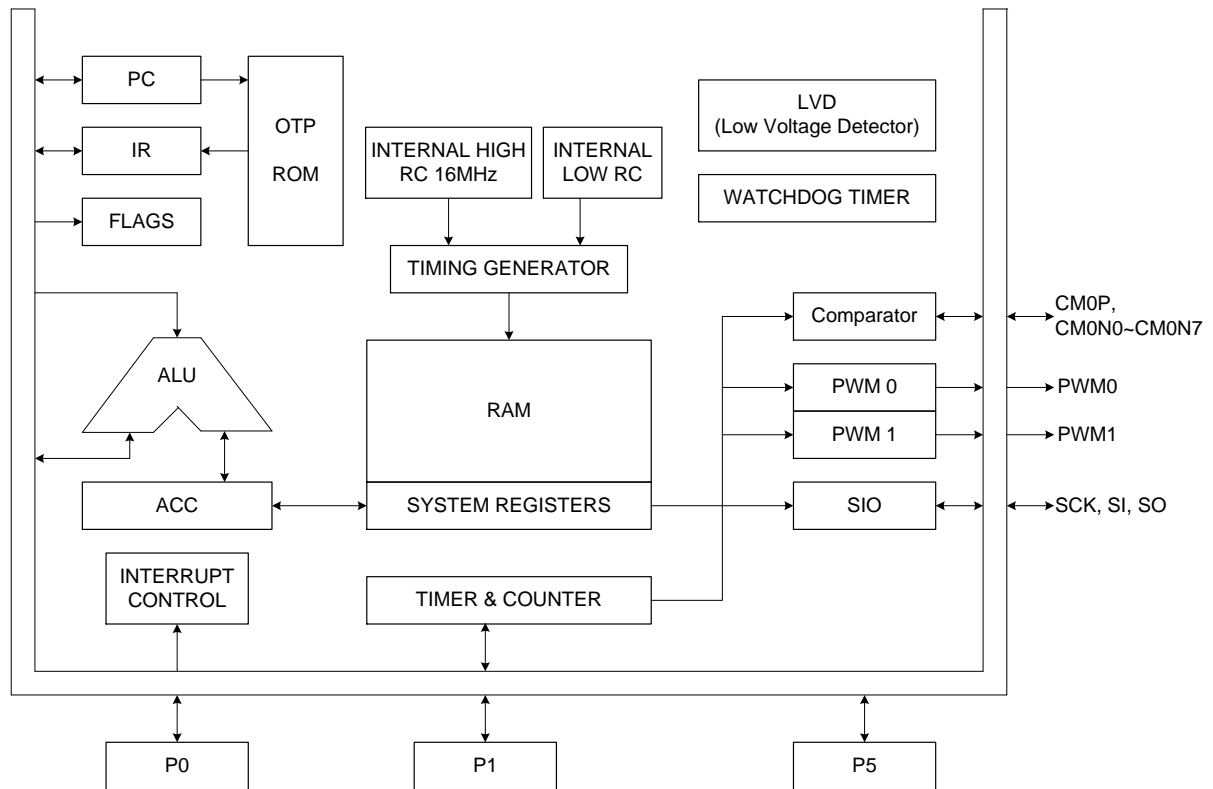
## 1.1 FEATURES

- ◆ **Memory configuration**  
ROM size: 2K \* 16 bits.  
RAM size: 128 \* 8 bits.
- ◆ **8 levels stack buffer.**
- ◆ **7 interrupt sources**  
6 internal interrupts: T0, T1, TC0, TC1, CM0, SIO  
1 external interrupt: INT0
- ◆ **I/O pin configuration**  
Bi-directional: P0, P1, P5.  
Wakeup: P0, P1 level change.  
Pull-up resistors: P0, P1, P5.  
Programmable open-drain: P5.0~P5.4  
Comparator input pin: CM0N0~CM0N7.  
200mA sunk pin: P5.3, P5.4.
- ◆ **Fcpu (Instruction cycle)**  
 $F_{cpu} = F_{psc}/2, F_{osc}/4, F_{osc}/8, F_{osc}/16$ .
- ◆ **Powerful instructions**  
Instruction's length is one word.  
Most of instructions are one cycle only.  
All ROM area JMP/CALL instruction.  
All ROM area lookup table function (MOVC).
- ◆ **One 8-bit basic timer. (T0).**
- ◆ **One 8-bit timer with external event counter and duty/cycle programmable PWM. (TC0).**
- ◆ **One 8-bit timer with duty/cycle programmable PWM. (TC1).**
- ◆ **One 16-bit capture timer. (T1).**
- ◆ **8-channel comparator.**
- ◆ **SIO serial input/output interface.**
- ◆ **On chip watchdog timer and clock source is Internal low clock RC type (16KHz @3V, 32KHz @5V).**
- ◆ **Two system clocks**  
Internal high clock: RC type 16MHz  
Internal low clock: RC type 16KHz(3V), 32KHz(5V)
- ◆ **Four operating modes**  
Normal mode: Both high and low clock active  
Slow mode: Low clock only  
Sleep mode: Both high and low clock stop  
Green mode: Periodical wakeup by timer
- ◆ **Package (Chip form support)**  
PDIP 18 pin  
SOP 18 pin  
SSOP 20 pin  
PDIP 14 pin  
SOP 14 pin

☞ **Features Selection Table**

CHIP	ROM	RAM	Stack	Timer				I/O	Comparator	PWM	Wake-up Pin No.	Package
				T0	TC0	TC1	T1					
SN8P2522	2K*16	128	8	V	V	V	V	16	8-ch	2	9	PDIP18/ SOP18/SSOP20
SN8P2521	2K*16	128	8	V	V	V	V	12	5-ch	2	6	PDIP14/SOP14

## 1.2 SYSTEM BLOCK DIAGRAM





## 1.3 PIN ASSIGNMENT

**SN8P2522P (PDIP 18 pins)**

**SN8P2522S (SOP 18 pins)**

P1.3/CM0N3	1	U	18	P1.4/CM0N4
P1.2/CM0N2	2		17	P1.5/CM0N5
P1.1/CM0N1	3		16	P1.6/CM0N6
P1.0/CM0P/CM0N0	4		15	P1.7/CM0N7
VDD	5		14	VSS
RST/VPP/P5.6	6		13	P5.4/PWM0
P5.5	7		12	P5.3/PWM1
P5.2/SO	8		11	P0.0/INT0
P5.1/SI	9		10	P5.0/SCK
<b>SN8P2522P</b>				
<b>SN8P2522S</b>				

**SN8P2522X (SSOP 20 pins)**

VDD	1	U	20	VDD
RST/VPP/P5.6	2		19	P1.0/CM0P/CM0N0
P5.5	3		18	P1.1/CM0N1
P5.2/SO	4		17	P1.2/CM0N2
P5.1/SI	5		16	P1.3/CM0N3
P5.0/SCK	6		15	P1.4/CM0N4
P0.0/INT0	7		14	P1.5/CM0N5
P5.3/PWM1	8		13	P1.6/CM0N6
P5.4/PWM0	9		12	P1.7/CM0N7
VSS	10		11	VSS
<b>SN8P2522X</b>				

**SN8P2521P (PDIP 14 pins)**

**SN8P2521S (SOP 14 pins)**

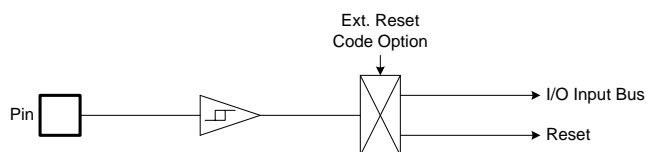
P1.2/CM0N2	1	U	14	P1.3/CM0N3
P1.1/CM0N1	2		13	P1.4/CM0N4
P1.0/CM0P/CM0N0	3		12	VSS
VDD	4		11	P5.4/PWM0
RST/VPP/P5.6	5		10	P5.3/PWM1
P5.2/SO	6		9	P0.0/INT0
P5.1/SI	7		8	P5.0/SCK
<b>SN8P2521P</b>				
<b>SN8P2521S</b>				

## 1.4 PIN DESCRIPTIONS

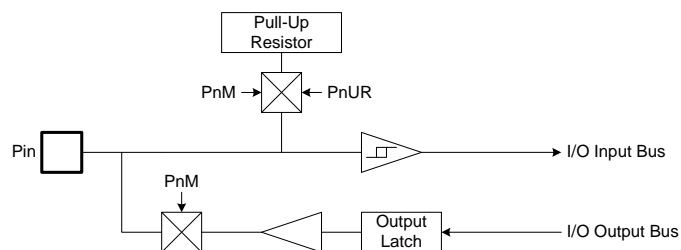
PIN NAME	TYPE	DESCRIPTION
VDD, VSS	P	Power supply input pins.
P5.6/RST/VPP	I, P	RST: System reset input pin. Schmitt trigger structure, low active, normal stay to "high".
		VPP: OTP 12.3V power input pin in programming mode.
		P5.6: Input only pin. Schmitt trigger structure. Built-in wakeup function.
		The external reset function must be disabled.
P0.0/INT0	I/O	Port 0.0 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors and wakeup function.
		INT0 trigger pin (Schmitt trigger). TC0 event counter input pin.
P1.0/CM0P/CM0N0	I/O	Port 1.0 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors and wakeup function.
		CM0P: Comparator positive input pin.
		CM0N0: Channel 0 of comparator negative input pin.
P1[7:1]/CM0N[7:1]	I/O	Port 1 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors and wakeup function.
		CM0N[7:1]: Channel 1~7 of comparator negative input pin.
P5.0/SCK	I/O	Port 5.0 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors. Programmable open-drain.
		SCK: SIO clock pin.
P5.1/SI	I/O	Port 5.1 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors. Programmable open-drain.
		SI: SIO data input pin.
P5.2/SO	I/O	Port 5.2 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors. Programmable open-drain.
		SO: SIO data output pin.
P5.3/PWM1	I/O	Port 5.3 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors. Programmable open-drain.
		PWM1: PWM output pin.
P5.4/PWM0	I/O	Port 5.4 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors. Programmable open-drain.
		PWM0: PWM output pin.
P5.5	I/O	Port 5.5 bi-direction pin. Schmitt trigger structure as input mode.
		Built-in pull-up resistors.

## 1.5 PIN CIRCUIT DIAGRAMS

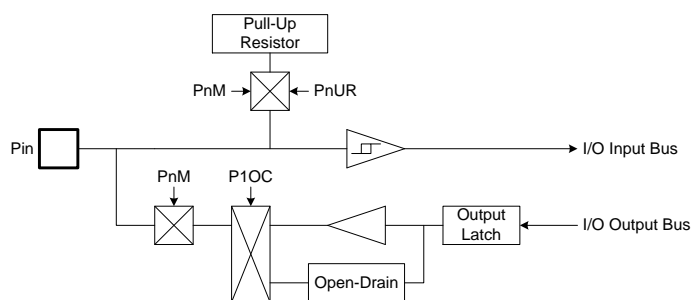
**Port 5.6 structure:**



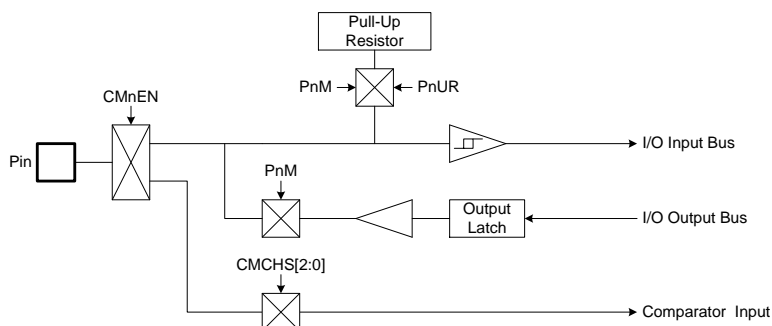
**Port 0, Port 5.5 structure:**



**Port 5.0~5.4 structure:**



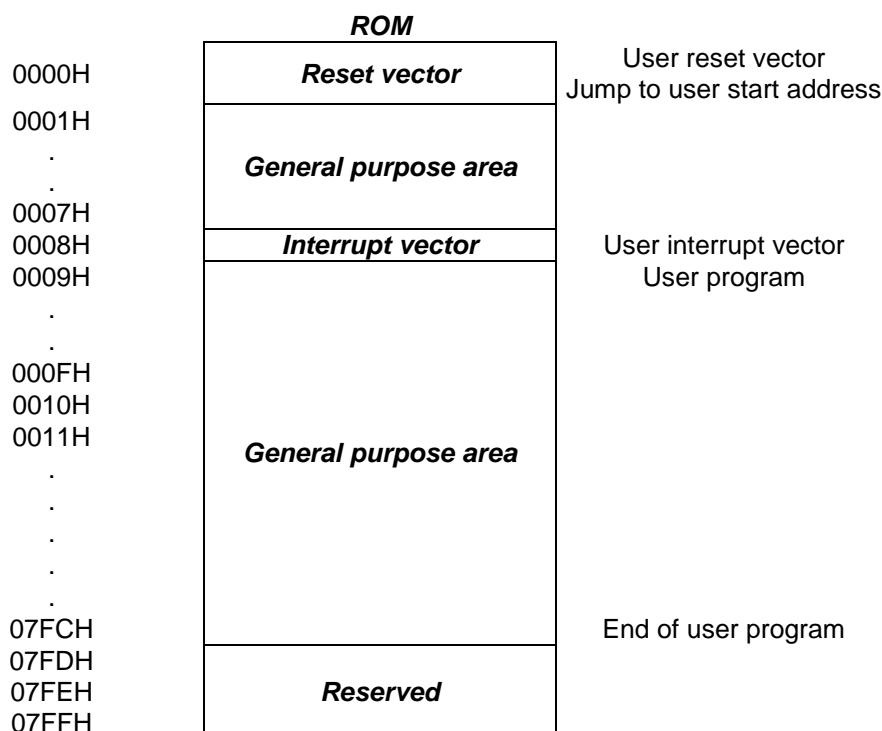
**Port 1.0~1.7 structure:**



# 2 CENTRAL PROCESSOR UNIT (CPU)

## 2.1 PROGRAM MEMORY (ROM)

☞ 2K words ROM



The ROM includes Reset vector, Interrupt vector, General purpose area and Reserved area. The Reset vector is program beginning address. The Interrupt vector is the head of interrupt service routine when any interrupt occurring. The General purpose area is main program area including main loop, sub-routines and data table.

## 2.1.1 RESET VECTOR (0000H)

A one-word vector address area is used to execute system reset.

- ☞ **Power On Reset (NT0=1, NPD=0).**
- ☞ **Watchdog Reset (NT0=0, NPD=0).**
- ☞ **External Reset (NT0=1, NPD=1).**

After power on reset, external reset or watchdog timer overflow reset, then the chip will restart the program from address 0000h and all system registers will be set as default values. It is easy to know reset status from NT0, NPD flags of PFLAG register. The following example shows the way to define the reset vector in the program memory.

### ➤ Example: Defining Reset Vector

```

                                ORG      0          ; 0000H
                                JMP      START      ; Jump to user program address.
                                ...
START:
                                ORG      10H
                                ; 0010H, The head of user program.
                                ; User program
                                ...
                                ENDP              ; End of program
```

## 2.1.2 INTERRUPT VECTOR (0008H)

A 1-word vector address area is used to execute interrupt request. If any interrupt service executes, the program counter (PC) value is stored in stack buffer and jump to 0008h of program memory to execute the vectored interrupt. Users have to define the interrupt vector. The following example shows the way to define the interrupt vector in the program memory.

\* **Note: "PUSH", "POP" instructions save and load ACC/PFLAG without (NT0, NPD). PUSH/POP buffer is a unique buffer and only one level.**

➤ **Example: Defining Interrupt Vector.** The interrupt service routine is following ORG 8.

```
.CODE
    ORG      0          ; 0000H
    JMP      START      ; Jump to user program address.
    ...

    ORG      8          ; Interrupt vector.
    PUSH     ; Save ACC and PFLAG register to buffers.
    ...
    POP      ; Load ACC and PFLAG register from buffers.
    RETI      ; End of interrupt service routine
    ...

START:
    ...              ; The head of user program.
    ...              ; User program
    JMP      START      ; End of user program
    ...

    ENDP              ; End of program
```

➤ **Example: Defining Interrupt Vector.** The interrupt service routine is following user program.

```
.CODE
    ORG      0          ; 0000H
    JMP      START      ; Jump to user program address.
    ...
    ORG      8          ; Interrupt vector.
    JMP      MY_IRQ      ; 0008H, Jump to interrupt service routine address.

START:
    ORG      10H         ; 0010H, The head of user program.
    ...                ; User program.
    ...
    JMP      START      ; End of user program.
    ...

MY_IRQ:
    ...                ; The head of interrupt service routine.
    PUSH                     ; Save ACC and PFLAG register to buffers.
    ...
    ...
    POP                      ; Load ACC and PFLAG register from buffers.
    RETI                   ; End of interrupt service routine.
    ...

    ENDP                ; End of program.
```

\* **Note:** It is easy to understand the rules of SONiX program from demo programs given above. These points are as following:

1. The address 0000H is a "JMP" instruction to make the program starts from the beginning.
2. The address 0008H is interrupt vector.
3. User's program is a loop routine for main purpose application.

### 2.1.3 LOOK-UP TABLE DESCRIPTION

In the ROM's data lookup function, Y register is pointed to middle byte address (bit 8~bit 15) and Z register is pointed to low byte address (bit 0~bit 7) of ROM. After MOVC instruction executed, the low-byte data will be stored in ACC and high-byte data stored in R register.

➤ **Example: To look up the ROM data located "TABLE1".**

```

        B0MOV    Y, #TABLE1$M    ; To set lookup table1's middle address
        B0MOV    Z, #TABLE1$L    ; To set lookup table1's low address.
        MOVC     ; To lookup data, R = 00H, ACC = 35H

        INCMS    Z                ; Increment the index address for next address.
        JMP      @F               ; Z+1
        INCMS    Y                ; Z is not overflow.
        NOP      ; Z overflow (FFH → 00), → Y=Y+1
        ;
        ;
@@:      MOVC     ; To lookup data, R = 51H, ACC = 05H.
        ...
TABLE1:  DW       0035H           ; To define a word (16 bits) data.
        DW       5105H
        DW       2012H
        ...

```

\* **Note:** The Y register will not increase automatically when Z register crosses boundary from 0xFF to 0x00. Therefore, user must be take care such situation to avoid look-up table errors. If Z register is overflow, Y register must be added one. The following INC\_YZ macro shows a simple method to process Y and Z registers automatically.

➤ **Example: INC\_YZ macro.**

```

INC_YZ    MACRO
        INCMS    Z                ; Z+1
        JMP      @F               ; Not overflow

        INCMS    Y                ; Y+1
        NOP      ; Not overflow

@@:
        ENDM

```



➤ **Example: Modify above example by “INC\_YZ” macro.**

```

        B0MOV    Y, #TABLE1$M    ; To set lookup table1's middle address
        B0MOV    Z, #TABLE1$L    ; To set lookup table1's low address.
        MOVC     ; To lookup data, R = 00H, ACC = 35H

        INC_YZ                    ; Increment the index address for next address.
        ;
@@:      MOVC     ; To lookup data, R = 51H, ACC = 05H.
        ...
TABLE1:  DW       0035H          ; To define a word (16 bits) data.
        DW       5105H
        DW       2012H
        ...

```

The other example of look-up table is to add Y or Z index register by accumulator. Please be careful if “carry” happen.

➤ **Example: Increase Y and Z register by B0ADD/ADD instruction.**

```

        B0MOV    Y, #TABLE1$M    ; To set lookup table's middle address.
        B0MOV    Z, #TABLE1$L    ; To set lookup table's low address.

        B0MOV    A, BUF          ; Z = Z + BUF.
        B0ADD    Z, A

        B0BTS1   FC              ; Check the carry flag.
        JMP      GETDATA         ; FC = 0
        INCMS    Y               ; FC = 1. Y+1.
        NOP

GETDATA: MOVC                    ;
        ; To lookup data. If BUF = 0, data is 0x0035
        ; If BUF = 1, data is 0x5105
        ; If BUF = 2, data is 0x2012
        ...

TABLE1:  DW       0035H          ; To define a word (16 bits) data.
        DW       5105H
        DW       2012H
        ...

```

## 2.1.4 JUMP TABLE DESCRIPTION

The jump table operation is one of multi-address jumping function. Add low-byte program counter (PCL) and ACC value to get one new PCL. If PCL is overflow after PCL+ACC, PCH adds one automatically. The new program counter (PC) points to a series jump instructions as a listing table. It is easy to make a multi-jump program depends on the value of the accumulator (A).

\* **Note:** PCH only support PC up counting result and doesn't support PC down counting. When PCL is carry after PCL+ACC, PCH adds one automatically. If PCL borrow after PCL-ACC, PCH keeps value and not change.

➤ **Example: Jump table.**

```

ORG      0X0100      ; The jump table is from the head of the ROM boundary

B0ADD    PCL, A       ; PCL = PCL + ACC, PCH + 1 when PCL overflow occurs.
JMP      A0POINT     ; ACC = 0, jump to A0POINT
JMP      A1POINT     ; ACC = 1, jump to A1POINT
JMP      A2POINT     ; ACC = 2, jump to A2POINT
JMP      A3POINT     ; ACC = 3, jump to A3POINT

```

SONiX provides a macro for safe jump table function. This macro will check the ROM boundary and move the jump table to the right position automatically. The side effect of this macro maybe wastes some ROM size.

➤ **Example: If “jump table” crosses over ROM boundary will cause errors.**

```

@JMP_A    MACRO      VAL
IF        (($+1) !& 0XFF00) != (($+(VAL)) !& 0XFF00)
JMP       ($ | 0XFF)
ORG       ($ | 0XFF)
ENDIF
B0ADD     PCL, A
ENDM

```

\* **Note:** “VAL” is the number of the jump table listing number.

➤ **Example: “@JMP\_A” application in SONiX macro file called “MACRO3.H”.**

B0MOV	A, BUF0	; “BUF0” is from 0 to 4.
@JMP_A	5	; The number of the jump table listing is five.
JMP	A0POINT	; ACC = 0, jump to A0POINT
JMP	A1POINT	; ACC = 1, jump to A1POINT
JMP	A2POINT	; ACC = 2, jump to A2POINT
JMP	A3POINT	; ACC = 3, jump to A3POINT
JMP	A4POINT	; ACC = 4, jump to A4POINT

If the jump table position is across a ROM boundary (0x00FF~0x0100), the “@JMP\_A” macro will adjust the jump table routine begin from next RAM boundary (0x0100).

➤ **Example: “@JMP\_A” operation.**

**; Before compiling program.**

ROM address			
	B0MOV	A, BUF0	; “BUF0” is from 0 to 4.
	@JMP_A	5	; The number of the jump table listing is five.
0X00FD	JMP	A0POINT	; ACC = 0, jump to A0POINT
0X00FE	JMP	A1POINT	; ACC = 1, jump to A1POINT
0X00FF	JMP	A2POINT	; ACC = 2, jump to A2POINT
0X0100	JMP	A3POINT	; ACC = 3, jump to A3POINT
0X0101	JMP	A4POINT	; ACC = 4, jump to A4POINT

**; After compiling program.**

ROM address			
	B0MOV	A, BUF0	; “BUF0” is from 0 to 4.
	@JMP_A	5	; The number of the jump table listing is five.
0X0100	JMP	A0POINT	; ACC = 0, jump to A0POINT
0X0101	JMP	A1POINT	; ACC = 1, jump to A1POINT
0X0102	JMP	A2POINT	; ACC = 2, jump to A2POINT
0X0103	JMP	A3POINT	; ACC = 3, jump to A3POINT
0X0104	JMP	A4POINT	; ACC = 4, jump to A4POINT

## 2.1.5 CHECKSUM CALCULATION

The last ROM address are reserved area. User should avoid these addresses (last address) when calculate the Checksum value.

➤ **Example: The demo program shows how to calculated Checksum from 00H to the end of user's code.**

```

MOV      A,#END_USER_CODE$L
B0MOV    END_ADDR1, A      ; Save low end address to end_addr1
MOV      A,#END_USER_CODE$M
B0MOV    END_ADDR2, A      ; Save middle end address to end_addr2
CLR      Y                  ; Set Y to 00H
CLR      Z                  ; Set Z to 00H

@@:
        MOV      FC          ; Clear C flag
        B0BSET   FC          ; Add A to Data1
        ADD      DATA1, A
        MOV      A, R
        ADC      DATA2, A    ; Add R to Data2
        JMP      END_CHECK    ; Check if the YZ address = the end of code

AAA:
        INCMS    Z            ; Z=Z+1
        JMP      @B           ; If Z != 00H calculate to next address
        JMP      Y_ADD_1      ; If Z = 00H increase Y

END_CHECK:
        MOV      A, END_ADDR1
        CMPSR    A, Z         ; Check if Z = low end address
        JMP      AAA          ; If Not jump to checksum calculate
        MOV      A, END_ADDR2
        CMPSR    A, Y         ; If Yes, check if Y = middle end address
        JMP      AAA          ; If Not jump to checksum calculate
        JMP      CHECKSUM_END ; If Yes checksum calculated is done.

Y_ADD_1:
        INCMS    Y            ; Increase Y
        NOP
        JMP      @B           ; Jump to checksum calculate

CHECKSUM_END:
        ...
        ...

END_USER_CODE:                ; Label of program end

```

## 2.2 DATA MEMORY (RAM)

### 128 X 8-bit RAM

Address		RAM location
BANK 0	000h	General purpose area
	"	
	"	
	"	
	"	
	07Fh	System register
	080h	
	"	
	"	
	"	
	0FFh	End of bank 0 area

080h~0FFh of Bank 0 store system registers (128 bytes).

### 2.2.1 SYSTEM REGISTER

#### 2.2.1.1 SYSTEM REGISTER TABLE

	0	1	2	3	4	5	6	7	8	9	A	B	C	D	E	F
8	L	H	R	Z	Y	-	PFLAG	-	-	-	-	-	-	-	-	-
9	-	-	-	-	-	-	-	-	-	-	-	-	CMP0M	CM0PM1	-	-
A	T1M	T1CL	T1CH	T1VCH	T1VCL	T1CKM	-	-	-	-	-	-	-	-	-	-
B	-	-	-	-	SIOM	SIOR	SIOB	-	P0M	-	-	-	-	-	-	PEDGE
C	P1W	P1M	-	-	-	P5M	-	-	INTRQ	INTEN	OSCM	-	WDTR	TC0R	PCL	PCH
D	P0	P1	-	-	-	P5	-	-	T0M	T0C	TC0M	TC0C	TC1M	TC1C	TC1R	STKP
E	P0UR	P1UR	-	-	-	P5UR	@HL	@YZ	TC0D	P1OC	TC1D	-	-	-	-	-
F	STK7L	STK7H	STK6L	STK6H	STK5L	STK5H	STK4L	STK4H	STK3L	STK3H	STK2L	STK2H	STK1L	STK1H	STK0L	STK0H

#### 2.2.1.2 SYSTEM REGISTER DESCRIPTION

H, L = Working, @HL.

R = Working register and ROM look-up data buffer.

CMP0M = Comparator configuration register.

T1M = T1 mode register.

T1VCH, T1VCL = T1 event counter counting register.

SIOM = SIO configuration register.

SIOB = SIO data buffer.

PEDGE = P0.0 edge direction register.

INTEN = Interrupt enable register.

WDTR = Watchdog timer clear register.

Pn = Port n data buffer.

T0M = T0 mode register.

TC0M = TC0 mode register.

TC0R = TC0 auto-reload data buffer.

TC1M = TC1 mode register.

TC1R = TC1 auto-reload data buffer.

@HL = RAM HL indirect addressing index pointer.

STK0~STK7 = Stack 0 ~ stack 7 buffer.

Y, Z = Working, @YZ and ROM addressing register.

PFLAG = ROM page and special flag register.

CMP0M1 = Comparator configuration register.

T1CH, T1CL = T1 counting register.

T1CKM = T1 event counter mode register.

SIOR = SIO clock register.

PnM = Port n input/output mode register.

INTRQ = Interrupt request register.

OSCM = Oscillator mode register.

PCH, PCL = Program counter.

PnUR = Port n pull-up resistor control register.

T0C = T0 counting register.

TC0C = TC0 counting register.

TC0D = TC0 duty control register.

TC1C = TC1 counting register.

TC1D = TC1 duty control register.

@YZ = RAM YZ indirect addressing index pointer.

STKP = Stack pointer buffer.

### 2.2.1.3 BIT DEFINITION of SYSTEM REGISTER

Address	Bit7	Bit6	Bit5	Bit4	Bit3	Bit2	Bit1	Bit0	R/W	Remarks
080H	LBIT7	LBIT6	LBIT5	LBIT4	LBIT3	LBIT2	LBIT1	LBIT0	R/W	L
081H	HBIT7	HBIT6	HBIT5	HBIT4	HBIT3	HBIT2	HBIT1	HBIT0	R/W	H
082H	RBIT7	RBIT6	RBIT5	RBIT4	RBIT3	RBIT2	RBIT1	RBIT0	R/W	R
083H	ZBIT7	ZBIT6	ZBIT5	ZBIT4	ZBIT3	ZBIT2	ZBIT1	ZBIT0	R/W	Z
084H	YBIT7	YBIT6	YBIT5	YBIT4	YBIT3	YBIT2	YBIT1	YBIT0	R/W	Y
086H	NT0	NPD	LVD36	LVD24		C	DC	Z	R/W	PFLAG
09CH	CM0EN	CM0OUT		CM0S1	CM0S0	CMCH2	CMCH1	CMCH0	R/W	CMP0M
09DH					CMDB1	CMDB0	CM0G1	CM0G0	R/W	CMP0M1
0A0H	T1ENB	T1rate2	T1rate1	T1rate0	CPTCKS	CPTStart	CPTG1	CPTG0	R/W	T1M
0A1H	T1CL7	T1CL6	T1CL5	T1CL4	T1CL3	T1CL2	T1CL1	T1CL0	R/W	T1CL
0A2H	T1CH7	T1CH6	T1CH5	T1CH4	T1CH3	T1CH2	T1CH1	T1CH0	R/W	T1CH
0A3H	T1VC7	T1VC6	T1VC5	T1VC4	T1VC3	T1VC2	T1VC1	T1VC0	R/W	T1VCL
0A4H					T1VC11	T1VC10	T1VC9	T1VC8	R/W	T1VCH
0A5H	CPTVC								R/W	T1CKM
0B4H	SENB	START	SRATE1	SRATE0	MLSB	SCLKMD	CPOL	CPHA	R/W	SIOM
0B5H	SIOR7	SIOR6	SIOR5	SIOR4	SIOR3	SIOR2	SIOR1	SIOR0	W	SIOR
0B6H	SIOB7	SIOB6	SIOB5	SIOB4	SIOB3	SIOB2	SIOB1	SIOB0	R/W	SIOB
0B8H								P00M	R/W	P0M
0BFH				P00G1	P00G0				R/W	PEDGE
0C0H	P17W	P16W	P15W	P14W	P13W	P12W	P11W	P10W	W	P1W
0C1H	P17M	P16M	P15M	P14M	P13M	P12M	P11M	P10M	R/W	P1M
0C5H			P55M	P54M	P53M	P52M	P51M	P50M	R/W	P5M
0C8H	CM0IRQ	TC1IRQ	TC0IRQ	T0IRQ	SIOIRQ	T1IRQ		P00IRQ	R/W	INTRQ
0C9H	CM0IEN	TC1IEN	TC0IEN	T0IEN	SIOIEN	T1IEN		P00IEN	R/W	INTEN
0CAH				CPUM1	CPUM0	CLKMD	STPHX		R/W	OSCM
0CCH	WDTR7	WDTR6	WDTR5	WDTR4	WDTR3	WDTR2	WDTR1	WDTR0	W	WDTR
0CDH	TC0R7	TC0R6	TC0R5	TC0R4	TC0R3	TC0R2	TC0R1	TC0R0	W	TC0R
0CEH	PC7	PC6	PC5	PC4	PC3	PC2	PC1	PC0	R/W	PCL
0CFH						PC10	PC9	PC8	R/W	PCH
0D0H								P00	R/W	P0
0D1H	P17	P16	P15	P14	P13	P12	P11	P10	R/W	P1
0D5H		P56	P55	P54	P53	P52	P51	P50	R/W	P5
0D8H	T0ENB	T0rate2	T0rate1	T0rate0					R/W	T0M
0D9H	T0C7	T0C6	T0C5	T0C4	T0C3	T0C2	T0C1	T0C0	R/W	T0C
0DAH	TC0ENB	TC0rate2	TC0rate1	TC0rate0	TC0CKS1	TC0CKS0		PWM0OUT	R/W	TC0M
0DBH	TC0C7	TC0C6	TC0C5	TC0C4	TC0C3	TC0C2	TC0C1	TC0C0	R/W	TC0C
0DCH	TC1ENB	TC1rate2	TC1rate1	TC1rate0		TC1CKS0		PWM1OUT	R/W	TC1M
0DDH	TC1C7	TC1C6	TC1C5	TC1C4	TC1C3	TC1C2	TC1C1	TC1C0	R/W	TC1C
0DEH	TC1R7	TC1R6	TC1R5	TC1R4	TC1R3	TC1R2	TC1R1	TC1R0	W	TC1R
0DFH	GIE					STKPB2	STKPB1	STKPB0	R/W	STKP
0E0H								P00R	W	P0UR
0E1H	P17R	P16R	P15R	P14R	P13R	P12R	P11R	P10R	W	P1UR
0E5H			P55R	P54R	P53R	P52R	P51R	P50R	W	P5UR
0E6H	@HL7	@HL6	@HL5	@HL4	@HL3	@HL2	@HL1	@HL0	R/W	@HL
0E7H	@YZ7	@YZ6	@YZ5	@YZ4	@YZ3	@YZ2	@YZ1	@YZ0	R/W	@YZ
0E8H	TC0D7	TC0D6	TC0D5	TC0D4	TC0D3	TC0D2	TC0D1	TC0D0	R/W	TC0D
0E9H		P54OC	P53OC	P52OC	P51OC	P50OC			W	P1OC
0EAH	TC1D7	TC1D6	TC1D5	TC1D4	TC1D3	TC1D2	TC1D1	TC1D0	R/W	TC1D
0F0H	S7PC7	S7PC6	S7PC5	S7PC4	S7PC3	S7PC2	S7PC1	S7PC0	R/W	STK7L
0F1H						S7PC10	S7PC9	S7PC8	R/W	STK7H
0F2H	S6PC7	S6PC6	S6PC5	S6PC4	S6PC3	S6PC2	S6PC1	S6PC0	R/W	STK6L
0F3H						S6PC10	S6PC9	S6PC8	R/W	STK6H
0F4H	S5PC7	S5PC6	S5PC5	S5PC4	S5PC3	S5PC2	S5PC1	S5PC0	R/W	STK5L
0F5H						S5PC10	S5PC9	S5PC8	R/W	STK5H
0F6H	S4PC7	S4PC6	S4PC5	S4PC4	S4PC3	S4PC2	S4PC1	S4PC0	R/W	STK4L
0F7H						S4PC10	S4PC9	S4PC8	R/W	STK4H
0F8H	S3PC7	S3PC6	S3PC5	S3PC4	S3PC3	S3PC2	S3PC1	S3PC0	R/W	STK3L
0F9H						S3PC10	S3PC9	S3PC8	R/W	STK3H
0FAH	S2PC7	S2PC6	S2PC5	S2PC4	S2PC3	S2PC2	S2PC1	S2PC0	R/W	STK2L
0FBH						S2PC10	S2PC9	S2PC8	R/W	STK2H
0FCH	S1PC7	S1PC6	S1PC5	S1PC4	S1PC3	S1PC2	S1PC1	S1PC0	R/W	STK1L
0FDH						S1PC10	S1PC9	S1PC8	R/W	STK1H
0FEH	S0PC7	S0PC6	S0PC5	S0PC4	S0PC3	S0PC2	S0PC1	S0PC0	R/W	STK0L
0FFH						S0PC10	S0PC9	S0PC8	R/W	STK0H

**\* Note:**

1. To avoid system error, make sure to put all the "0" and "1" as it indicates in the above table.
2. All of register names had been declared in SN8ASM assembler.
3. One-bit name had been declared in SN8ASM assembler with "F" prefix code.
4. "b0bset", "b0bclr", "bset", "bclr" instructions are only available to the "R/W" registers.

## 2.2.2 ACCUMULATOR

The ACC is an 8-bit data register responsible for transferring or manipulating data between ALU and data memory. If the result of operating is zero (Z) or there is carry (C or DC) occurrence, then these flags will be set to PFLAG register. ACC is not in data memory (RAM), so ACC can't be access by "B0MOV" instruction during the instant addressing mode.

➤ **Example: Read and write ACC value.**

```

; Read ACC data and store in BUF data memory.

```

MOV BUF, A

; Write a immediate data into ACC.

```
MOV    A, #0FH
```

```
; Write ACC data from BUF data memory.
```

MOV A, BUF

; or

B0MOV      A, BUF

The system doesn't store ACC and PFLAG value when interrupt executed. ACC and PFLAG data must be saved to other data memories. "PUSH", "POP" save and load ACC, PFLAG data into buffers.

- **Example: Protect ACC and working registers.**

INT\_SERVICE:

**PUSH** ; Save ACC and PFLAG to buffers.

...

**POP**

POP ; Load ACC and PFLAG from buffers.

RETI ; Exit interrupt service vector



## 2.2.3 PROGRAM FLAG

The PFLAG register contains the arithmetic status of ALU operation, system reset status and LVD detecting status. NT0, NPD bits indicate system reset status including power on reset, LVD reset, reset by external pin active and watchdog reset. C, DC, Z bits indicate the result status of ALU operation. LVD24, LVD36 bits indicate LVD detecting power voltage status.

086H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>PFLAG</b>	NT0	NPD	LVD36	LVD24	-	C	DC	Z
Read/Write	R/W	R/W	R	R	-	R/W	R/W	R/W
After reset	-	-	0	0	-	0	0	0

Bit [7:6] **NT0, NPD**: Reset status flag.

NT0	NPD	Reset Status
0	0	Watch-dog time out
0	1	Reserved
1	0	Reset by LVD
1	1	Reset by external Reset Pin

Bit 5 **LVD36**: LVD 3.6V operating flag and only support LVD code option is LVD\_H.

0 = Inactive ( $V_{DD} > 3.6V$ ).

1 = Active ( $V_{DD} \leq 3.6V$ ).

Bit 4 **LVD24**: LVD 2.4V operating flag and only support LVD code option is LVD\_M.

0 = Inactive ( $V_{DD} > 2.4V$ ).

1 = Active ( $V_{DD} \leq 2.4V$ ).

Bit 2 **C**: Carry flag

1 = Addition with carry, subtraction without borrowing, rotation with shifting out logic "1", comparison result  $\geq 0$ .

0 = Addition without carry, subtraction with borrowing signal, rotation with shifting out logic "0", comparison result  $< 0$ .

Bit 1 **DC**: Decimal carry flag

1 = Addition with carry from low nibble, subtraction without borrow from high nibble.

0 = Addition without carry from low nibble, subtraction with borrow from high nibble.

Bit 0 **Z**: Zero flag

1 = The result of an arithmetic/logic/branch operation is zero.

0 = The result of an arithmetic/logic/branch operation is not zero.

\* **Note:** Refer to instruction set table for detailed information of C, DC and Z flags.

## 2.2.4 PROGRAM COUNTER

The program counter (PC) is a 11-bit binary counter separated into the high-byte 3 and the low-byte 8 bits. This counter is responsible for pointing a location in order to fetch an instruction for kernel circuit. Normally, the program counter is automatically incremented with each instruction during program execution.

Besides, it can be replaced with specific address by executing CALL or JMP instruction. When JMP or CALL instruction is executed, the destination address will be inserted to bit 0 ~ bit 10.

	Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>PC</b>	-	-	-	-	-	PC10	PC9	PC8	PC7	PC6	PC5	PC4	PC3	PC2	PC1	PC0
After reset	-	-	-	-	-	0	0	0	0	0	0	0	0	0	0	0
	PCH								PCL							

### ☞ ONE ADDRESS SKIPPING

There are nine instructions (CMPRS, INCS, INCMS, DECS, DECMS, BTS0, BTS1, B0BTS0, B0BTS1) with one address skipping function. If the result of these instructions is true, the PC will add 2 steps to skip next instruction.

***If the condition of bit test instruction is true, the PC will add 2 steps to skip next instruction.***

```

        B0BTS1    FC          ; To skip, if Carry_flag = 1
        JMP      C0STEP      ; Else jump to C0STEP.
        ...
        ...
C0STEP:    NOP

        B0MOV     A, BUF0     ; Move BUF0 value to ACC.
        B0BTS0    FZ          ; To skip, if Zero flag = 0.
        JMP      C1STEP      ; Else jump to C1STEP.
        ...
        ...
C1STEP:    NOP

```

***If the ACC is equal to the immediate data or memory, the PC will add 2 steps to skip next instruction.***

```

        CMPRS     A, #12H     ; To skip, if ACC = 12H.
        JMP      C0STEP      ; Else jump to C0STEP.
        ...
        ...
C0STEP:    NOP

```

*If the destination increased by 1, which results overflow of 0xFF to 0x00, the PC will add 2 steps to skip next instruction.*

**INCS instruction:**

**INCS**      BUF0  
JMP      C0STEP      ; Jump to C0STEP if ACC is not zero.

...

...

C0STEP:      NOP

**INCMS instruction:**

**INCMS**      BUF0  
JMP      C0STEP      ; Jump to C0STEP if BUF0 is not zero.

...

...

C0STEP:      NOP

*If the destination decreased by 1, which results underflow of 0x01 to 0x00, the PC will add 2 steps to skip next instruction.*

**DECS instruction:**

**DECS**      BUF0  
JMP      C0STEP      ; Jump to C0STEP if ACC is not zero.

...

...

C0STEP:      NOP

**DECMS instruction:**

**DECMS**      BUF0  
JMP      C0STEP      ; Jump to C0STEP if BUF0 is not zero.

...

...

C0STEP:      NOP

## ✎ MULTI-ADDRESS JUMPING

Users can jump around the multi-address by either JMP instruction or ADD M, A instruction (M = PCL) to activate multi-address jumping function. Program Counter supports “**ADD M,A**”, “**ADC M,A**” and “**B0ADD M,A**” instructions for carry to PCH when PCL overflow automatically. For jump table or others applications, users can calculate PC value by the three instructions and don't care PCL overflow problem.

\* **Note:** PCH only support PC up counting result and doesn't support PC down counting. When PCL is carry after PCL+ACC, PCH adds one automatically. If PCL borrow after PCL-ACC, PCH keeps value and not change.

### ➤ Example: If PC = 0323H (PCH = 03H, PCL = 23H)

; PC = 0323H

```
MOV      A, #28H
B0MOV    PCL, A          ; Jump to address 0328H
...
```

; PC = 0328H

```
MOV      A, #00H
B0MOV    PCL, A          ; Jump to address 0300H
...
```

### ➤ Example: If PC = 0323H (PCH = 03H, PCL = 23H)

; PC = 0323H

```
B0ADD    PCL, A          ; PCL = PCL + ACC, the PCH cannot be changed.
JMP      A0POINT        ; If ACC = 0, jump to A0POINT
JMP      A1POINT        ; ACC = 1, jump to A1POINT
JMP      A2POINT        ; ACC = 2, jump to A2POINT
JMP      A3POINT        ; ACC = 3, jump to A3POINT
...
```

## 2.2.5 H, L REGISTERS

The H and L registers are the 8-bit buffers. There are two major functions of these registers.

- Can be used as general working registers
- Can be used as RAM data pointers with @HL register

081H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>H</b>	HBIT7	HBIT6	HBIT5	HBIT4	HBIT3	HBIT2	HBIT1	HBIT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	-	-	-	-	-	-

080H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>L</b>	LBIT7	LBIT6	LBIT5	LBIT4	LBIT3	LBIT2	LBIT1	LBIT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	-	-	-	-	-	-

- **Example: If want to read a data from RAM address 20H of bank\_0, it can use indirectly addressing mode to access data as following.**

```

B0MOV    H, #00H        ; To set RAM bank 0 for H register
B0MOV    L, #20H        ; To set location 20H for L register
B0MOV    A, @HL         ; To read a data into ACC

```

- **Example: Clear general-purpose data memory area of bank 0 using @HL register.**

```

CLR      H              ; H = 0, bank 0
B0MOV    L, #07FH       ; L = 7FH, the last address of the data memory area

CLR_HL_BUF:
CLR      @HL            ; Clear @HL to be zero
DECMS    L              ; L - 1, if L = 0, finish the routine
JMP      CLR_HL_BUF     ; Not zero

END_CLR:
CLR      @HL            ; End of clear general purpose data memory area of bank 0
...
...

```

## 2.2.6 Y, Z REGISTERS

The Y and Z registers are the 8-bit buffers. There are three major functions of these registers.

- Can be used as general working registers
- Can be used as RAM data pointers with @YZ register
- Can be used as ROM data pointer with the MOVC instruction for look-up table

084H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>Y</b>	YBIT7	YBIT6	YBIT5	YBIT4	YBIT3	YBIT2	YBIT1	YBIT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	-	-	-	-	-	-

083H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>Z</b>	ZBIT7	ZBIT6	ZBIT5	ZBIT4	ZBIT3	ZBIT2	ZBIT1	ZBIT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	-	-	-	-	-	-

➤ **Example:** Uses Y, Z register as the data pointer to access data in the RAM address 025H of bank0.

```

B0MOV    Y, #00H        ; To set RAM bank 0 for Y register
B0MOV    Z, #25H        ; To set location 25H for Z register
B0MOV    A, @YZ         ; To read a data into ACC

```

➤ **Example:** Uses the Y, Z register as data pointer to clear the RAM data.

```

B0MOV    Y, #0          ; Y = 0, bank 0
B0MOV    Z, #07FH       ; Z = 7FH, the last address of the data memory area

```

CLR\_YZ\_BUF:

```

CLR      @YZ            ; Clear @YZ to be zero

```

```

DECMS    Z              ; Z - 1, if Z = 0, finish the routine
JMP      CLR_YZ_BUF     ; Not zero

```

```

CLR      @YZ

```

END\_CLR: ; End of clear general purpose data memory area of bank 0

...

## 2.2.7 R REGISTER

R register is an 8-bit buffer. There are two major functions of the register.

- Can be used as working register
- For store high-byte data of look-up table  
(MOVC instruction executed, the high-byte data of specified ROM address will be stored in R register and the low-byte data will be stored in ACC).

082H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>R</b>	RBIT7	RBIT6	RBIT5	RBIT4	RBIT3	RBIT2	RBIT1	RBIT0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	-	-	-	-	-	-

\* **Note:** Please refer to the "LOOK-UP TABLE DESCRIPTION" about R register look-up table application.

## 2.3 ADDRESSING MODE

### 2.3.1 IMMEDIATE ADDRESSING MODE

The immediate addressing mode uses an immediate data to set up the location in ACC or specific RAM.

- **Example: Move the immediate data 12H to ACC.**

MOV            A, #12H            ; To set an immediate data 12H into ACC.

- **Example: Move the immediate data 12H to R register.**

B0MOV        R, #12H            ; To set an immediate data 12H into R register.

\* **Note: In immediate addressing mode application, the specific RAM must be 0x80~0x87 working register.**

### 2.3.2 DIRECTLY ADDRESSING MODE

The directly addressing mode moves the content of RAM location in or out of ACC.

- **Example: Move 0x12 RAM location data into ACC.**

B0MOV        A, 12H            ; To get a content of RAM location 0x12 of bank 0 and save in ACC.

- **Example: Move ACC data into 0x12 RAM location.**

B0MOV        12H, A            ; To get a content of ACC and save in RAM location 12H of bank 0.

### 2.3.3 INDIRECTLY ADDRESSING MODE

The indirectly addressing mode is to access the memory by the data pointer registers (Y/Z).

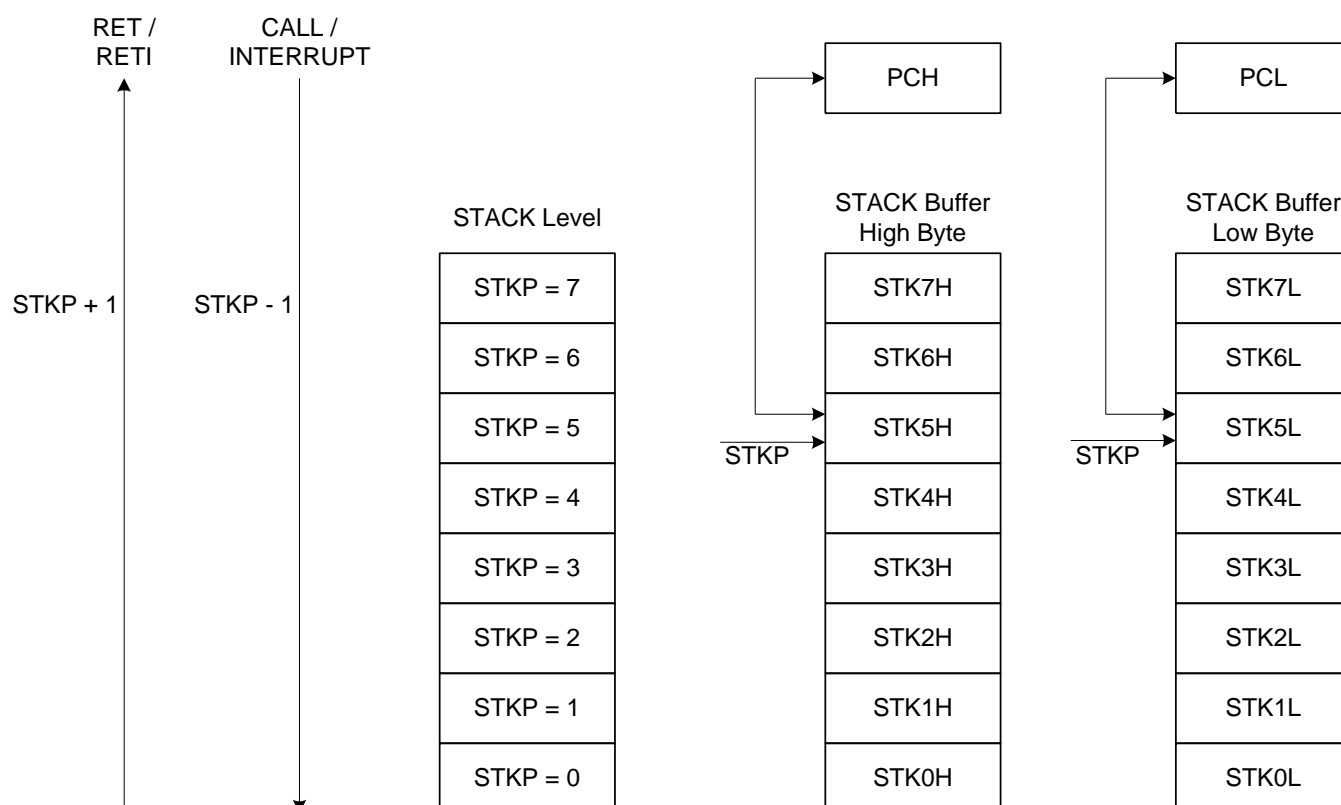
- **Example: Indirectly addressing mode with @YZ register.**

B0MOV        Y, #0            ; To clear Y register to access RAM bank 0.  
B0MOV        Z, #12H          ; To set an immediate data 12H into Z register.  
B0MOV        A, @YZ           ; Use data pointer @YZ reads a data from RAM location  
                                 ; 012H into ACC.

## 2.4 STACK OPERATION

### 2.4.1 OVERVIEW

The stack buffer has 8-level. These buffers are designed to push and pop up program counter's (PC) data when interrupt service routine and "CALL" instruction are executed. The STKP register is a pointer designed to point active level in order to push or pop up data from stack buffer. The STKnH and STKnL are the stack buffers to store program counter (PC) data.





## 2.4.2 STACK REGISTERS

The stack pointer (STKP) is a 3-bit register to store the address used to access the stack buffer, 11-bit data memory (STKnH and STKnL) set aside for temporary storage of stack addresses.

The two stack operations are writing to the top of the stack (push) and reading from the top of stack (pop). Push operation decrements the STKP and the pop operation increments each time. That makes the STKP always point to the top address of stack buffer and write the last program counter value (PC) into the stack buffer.

The program counter (PC) value is stored in the stack buffer before a CALL instruction executed or during interrupt service routine. Stack operation is a LIFO type (Last in and first out). The stack pointer (STKP) and stack buffer (STKnH and STKnL) are located in the system register area bank 0.

0DFH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>STKP</b>	GIE	-	-	-	-	STKPB2	STKPB1	STKPB0
Read/Write	R/W	-	-	-	-	R/W	R/W	R/W
After reset	0	-	-	-	-	1	1	1

Bit[2:0] **STKPBn**: Stack pointer (n = 0 ~ 2)

Bit 7 **GIE**: Global interrupt control bit.  
0 = Disable.  
1 = Enable. Please refer to the interrupt chapter.

- **Example: Stack pointer (STKP) reset, we strongly recommended to clear the stack pointer in the beginning of the program.**

```
MOV      A, #00000111B
B0MOV    STKP, A
```

0F0H~0FFH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>STKnH</b>	-	-	-	-	-	SnPC10	SnPC9	SnPC8
Read/Write	-	-	-	-	-	R/W	R/W	R/W
After reset	-	-	-	-	-	0	0	0

0F0H~0FFH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>STKnL</b>	SnPC7	SnPC6	SnPC5	SnPC4	SnPC3	SnPC2	SnPC1	SnPC0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

**STKn = STKnH , STKnL (n = 7 ~ 0)**

## 2.4.3 STACK OPERATION EXAMPLE

The two kinds of Stack-Save operations refer to the stack pointer (STKP) and write the content of program counter (PC) to the stack buffer are CALL instruction and interrupt service. Under each condition, the STKP decreases and points to the next available stack location. The stack buffer stores the program counter about the op-code address. The Stack-Save operation is as the following table.

Stack Level	STKP Register			Stack Buffer		Description
	STKPB2	STKPB1	STKPB0	High Byte	Low Byte	
0	1	1	1	Free	Free	-
1	1	1	0	STK0H	STK0L	-
2	1	0	1	STK1H	STK1L	-
3	1	0	0	STK2H	STK2L	-
4	0	1	1	STK3H	STK3L	-
5	0	1	0	STK4H	STK4L	-
6	0	0	1	STK5H	STK5L	-
7	0	0	0	STK6H	STK6L	-
8	1	1	1	STK7H	STK7L	-
> 8	1	1	0	-	-	Stack Over, error

There are Stack-Restore operations correspond to each push operation to restore the program counter (PC). The RETI instruction uses for interrupt service routine. The RET instruction is for CALL instruction. When a pop operation occurs, the STKP is incremented and points to the next free stack location. The stack buffer restores the last program counter (PC) to the program counter registers. The Stack-Restore operation is as the following table.

Stack Level	STKP Register			Stack Buffer		Description
	STKPB2	STKPB1	STKPB0	High Byte	Low Byte	
8	1	1	1	STK7H	STK7L	-
7	0	0	0	STK6H	STK6L	-
6	0	0	1	STK5H	STK5L	-
5	0	1	0	STK4H	STK4L	-
4	0	1	1	STK3H	STK3L	-
3	1	0	0	STK2H	STK2L	-
2	1	0	1	STK1H	STK1L	-
1	1	1	0	STK0H	STK0L	-
0	1	1	1	Free	Free	-

## 2.5 CODE OPTION TABLE

The code option is the system hardware configurations including noise filter option, watchdog timer operation, LVD option, reset pin option and OTP ROM security control. The code option items are as following table:

Code Option	Content	Function Description
Watch_Dog	Always_On	Watchdog timer is always on enable even in power down and green mode.
	Enable	Enable watchdog timer. Watchdog timer stops in power down mode and green mode.
	Disable	Disable Watchdog function.
Fcpu	Fhosc/2	Instruction cycle is 2 oscillator clocks.
	Fhosc/4	Instruction cycle is 4 oscillator clocks.
	Fhosc/8	Instruction cycle is 8 oscillator clocks.
	Fhosc/16	Instruction cycle is 16 oscillator clocks.
Reset_Pin	Reset	Enable External reset pin.
	P56	Enable P5.6 input only without pull-up resister.
Security	Enable	Enable ROM code Security function.
	Disable	Disable ROM code Security function.
LVD	LVD_L	LVD will reset chip if VDD is below 2.0V
	LVD_M	LVD will reset chip if VDD is below 2.0V Enable LVD24 bit of PFLAG register for 2.4V low voltage indicator.
	LVD_H	LVD will reset chip if VDD is below 2.4V Enable LVD36 bit of PFLAG register for 3.6V low voltage indicator.
	LVD_MAX	LVD will reset chip if VDD is below 3.6V

### 2.5.1 Fcpu code option

Fcpu means instruction cycle of normal mode (high clock). In slow mode, the system clock source is internal low speed RC oscillator. The Fcpu of slow mode isn't controlled by Fcpu code option and fixed Fhosc/4 (16KHz/4 @3V, 32KHz/4 @5V).

### 2.5.2 Reset\_Pin code option

The reset pin is shared with general input only pin controlled by code option.

- **Reset:** The reset pin is external reset function. When falling edge trigger occurring, the system will be reset.
- **P56:** Set reset pin to general input only pin (P5.6). The external reset function is disabled and the pin is input pin.

### 2.5.3 Security code option

Security code option is OTP ROM protection. When enable security code option, the ROM code is secured and not dumped complete ROM contents.

# 3 RESET

## 3.1 OVERVIEW

The system would be reset in three conditions as following.

- Power on reset
- Watchdog reset
- Brown out reset
- External reset (only supports external reset pin enable situation)

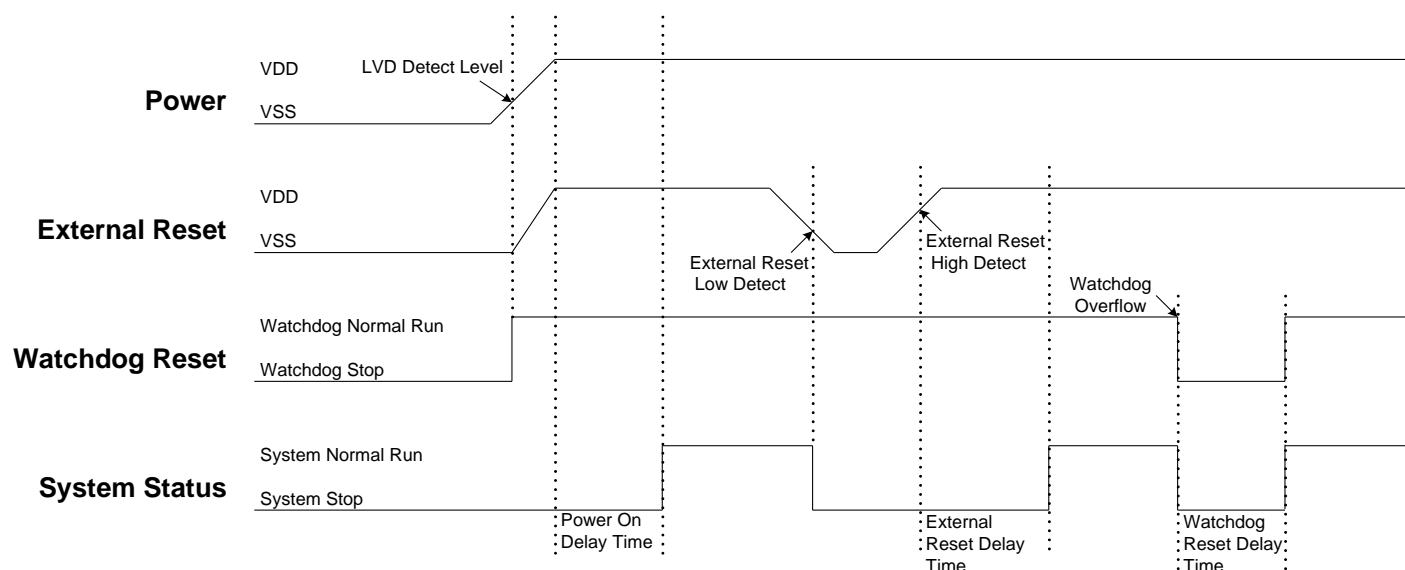
When any reset condition occurs, all system registers keep initial status, program stops and program counter is cleared. After reset status released, the system boots up and program starts to execute from ORG 0. The NT0, NPD flags indicate system reset status. The system can depend on NT0, NPD status and go to different paths by program.

086H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>PFLAG</b>	NT0	NPD	LVD36	LVD24	-	C	DC	Z
Read/Write	R/W	R/W	R	R	-	R/W	R/W	R/W
After reset	-	-	0	0	-	0	0	0

Bit [7:6] **NT0, NPD**: Reset status flag.

NT0	NPD	Condition	Description
0	0	Watchdog reset	Watchdog timer overflow.
0	1	Reserved	-
1	0	Power on reset and LVD reset.	Power voltage is lower than LVD detecting level.
1	1	External reset	External reset pin detect low level status.

Finishing any reset sequence needs some time. The system provides complete procedures to make the power on reset successful. For different oscillator types, the reset time is different. That causes the VDD rise rate and start-up time of different oscillator is not fixed. RC type oscillator's start-up time is very short, but the crystal type is longer. Under client terminal application, users have to take care the power on reset time for the master terminal requirement. The reset timing diagram is as following.



## 3.2 POWER ON RESET

The power on reset depend no LVD operation for most power-up situations. The power supplying to system is a rising curve and needs some time to achieve the normal voltage. Power on reset sequence is as following.

- **Power-up:** System detects the power voltage up and waits for power stable.
- **External reset (only external reset pin enable):** System checks external reset pin status. If external reset pin is not high level, the system keeps reset status and waits external reset pin released.
- **System initialization:** All system registers is set as initial conditions and system is ready.
- **Oscillator warm up:** Oscillator operation is successfully and supply to system clock.
- **Program executing:** Power on sequence is finished and program executes from ORG 0.

## 3.3 WATCHDOG RESET

Watchdog reset is a system protection. In normal condition, system works well and clears watchdog timer by program. Under error condition, system is in unknown situation and watchdog can't be clear by program before watchdog timer overflow. Watchdog timer overflow occurs and the system is reset. After watchdog reset, the system restarts and returns normal mode. Watchdog reset sequence is as following.

- **Watchdog timer status:** System checks watchdog timer overflow status. If watchdog timer overflow occurs, the system is reset.
- **System initialization:** All system registers is set as initial conditions and system is ready.
- **Oscillator warm up:** Oscillator operation is successfully and supply to system clock.
- **Program executing:** Power on sequence is finished and program executes from ORG 0.

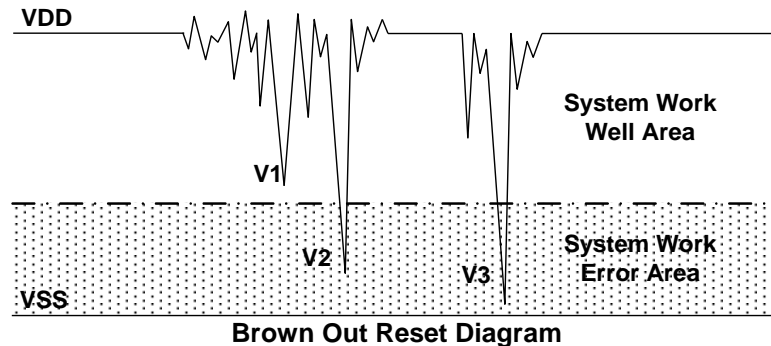
Watchdog timer application note is as following.

- Before clearing watchdog timer, check I/O status and check RAM contents can improve system error.
- Don't clear watchdog timer in interrupt vector and interrupt service routine. That can improve main routine fail.
- Clearing watchdog timer program is only at one part of the program. This way is the best structure to enhance the watchdog timer function.

\* **Note:** Please refer to the "WATCHDOG TIMER" about watchdog timer detail information.

### 3.4 BROWN OUT RESET

The brown out reset is a power dropping condition. The power drops from normal voltage to low voltage by external factors (e.g. EFT interference or external loading changed). The brown out reset would make the system not work well or executing program error.



The power dropping might through the voltage range that's the system dead-band. The dead-band means the power range can't offer the system minimum operation power requirement. The above diagram is a typical brown out reset diagram. There is a serious noise under the VDD, and VDD voltage drops very deep. There is a dotted line to separate the system working area. The above area is the system work well area. The below area is the system work error area called dead-band. V1 doesn't touch the below area and not effect the system operation. But the V2 and V3 is under the below area and may induce the system error occurrence. Let system under dead-band includes some conditions.

#### DC application:

The power source of DC application is usually using battery. When low battery condition and MCU drive any loading, the power drops and keeps in dead-band. Under the situation, the power won't drop deeper and not touch the system reset voltage. That makes the system under dead-band.

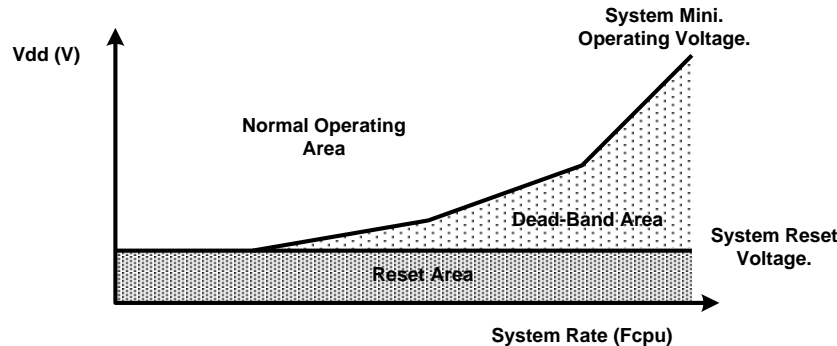
#### AC application:

In AC power application, the DC power is regulated from AC power source. This kind of power usually couples with AC noise that makes the DC power dirty. Or the external loading is very heavy, e.g. driving motor. The loading operating induces noise and overlaps with the DC power. VDD drops by the noise, and the system works under unstable power situation.

The power on duration and power down duration are longer in AC application. The system power on sequence protects the power on successful, but the power down situation is like DC low battery condition. When turn off the AC power, the VDD drops slowly and through the dead-band for a while.

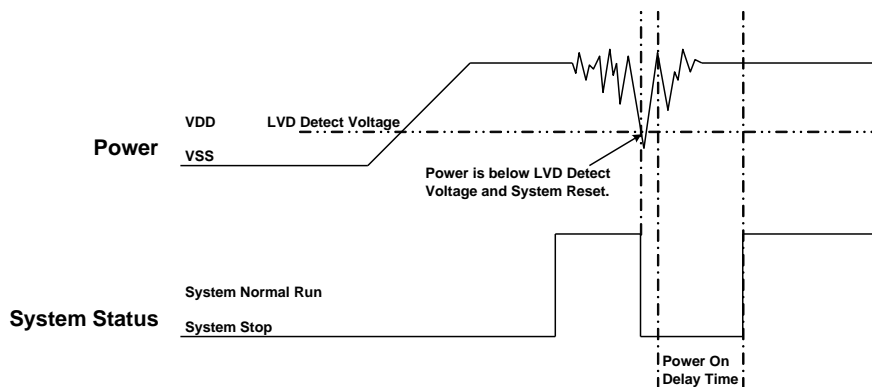
### 3.4.1 THE SYSTEM OPERATING VOLTAGE

To improve the brown out reset needs to know the system minimum operating voltage which is depend on the system executing rate and power level. Different system executing rates have different system minimum operating voltage. The electrical characteristic section shows the system voltage to executing rate relationship.



Normally the system operation voltage area is higher than the system reset voltage to VDD, and the reset voltage is decided by LVD detect level. The system minimum operating voltage rises when the system executing rate upper even higher than system reset voltage. The dead-band definition is the system minimum operating voltage above the system reset voltage.

### 3.4.2 LOW VOLTAGE DETECTOR (LVD)



The LVD (low voltage detector) is built-in Sonix 8-bit MCU to be brown out reset protection. When the VDD drops and is below LVD detect voltage, the LVD would be triggered, and the system is reset. The LVD detect level is different by each MCU. The LVD voltage level is a point of voltage and not easy to cover all dead-band range. Using LVD to improve brown out reset is depend on application requirement and environment. If the power variation is very deep, violent and trigger the LVD, the LVD can be the protection. If the power variation can touch the LVD detect level and make system work error, the LVD can't be the protection and need to other reset methods. More detail LVD information is in the electrical characteristic section.

The LVD is three levels design (2.0V/2.4V/3.6V) and controlled by LVD code option. The 2.0V LVD is always enable for power on reset and Brown Out reset. The 2.4V LVD includes LVD reset function and flag function to indicate VDD status function. The 3.6V includes flag function to indicate VDD status. LVD flag function can be an **easy low battery detector**. LVD24, LVD36 flags indicate VDD voltage level. For low battery detect application, only checking LVD24, LVD36 status to be battery status. This is a cheap and easy solution.

086H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>PFLAG</b>	NT0	NPD	LVD36	LVD24	-	C	DC	Z
Read/Write	R/W	R/W	R	R	-	R/W	R/W	R/W
After reset	-	-	0	0	-	0	0	0

Bit 5 **LVD36:** LVD 3.6V operating flag and only support LVD code option is LVD\_H.  
 0 = Inactive ( $VDD > 3.6V$ ).  
 1 = Active ( $VDD \leq 3.6V$ ).

Bit 4 **LVD24:** LVD 2.4V operating flag and only support LVD code option is LVD\_M.  
 0 = Inactive ( $VDD > 2.4V$ ).  
 1 = Active ( $VDD \leq 2.4V$ ).

LVD	LVD Code Option			
	LVD_L	LVD_M	LVD_H	LVD_MAX
2.0V Reset	Available	Available	Available	Available
2.4V Flag	-	Available	-	-
2.4V Reset	-	-	Available	-
3.6V Flag	-	-	Available	-
3.6V Reset	-	-	-	Available

#### LVD\_L

If  $VDD < 2.0V$ , system will be reset.  
 Disable LVD24 and LVD36 bit of PFLAG register.

#### LVD\_M

If  $VDD < 2.0V$ , system will be reset.  
 Enable LVD24 bit of PFLAG register. If  $VDD > 2.4V$ , LVD24 is "0". If  $VDD \leq 2.4V$ , LVD24 flag is "1".  
 Disable LVD36 bit of PFLAG register.

#### LVD\_H

If  $VDD < 2.4V$ , system will be reset.  
 Enable LVD24 bit of PFLAG register. If  $VDD > 2.4V$ , LVD24 is "0". If  $VDD \leq 2.4V$ , LVD24 flag is "1".  
 Enable LVD36 bit of PFLAG register. If  $VDD > 3.6V$ , LVD36 is "0". If  $VDD \leq 3.6V$ , LVD36 flag is "1".

#### LVD\_MAX

If  $VDD < 3.6V$ , system will be reset.

#### \* Note:

1. After any LVD reset, LVD24, LVD36 flags are cleared.
2. The voltage level of LVD 2.4V or 3.6V is for design reference only. Don't use the LVD indicator as precision VDD measurement.



### 3.4.3 BROWN OUT RESET IMPROVEMENT

How to improve the brown reset condition? There are some methods to improve brown out reset as following.

- LVD reset
- Watchdog reset
- Reduce the system executing rate
- External reset circuit. (Zener diode reset circuit, Voltage bias reset circuit, External reset IC)

**\* Note:**

1. *The “ Zener diode reset circuit”, “Voltage bias reset circuit” and “External reset IC” can completely improve the brown out reset, DC low battery and AC slow power down conditions.*
2. *For AC power application and enhance EFT performance, the system clock is 4MHz/4 (1 mips) and use external reset (“ Zener diode reset circuit”, “Voltage bias reset circuit”, “External reset IC”). The structure can improve noise effective and get good EFT characteristic.*

**Watchdog reset:**

The watchdog timer is a protection to make sure the system executes well. Normally the watchdog timer would be clear at one point of program. Don't clear the watchdog timer in several addresses. The system executes normally and the watchdog won't reset system. When the system is under dead-band and the execution error, the watchdog timer can't be clear by program. The watchdog is continuously counting until overflow occurrence. The overflow signal of watchdog timer triggers the system to reset, and the system return to normal mode after reset sequence. This method also can improve brown out reset condition and make sure the system to return normal mode.

If the system reset by watchdog and the power is still in dead-band, the system reset sequence won't be successful and the system stays in reset status until the power return to normal range. Watchdog timer application note is as following.

**Reduce the system executing rate:**

If the system rate is fast and the dead-band exists, to reduce the system executing rate can improve the dead-band. The lower system rate is with lower minimum operating voltage. Select the power voltage that's no dead-band issue and find out the mapping system rate. Adjust the system rate to the value and the system exits the dead-band issue. This way needs to modify whole program timing to fit the application requirement.

**External reset circuit:**

The external reset methods also can improve brown out reset and is the complete solution. There are three external reset circuits to improve brown out reset including “Zener diode reset circuit”, “Voltage bias reset circuit” and “External reset IC”. These three reset structures use external reset signal and control to make sure the MCU be reset under power dropping and under dead-band. The external reset information is described in the next section.

## 3.5 EXTERNAL RESET

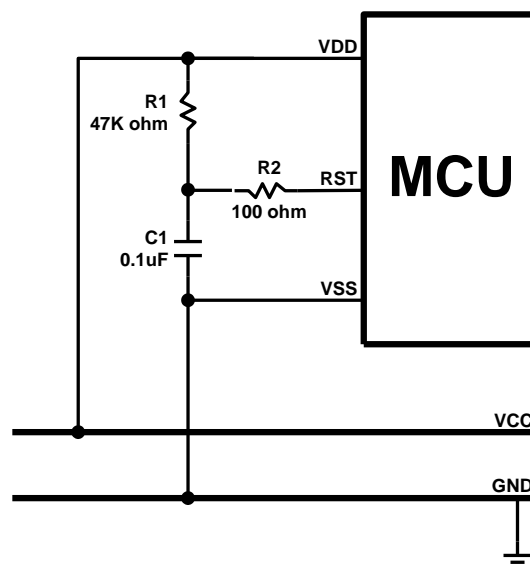
External reset function is controlled by “Reset\_Pin” code option. Set the code option as “Reset” option to enable external reset function. External reset pin is Schmitt Trigger structure and low level active. The system is running when reset pin is high level voltage input. The reset pin receives the low voltage and the system is reset. The external reset operation activates in power on and normal running mode. During system power-up, the external reset pin must be high level input, or the system keeps in reset status. External reset sequence is as following.

- **External reset (only external reset pin enable):** System checks external reset pin status. If external reset pin is not high level, the system keeps reset status and waits external reset pin released.
- **System initialization:** All system registers is set as initial conditions and system is ready.
- **Oscillator warm up:** Oscillator operation is successfully and supply to system clock.
- **Program executing:** Power on sequence is finished and program executes from ORG 0.

The external reset can reset the system during power on duration, and good external reset circuit can protect the system to avoid working at unusual power condition, e.g. brown out reset in AC power application...

## 3.6 EXTERNAL RESET CIRCUIT

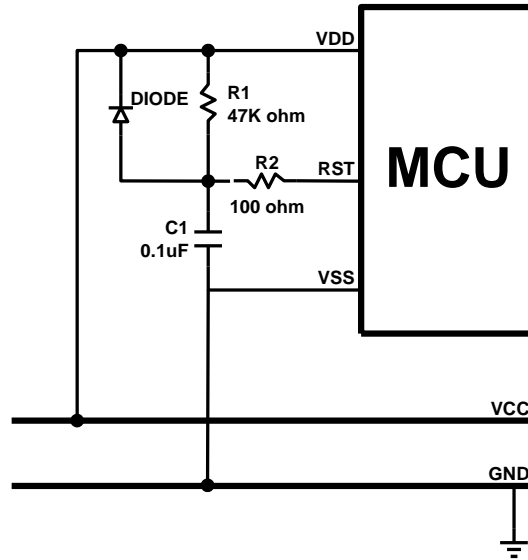
### 3.6.1 Simply RC Reset Circuit



This is the basic reset circuit, and only includes R1 and C1. The RC circuit operation makes a slow rising signal into reset pin as power up. The reset signal is slower than VDD power up timing, and system occurs a power on signal from the timing difference.

\* **Note:** The reset circuit is no any protection against unusual power or brown out reset.

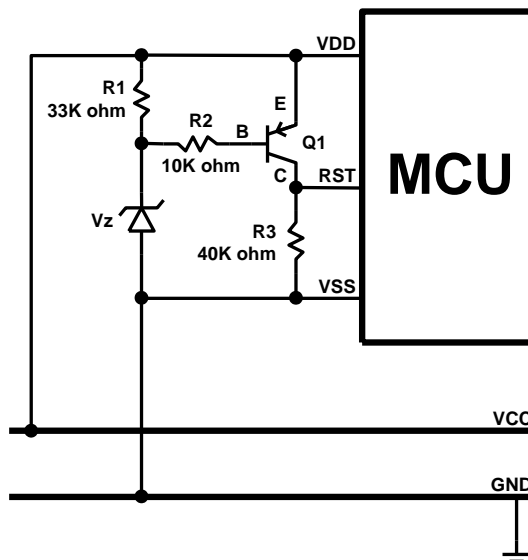
### 3.6.2 Diode & RC Reset Circuit



This is the better reset circuit. The R1 and C1 circuit operation is like the simply reset circuit to make a power on signal. The reset circuit has a simply protection against unusual power. The diode offers a power positive path to conduct higher power to VDD. It is can make reset pin voltage level to synchronize with VDD voltage. The structure can improve slight brown out reset condition.

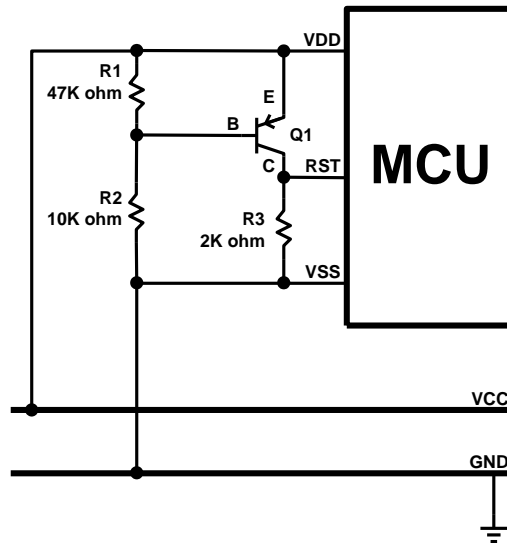
\* **Note:** The R2 100 ohm resistor of “Simply reset circuit” and “Diode & RC reset circuit” is necessary to limit any current flowing into reset pin from external capacitor C in the event of reset pin breakdown due to Electrostatic Discharge (ESD) or Electrical Over-stress (EOS).

### 3.6.3 Zener Diode Reset Circuit



The zener diode reset circuit is a simple low voltage detector and can **improve brown out reset condition completely**. Use zener voltage to be the active level. When VDD voltage level is above “ $V_z + 0.7V$ ”, the C terminal of the PNP transistor outputs high voltage and MCU operates normally. When VDD is below “ $V_z + 0.7V$ ”, the C terminal of the PNP transistor outputs low voltage and MCU is in reset mode. Decide the reset detect voltage by zener specification. Select the right zener voltage to conform the application.

### 3.6.4 Voltage Bias Reset Circuit

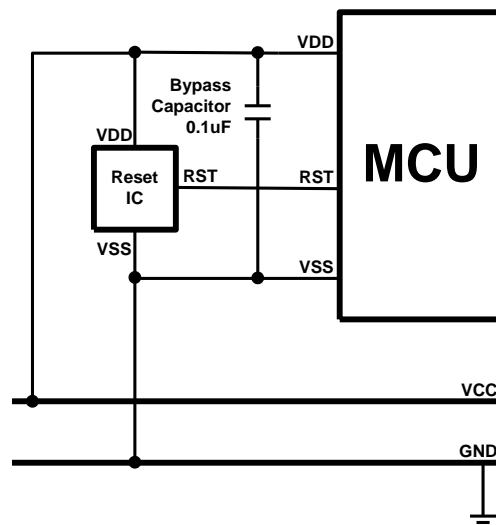


The voltage bias reset circuit is a low cost voltage detector and can **improve brown out reset condition completely**. The operating voltage is not accurate as zener diode reset circuit. Use R1, R2 bias voltage to be the active level. When VDD voltage level is above or equal to  $0.7V \times (R1 + R2) / R1$ , the C terminal of the PNP transistor outputs high voltage and MCU operates normally. When VDD is below  $0.7V \times (R1 + R2) / R1$ , the C terminal of the PNP transistor outputs low voltage and MCU is in reset mode.

Decide the reset detect voltage by R1, R2 resistances. Select the right R1, R2 value to conform the application. In the circuit diagram condition, the MCU's reset pin level varies with VDD voltage variation, and the differential voltage is 0.7V. If the VDD drops and the voltage lower than reset pin detect level, the system would be reset. If want to make the reset active earlier, set the  $R2 > R1$  and the cap between VDD and C terminal voltage is larger than 0.7V. The external reset circuit is with a stable current through R1 and R2. For power consumption issue application, e.g. DC power system, the current must be considered to whole system power consumption.

**\* Note:** Under unstable power condition as brown out reset, "Zener diode rest circuit" and "Voltage bias reset circuit" can protects system no any error occurrence as power dropping. When power drops below the reset detect voltage, the system reset would be triggered, and then system executes reset sequence. That makes sure the system work well under unstable power situation.

### 3.6.5 External Reset IC



The external reset circuit also use external reset IC to enhance MCU reset performance. This is a high cost and good effect solution. By different application and system requirement to select suitable reset IC. The reset circuit can improve all power variation.

# 4 SYSTEM CLOCK

## 4.1 OVERVIEW

The micro-controller is a dual clock system including high-speed and low-speed clocks. The high-speed clock is internal high-speed oscillator. The low-speed clock is from internal low-speed oscillator controlled by “CLKMD” bit of OSCM register. Both high-speed clock and low-speed clock can be system clock source through a divider to decide the system clock rate.

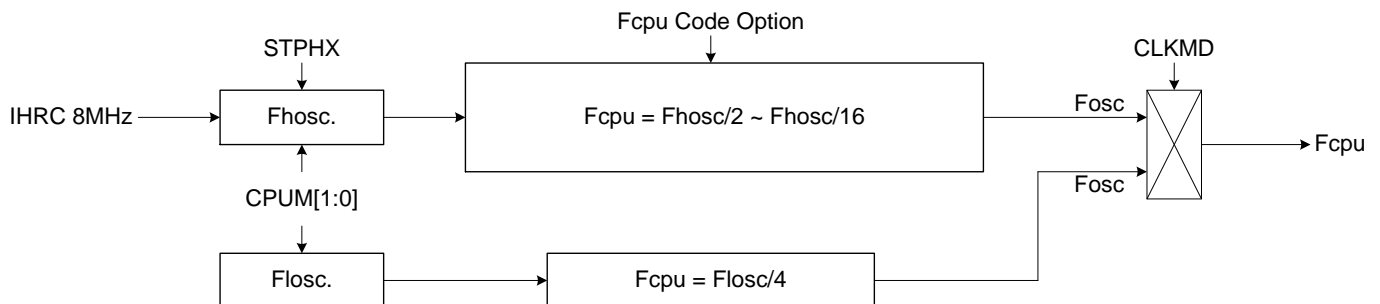
- **High-speed oscillator**

Internal high-speed oscillator is 16MHz RC type called “IHRC”.

- **Low-speed oscillator**

Internal low-speed oscillator is 16KHz @3V, 32KHz @5V RC type called “ILRC”.

- **System clock block diagram**



- Fhosc: Internal high-speed RC clock.
- Fosc: Internal low-speed RC clock (about 16KHz@3V, 32KHz@5V).
- Fosc: System clock source.
- Fcpu: Instruction cycle.

## 4.2 Fcpu (INSTRUCTION CYCLE)

The system clock rate is instruction cycle called “Fcpu” which is divided from the system clock source and decides the system operating rate. Fcpu rate is selected by Fcpu code option and the range is **Fhosc/1~Fhosc/16** under system normal mode. If Fcpu code option is Fhosc/4, the Fcpu frequency is 16MHz/4 = 4MHz. Under system slow mode, the Fcpu is fixed Fosc/4, 16KHz/4=4KHz @3V, 32KHz/4=8KHz @5V.

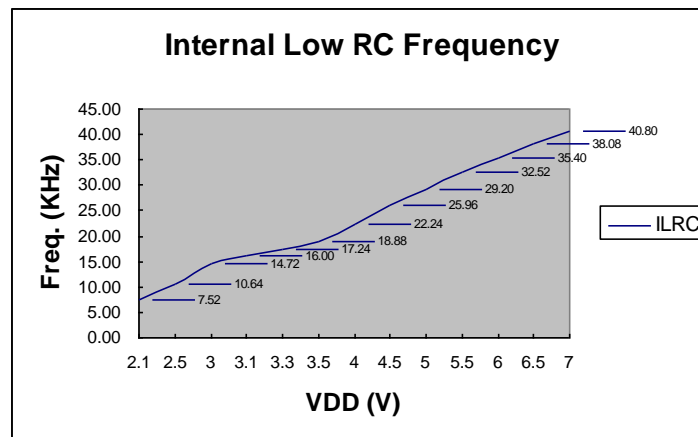
\* **Note:** In high noisy environment, “Fcpu = Fhosc/4~Fhosc/16” is the strongly recommendation to reduce noise effect.

### 4.3 SYSTEM HIGH-SPEED CLOCK

The system high-speed clock is internal high-speed RC type oscillator and is the system clock source. The internal high-speed oscillator is 16MHz RC type. The accuracy is  $\pm 2\%$  under commercial condition.

### 4.4 SYSTEM LOW-SPEED CLOCK

The system low clock source is the internal low-speed oscillator built in the micro-controller. The low-speed oscillator uses RC type oscillator circuit. The frequency is affected by the voltage and temperature of the system. In common condition, the frequency of the RC oscillator is about 16KHz at 3V and 32KHz at 5V. The relation between the RC frequency and voltage is as the following figure.



The internal low RC supports watchdog clock source and system slow mode controlled by "CLKMD" bit of OSCM register.

- ***Fosc = Internal low RC oscillator (about 16KHz @3V, 32KHz @5V).***
- ***Slow mode Fcpu = Fosc / 4***

There are two conditions to stop internal low RC. One is power down mode, and the other is green mode of 32K mode and watchdog disable. If system is in 32K mode and watchdog disable, only 32K oscillator activates and system is under low power consumption.

➤ **Example: Stop internal low-speed oscillator by power down mode.**

```
B0BSET    FCPUM0    ; To stop external high-speed oscillator and internal low-speed
                    ; oscillator called power down mode (sleep mode).
```

\* **Note: The internal low-speed clock can't be turned off individually. It is controlled by CPUM0, CPUM1 (32K, watchdog disable) bits of OSCM register.**

## 4.5 OSCM REGISTER

The OSCM register is an oscillator control register. It controls oscillator status, system mode.

OCAH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>OSCM</b>	0	0	0	CPUM1	CPUM0	CLKMD	STPHX	0
Read/Write	-	-	-	R/W	R/W	R/W	R/W	-
After reset	-	-	-	0	0	0	0	-

- Bit 1     **STPHX**: Internal high-speed oscillator control bit.  
 0 = Internal high-speed oscillator free run.  
 1 = Internal high-speed oscillator free run stop. Internal low-speed RC oscillator is still running.
- Bit 2     **CLKMD**: System high/Low clock mode control bit.  
 0 = Normal (dual) mode. System clock is high clock.  
 1 = Slow mode. System clock is internal low clock.
- Bit[4:3]   **CPUM[1:0]**: CPU operating mode control bits.  
 00 = normal.  
 01 = sleep (power down) mode.  
 10 = green mode.  
 11 = reserved.

“STPHX” bit controls internal high speed RC type oscillator operation. When “STPHX=0”, the internal high speed RC type oscillator active. When “STPHX=1”, the internal high speed RC type oscillator are disabled. T

## 4.6 SYSTEM CLOCK MEASUREMENT

Under design period, the users can measure system clock speed by software instruction cycle (Fcpu).

➤ **Example: Fcpu instruction cycle of external oscillator.**

```
B0BSET    P0M.0           ; Set P0.0 to be output mode for outputting Fcpu toggle signal.
```

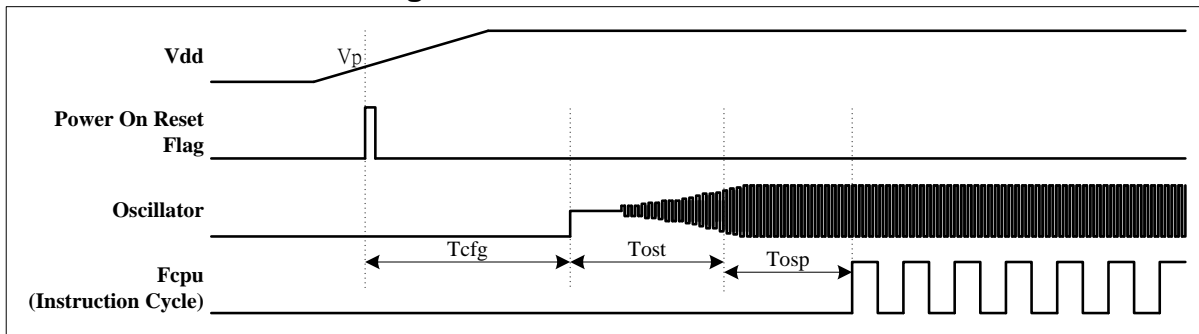
@ @:

```
B0BSET    P0.0           ; Output Fcpu toggle signal in low-speed clock mode.
B0BCLR    P0.0           ; Measure the Fcpu frequency by oscilloscope.
JMP       @B
```

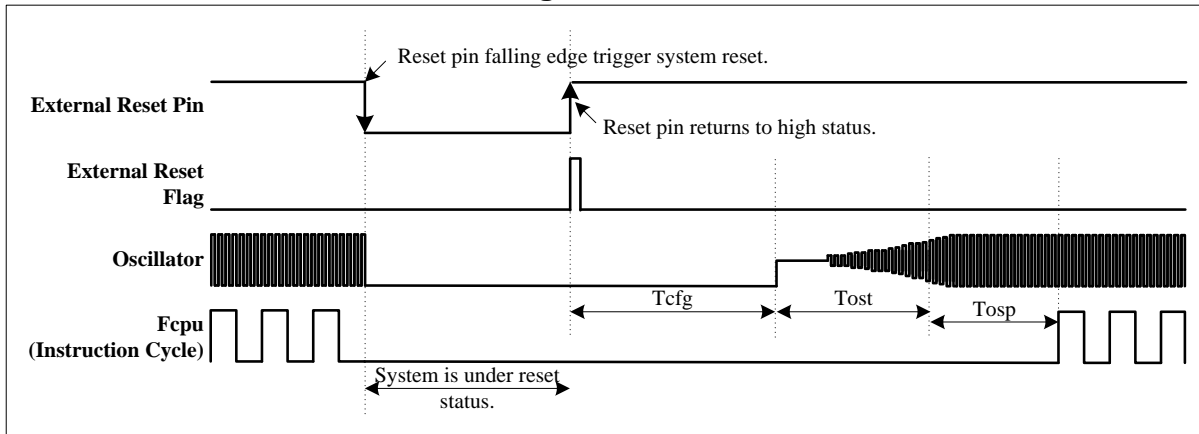
## 4.7 SYSTEM CLOCK TIMING

Parameter	Symbol	Description	Typical
Hardware configuration time	Tcfg	$2048 \cdot F_{ILRC}$	64ms @ $F_{ILRC} = 32\text{KHz}$ 128ms @ $F_{ILRC} = 16\text{KHz}$
Oscillator start up time	Tost	The start-up time is depended on oscillator's material, factory and architecture. The internal high speed RC type oscillator's start-up time is very short and ignored.	-
Oscillator warm-up time	Tosp	Oscillator warm-up time of reset condition. $2048 \cdot F_{hosc}$ (Power on reset, LVD reset, watchdog reset, external reset pin active.)	128us @ $F_{hosc} = 16\text{MHz}$
		Oscillator warm-up time of power down mode wake-up condition. $32 \cdot F_{hosc}$ .....Internal high-speed RC type oscillator.	2us @ $F_{hosc} = 16\text{MHz}$

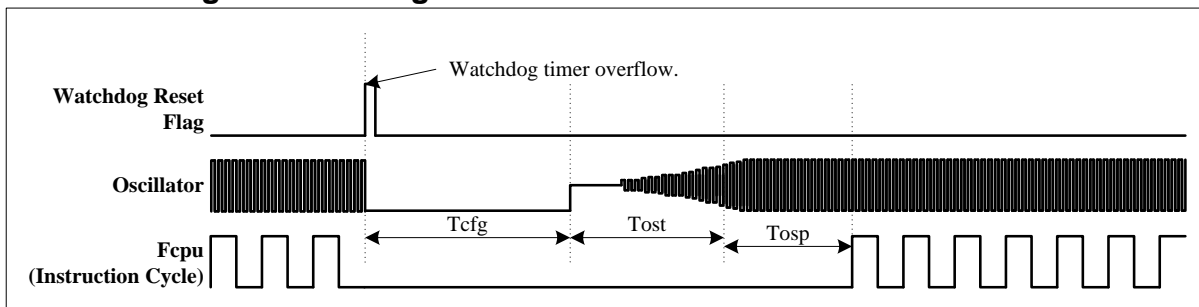
### ● Power On Reset Timing



### ● External Reset Pin Reset Timing

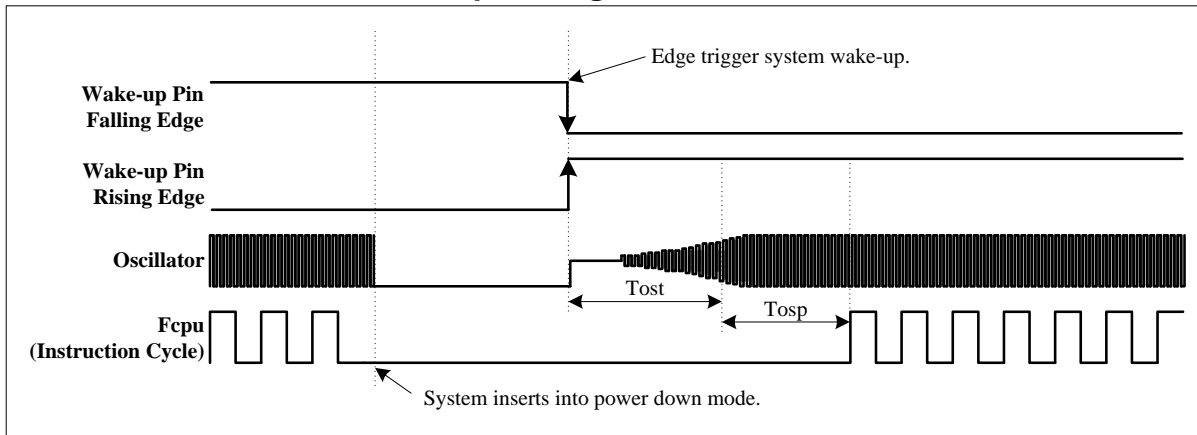


### ● Watchdog Reset Timing

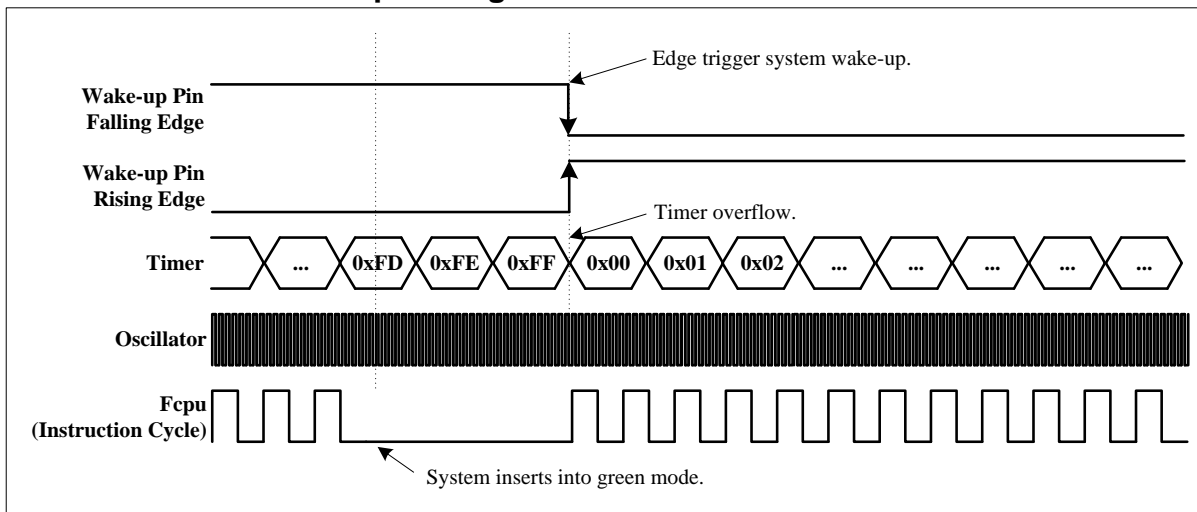




### ● Power Down Mode Wake-up Timing

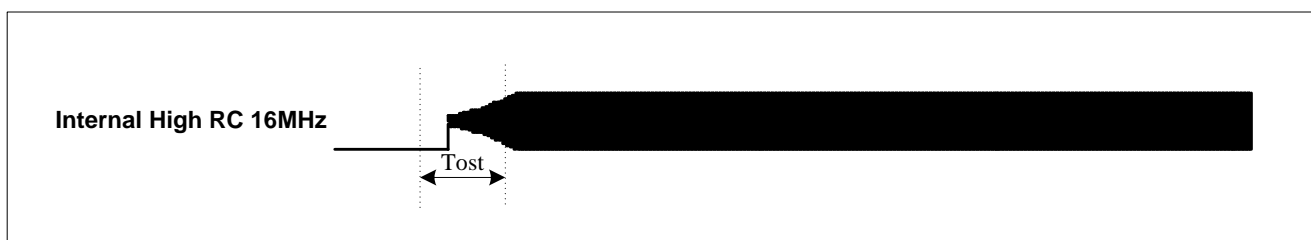


### ● Green Mode Wake-up Timing



### ● Oscillator Start-up Time

The start-up time is depended on oscillator's material, factory and architecture. The internal high speed RC type oscillator's start-up time is very short and ignored.



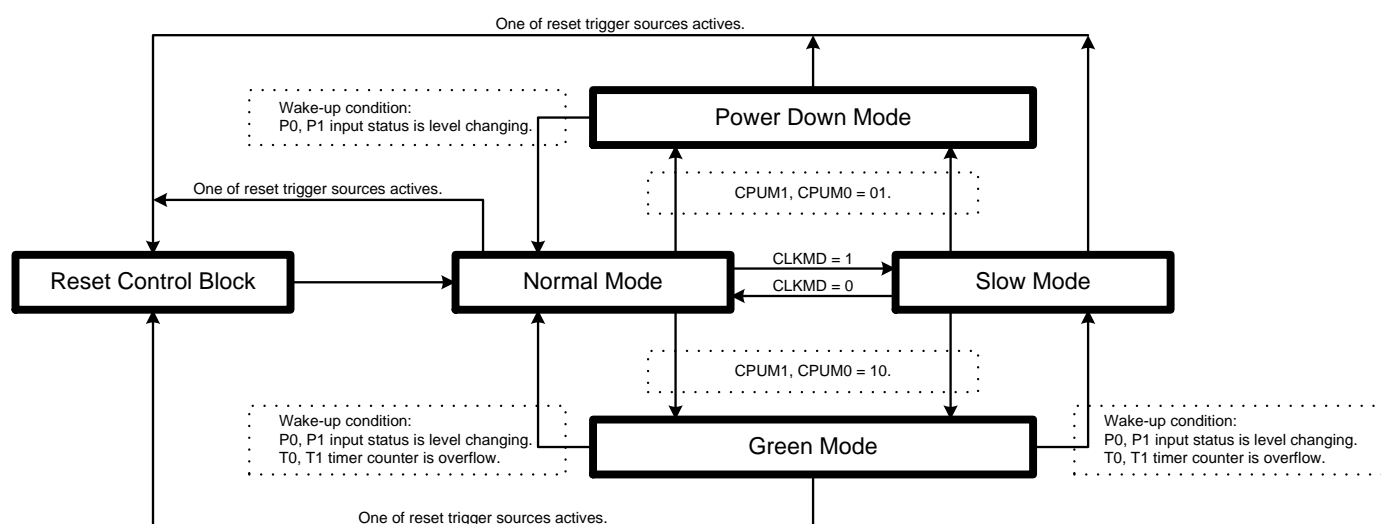
# 5 SYSTEM OPERATION MODE

## 5.1 OVERVIEW

The chip builds in four operating mode for difference clock rate and power saving reason. These modes control oscillators, op-code operation and analog peripheral devices' operation.

- Normal mode: System high-speed operating mode.
- Slow mode: System low-speed operating mode.
- Power down mode: System power saving mode (Sleep mode).
- Green mode: System ideal mode.

### Operating Mode Control Block



### Operating Mode Clock Control Table

Operating Mode	Normal Mode	Slow Mode	Green Mode	Power Down Mode
IHRC	Running	By STPHX	By STPHX	Stop
ILRC	Running	Running	Running	Stop
CPU instruction	Executing	Executing	Stop	Stop
T0 timer	By T0ENB	By T0ENB	By T0ENB	Inactive
TC0 timer	By TC0ENB	By TC0ENB	By TC0ENB (PWM active)	Inactive
TC1 timer	By TC1ENB	By TC1ENB	By TC1ENB (PWM active)	Inactive
T1 timer	By T1ENB	By T1ENB	By T1ENB	Inactive
Watchdog timer	By Watch_Dog Code option	By Watch_Dog Code option	By Watch_Dog Code option	By Watch_Dog Code option
Internal interrupt	All active	All active	T0, T1	All inactive
External interrupt	All active	All active	All active	All inactive
Wakeup source	-	-	P0, P1, T0, T1, CMP0, Reset	P0, P1, Reset

- **IHRC**: Internal high-speed oscillator RC type.
- **ILRC**: Internal low-speed oscillator RC type.

## 5.2 NORMAL MODE

The Normal Mode is system high clock operating mode. The system clock source is from high speed oscillator. The program is executed. After power on and any reset trigger released, the system inserts into normal mode to execute program. When the system is wake-up from power down mode, the system also inserts into normal mode. In normal mode, the high speed oscillator actives, and the power consumption is largest of all operating modes.

- The program is executed, and full functions are controllable.
- The system rate is high speed.
- The high speed oscillator and internal low speed RC type oscillator active.
- Normal mode can be switched to other operating modes through OSCM register.
- Power down mode is wake-up to normal mode.
- Slow mode is switched to normal mode.
- Green mode from normal mode is wake-up to normal mode.

## 5.3 SLOW MODE

The slow mode is system low clock operating mode. The system clock source is from internal low speed RC type oscillator. The slow mode is controlled by CLKMD bit of OSCM register. When CLKMD=0, the system is in normal mode. When CLKMD=1, the system inserts into slow mode. The high speed oscillator won't be disabled automatically after switching to slow mode, and must be disabled by SPTHX bit to reduce power consumption. In slow mode, the system rate is fixed  $F_{osc}/4$  ( $F_{osc}$  is internal low speed RC type oscillator frequency).

- The program is executed, and full functions are controllable.
- The system rate is low speed ( $F_{osc}/4$ ).
- The internal low speed RC type oscillator actives, and the high speed oscillator is controlled by SPTHX=1. In slow mode, to stop high speed oscillator is strongly recommendation.
- Slow mode can be switched to other operating modes through OSCM register.
- Power down mode from slow mode is wake-up to normal mode.
- Normal mode is switched to slow mode.
- Green mode from slow mode is wake-up to slow mode.

## 5.4 POWER DOWN MDOE

The power down mode is the system ideal status. No program execution and oscillator operation. Whole chip is under low power consumption status under 1uA. The power down mode is waked up by P0, P1 hardware level change trigger. P1 wake-up function is controlled by P1W register. Any operating modes into power down mode, the system is waked up to normal mode. Inserting power down mode is controlled by CPUM0 bit of OSCM register. When CPUM0=1, the system inserts into power down mode. After system wake-up from power down mode, the CPUM0 bit is disabled (zero status) automatically.

- The program stops executing, and full functions are disabled.
- All oscillators including external high speed oscillator, internal high speed oscillator and internal low speed oscillator stop.
- The power consumption is under 1uA.
- The system inserts into normal mode after wake-up from power down mode.
- The power down mode wake-up source is P0 and P1 level change trigger.

\* **Note:** If the system is in normal mode, to set SPTHX=1 to disable the high clock oscillator. The system is under no system clock condition. This condition makes the system stay as power down mode, and can be wake-up by P0, P1 level change trigger.

## 5.5 GREEN MODE

The green mode is another system ideal status not like power down mode. In power down mode, all functions and hardware devices are disabled. But in green mode, the system clock source keeps running, so the power consumption of green mode is larger than power down mode. In green mode, the program isn't executed, but the timer with wake-up function activates as enabled, and the timer clock source is the non-stop system clock. The green mode has 2 wake-up sources. One is the P0, P1 level change trigger wake-up. The other one is internal timer with wake-up function occurring overflow. That's mean users can setup one fix period to timer, and the system is waked up until the time out. Inserting green mode is controlled by CPUM1 bit of OSCM register. When CPUM1=1, the system inserts into green mode. After system wake-up from green mode, the CPUM1 bit is disabled (zero status) automatically.

- The program stops executing, and full functions are disabled.
- Only the timer with wake-up function activates.
- The oscillator to be the system clock source keeps running, and the other oscillators operation is depend on system operation mode configuration.
- If inserting green mode from normal mode, the system insets to normal mode after wake-up.
- If inserting green mode from slow mode, the system insets to slow mode after wake-up.
- The green mode wake-up sources are P0, P1 level change trigger and unique time overflow.
- PWM and buzzer output functions active in green mode, but the timer can't wake-up the system as overflow.

\* **Note: Sonix provides "GreenMode" macro to control green mode operation. It is necessary to use "GreenMode" macro to control system inserting green mode. The macro includes three instructions. Please take care the macro length as using BRANCH type instructions, e.g. bts0, bts1, b0bts0, b0bts1, ins, incms, decs, decms, cmprs, jmp, or the routine would be error.**

## 5.6 OPERATING MODE CONTROL MACRO

Sonix provides operating mode control macros to switch system operating mode easily.

Macro	Length	Description
<b>SleepMode</b>	1-word	The system insets into Sleep Mode (Power Down Mode).
<b>GreenMode</b>	3-word	The system inserts into Green Mode.
<b>SlowMode</b>	2-word	The system inserts into Slow Mode and stops high speed oscillator.
<b>Slow2Normal</b>	5-word	The system returns to Normal Mode from Slow Mode. The macro includes operating mode switch, enable high speed oscillator, high speed oscillator warm-up delay time.

- **Example: Switch normal/slow mode to power down (sleep) mode.**

```
SleepMode ; Declare "SleepMode" macro directly.
```

- **Example: Switch normal mode to slow mode.**

```
SlowMode ; Declare "SlowMode" macro directly.
```

- **Example: Switch slow mode to normal mode (The external high-speed oscillator stops).**

```
Slow2Normal ; Declare "Slow2Normal" macro directly.
```

- **Example: Switch normal/slow mode to green mode.**

```
GreenMode ; Declare "GreenMode" macro directly.
```

- **Example: Switch normal/slow mode to green mode and enable T0 wake-up function.**

; Set T0 timer wakeup function.

```

B0BCLR FT0IEN ; To disable T0 interrupt service
B0BCLR FT0ENB ; To disable T0 timer
MOV A,#20H ;
B0MOV T0M,A ; To set T0 clock = Fcpu / 64
MOV A,#74H ;
B0MOV T0C,A ; To set T0C initial value = 74H (To set T0 interval = 10 ms)
B0BCLR FT0IEN ; To disable T0 interrupt service
B0BCLR FT0IRQ ; To clear T0 interrupt request
B0BSET FT0ENB ; To enable T0 timer
```

; Go into green mode

```
GreenMode ; Declare "GreenMode" macro directly.
```

## 5.7 WAKEUP

### 5.7.1 OVERVIEW

Under power down mode (sleep mode) or green mode, program doesn't execute. The wakeup trigger can wake the system up to normal mode or slow mode. The wakeup trigger sources are external trigger (P0/P1 level change) and internal trigger (T0/T1 timer overflow).

- Power down mode is waked up to normal mode. The wakeup trigger is only external trigger (P0/P1 level change)
- Green mode is waked up to last mode (normal mode or slow mode). The wakeup triggers are external trigger (P0/P1 level change) and internal trigger (T0/T1 timer overflow).

### 5.7.2 WAKEUP TIME

When the system is in power down mode (sleep mode), the high clock oscillator stops. When waked up from power down mode, MCU waits for 32 internal high-speed oscillator clocks as the wakeup time to stable the oscillator circuit. After the wakeup time, the system goes into the normal mode.

\* **Note: Wakeup from green mode is no wakeup time because the clock doesn't stop in green mode.**

The value of the wakeup time is as the following.

$$\text{The Wakeup time} = 1/F_{\text{hosc}} * 32 \text{ (sec)} + \text{high clock start-up time}$$

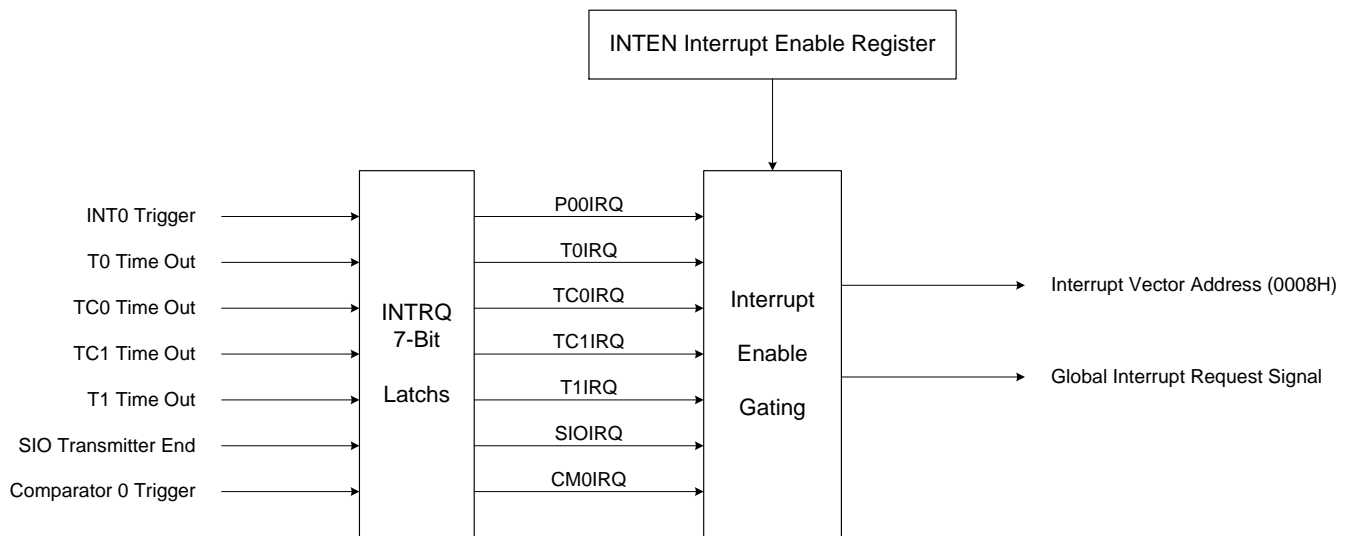
**Example:** In power down mode (sleep mode), the system is waked up. After the wakeup time, the system goes into normal mode. The wakeup time is as the following.

$$\text{The wakeup time} = 1/F_{\text{hosc}} * 32 = 2 \text{ us} \quad (F_{\text{hosc}} = 16\text{MHz})$$

# 6 INTERRUPT

## 6.1 OVERVIEW

This MCU provides 7 interrupt sources, including 6 internal interrupt (T0/TC0/TC1/T1/CM0/SIO) and 1 external interrupt (INT0). The external interrupt can wakeup the chip while the system is switched from power down mode to high-speed normal mode, and interrupt request is latched until return to normal mode. Once interrupt service is executed, the GIE bit in STKP register will clear to "0" for stopping other interrupt request. On the contrast, when interrupt service exits, the GIE bit will set to "1" to accept the next interrupts' request. The interrupt request signals are stored in INTRQ register.



**\* Note: The GIE bit must enable during all interrupt operation.**

## 6.2 INTEN INTERRUPT ENABLE REGISTER

INTEN is the interrupt request control register including three internal interrupts, two external interrupts enable control bits. One of the register to be set "1" is to enable the interrupt request function. Once of the interrupt occur, the stack is incremented and program jump to ORG 8 to execute interrupt service routines. The program exits the interrupt service routine when the returning interrupt service routine instruction (RETI) is executed.

0C9H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>INTEN</b>	CM0IEN	TC1IEN	TC0IEN	T0IEN	SIOIEN	T1IEN	-	P00IEN
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	-	R/W
After reset	0	0	0	0	0	0	-	0

Bit 0     **P00IEN:** External P0.0 interrupt (INT0) control bit.  
0 = Disable INT0 interrupt function.  
1 = Enable INT0 interrupt function.

Bit 2     **T1IEN:** T1 timer interrupt control bit.  
0 = Disable T1 interrupt function.  
1 = Enable T1 interrupt function.

Bit 3     **SIOIEN:** SIO interrupt control bit.  
0 = Disable SIO interrupt function.  
1 = Enable SIO interrupt function.

Bit 4     **T0IEN:** T0 timer interrupt control bit.  
0 = Disable T0 interrupt function.  
1 = Enable T0 interrupt function.

Bit 5     **TC0IEN:** TC0 timer interrupt control bit.  
0 = Disable TC0 interrupt function.  
1 = Enable TC0 interrupt function.

Bit 6     **TC1IEN:** TC1 timer interrupt control bit.  
0 = Disable TC1 interrupt function.  
1 = Enable TC1 interrupt function.

Bit 7     **CM0IEN:** Comparator 0 interrupt control bit.  
0 = Disable comparator 0 interrupt function.  
1 = Enable comparator 0 interrupt function.



## 6.3 INTRQ INTERRUPT REQUEST REGISTER

INTRQ is the interrupt request flag register. The register includes all interrupt request indication flags. Each one of the interrupt requests occurs, the bit of the INTRQ register would be set "1". The INTRQ value needs to be clear by programming after detecting the flag. In the interrupt vector of program, users know the any interrupt requests occurring by the register and do the routine corresponding of the interrupt request.

0C8H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>INTRQ</b>	CM0IRQ	TC1IRQ	TC0IRQ	T0IRQ	SIOIRQ	T1IRQ	-	P00IRQ
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	-	R/W
After reset	0	0	0	0	0	0	-	0

Bit 0     **P00IRQ**: External P0.0 interrupt (INT0) request flag.  
0 = None INT0 interrupt request.  
1 = INT0 interrupt request.

Bit 2     **T1IRQ**: T1 timer interrupt request flag.  
0 = None T1 interrupt request.  
1 = T1 interrupt request.

Bit 3     **SIOIRQ**: SIO interrupt request flag.  
0 = None SIO interrupt request.  
1 = SIO interrupt request.

Bit 4     **T0IRQ**: T0 timer interrupt request flag.  
0 = None T0 interrupt request.  
1 = T0 interrupt request.

Bit 5     **TC0IRQ**: TC0 timer interrupt request flag.  
0 = None TC0 interrupt request.  
1 = TC0 interrupt request.

Bit 6     **TC1IRQ**: TC1 timer interrupt request flag.  
0 = None TC1 interrupt request.  
1 = TC1 interrupt request.

Bit 7     **CM0IRQ**: Comparator 0 interrupt request flag.  
0 = None comparator 0 interrupt request.  
1 = Comparator 0 interrupt request.

## 6.4 GIE GLOBAL INTERRUPT OPERATION

GIE is the global interrupt control bit. All interrupts start work after the GIE = 1. It is necessary for interrupt service request. One of the interrupt requests occurs, and the program counter (PC) points to the interrupt vector (ORG 8) and the stack add 1 level.

ODFH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>STKP</b>	GIE	-	-	-	-	STKPB2	STKPB1	STKPB0
Read/Write	R/W	-	-	-	-	R/W	R/W	R/W
After reset	0	-	-	-	-	1	1	1

Bit 7      **GIE:** Global interrupt control bit.  
 0 = Disable global interrupt.  
 1 = Enable global interrupt.

□ **Example: Set global interrupt control bit (GIE).**

BOBSET      FGIE      ; Enable GIE

\* **Note: The GIE bit must enable during all interrupt operation.**

## 6.5 PUSH, POP ROUTINE

When any interrupt occurs, system will jump to ORG 8 and execute interrupt service routine. It is necessary to save ACC, PFLAG data. The chip includes "PUSH", "POP" for in/out interrupt service routine. The two instructions save and load **ACC**, **PFLAG** data into buffers and avoid main routine error after interrupt service routine finishing.

\* **Note:** "PUSH", "POP" instructions save and load ACC/PFLAG without (NT0, NPD). PUSH/POP buffer is an unique buffer and only one level.

➤ **Example:** Store ACC and PAFLG data by PUSH, POP instructions when interrupt service routine executed.

```

                                ORG      0
                                JMP      START

                                ORG      8
                                JMP      INT_SERVICE

START:                          ORG      10H
                                ...

INT_SERVICE:                    PUSH                      ; Save ACC and PFLAG to buffers.
                                ...
                                ...
                                POP                        ; Load ACC and PFLAG from buffers.
                                RETI                       ; Exit interrupt service vector
                                ...
                                ENDP

```

## 6.6 EXTERNAL INTERRUPT OPERATION (INT0)

INT0 is external interrupt trigger source and builds in edge trigger configuration function. When the external edge trigger occurs, the external interrupt request flag will be set to "1" no matter the external interrupt control bit enabled or disable. When external interrupt control bit is enabled and external interrupt edge trigger is occurring, the program counter will jump to the interrupt vector (ORG 8) and execute interrupt service routine.

The external interrupt builds in wake-up latch function. That means when the system is triggered wake-up from power down mode, the wake-up source is external interrupt source (P0.0), and the trigger edge direction matches interrupt edge configuration, the trigger edge will be latched, and the system executes interrupt service routine first after wake-up.

0BFH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>PEDGE</b>	-	-	-	P00G1	P00G0	-	-	-
Read/Write	-	-	-	R/W	R/W	-	-	-
After reset	-	-	-	1	0	-	-	-

Bit[4:3] **P00G[1:0]**: INT0 edge trigger select bits.  
 00 = reserved,  
 01 = rising edge,  
 10 = falling edge,  
 11 = rising/falling bi-direction.

- Example: Setup INT0 interrupt request and bi-direction edge trigger.**

```

MOV      A, #18H
B0MOV    PEDGE, A      ; Set INT0 interrupt trigger as bi-direction edge.

B0BSET   FP00IEN       ; Enable INT0 interrupt service
B0BCLR   FP00IRQ       ; Clear INT0 interrupt request flag
B0BSET   FGIE          ; Enable GIE
  
```

- Example: INT0 interrupt service routine.**

```

ORG      8              ; Interrupt vector
JMP      INT_SERVICE

INT_SERVICE:
...              ; Push routine to save ACC and PFLAG to buffers.

B0BTS1   FP00IRQ       ; Check P00IRQ
JMP      EXIT_INT      ; P00IRQ = 0, exit interrupt vector

B0BCLR   FP00IRQ       ; Reset P00IRQ
...              ; INT0 interrupt service routine

EXIT_INT:
...              ; Pop routine to load ACC and PFLAG from buffers.
RETI         ; Exit interrupt vector
  
```

## 6.7 T0 INTERRUPT OPERATION

When the T0C counter occurs overflow, the T0IRQ will be set to “1” however the T0IEN is enable or disable. If the T0IEN = 1, the trigger event will make the T0IRQ to be “1” and the system enter interrupt vector. If the T0IEN = 0, the trigger event will make the T0IRQ to be “1” but the system will not enter interrupt vector. Users need to care for the operation under multi-interrupt situation.

➤ **Example: T0 interrupt request setup.**

B0BCLR	FT0IEN	; Disable T0 interrupt service
B0BCLR	FT0ENB	; Disable T0 timer
MOV	A, #20H	;
B0MOV	T0M, A	; Set T0 clock = Fcpu / 64
MOV	A, #74H	; Set T0C initial value = 74H
B0MOV	T0C, A	; Set T0 interval = 10 ms
B0BSET	FT0IEN	; Enable T0 interrupt service
B0BCLR	FT0IRQ	; Clear T0 interrupt request flag
B0BSET	FT0ENB	; Enable T0 timer
B0BSET	FGIE	; Enable GIE

**Example: T0 interrupt service routine.**

ORG	8	; Interrupt vector
JMP	INT_SERVICE	
INT_SERVICE:		
...		; Push routine to save ACC and PFLAG to buffers.
<b>B0BTS1</b>	<b>FT0IRQ</b>	<b>; Check T0IRQ</b>
<b>JMP</b>	<b>EXIT_INT</b>	<b>; T0IRQ = 0, exit interrupt vector</b>
<b>B0BCLR</b>	<b>FT0IRQ</b>	<b>; Reset T0IRQ</b>
<b>MOV</b>	<b>A, #74H</b>	
<b>B0MOV</b>	<b>T0C, A</b>	<b>; Reset T0C.</b>
...		<b>; T0 interrupt service routine</b>
...		
EXIT_INT:		
...		; Pop routine to load ACC and PFLAG from buffers.
...		
RETI		; Exit interrupt vector

## 6.8 TC0 INTERRUPT OPERATION

When the TC0C counter overflows, the TC0IRQ will be set to “1” no matter the TC0IEN is enable or disable. If the TC0IEN and the trigger event TC0IRQ is set to be “1”. As the result, the system will execute the interrupt vector. If the TC0IEN = 0, the trigger event TC0IRQ is still set to be “1”. Moreover, the system won't execute interrupt vector even when the TC0IEN is set to be “1”. Users need to be cautious with the operation under multi-interrupt situation.

➤ **Example: TC0 interrupt request setup. Fcpu = 16MHz / 16.**

B0BCLR	FTC0IEN	; Disable TC0 interrupt service
B0BCLR	FTC0ENB	; Disable TC0 timer
MOV	A, #20H	;
B0MOV	TC0M, A	; Set TC0 clock = Fcpu / 64
MOV	A, #64H	; Set TC0C initial value = 64H
B0MOV	TC0C, A	; Set TC0 interval = 10 ms
B0BSET	FTC0IEN	; Enable TC0 interrupt service
B0BCLR	FTC0IRQ	; Clear TC0 interrupt request flag
B0BSET	FTC0ENB	; Enable TC0 timer
B0BSET	FGIE	; Enable GIE

➤ **Example: TC0 interrupt service routine.**

	ORG	8	; Interrupt vector
	JMP	INT_SERVICE	
INT_SERVICE:			
	...		; Push routine to save ACC and PFLAG to buffers.
	<b>B0BTS1</b>	<b>FTC0IRQ</b>	<b>; Check TC0IRQ</b>
	<b>JMP</b>	<b>EXIT_INT</b>	<b>; TC0IRQ = 0, exit interrupt vector</b>
	<b>B0BCLR</b>	<b>FTC0IRQ</b>	<b>; Reset TC0IRQ</b>
	<b>MOV</b>	<b>A, #64H</b>	<b>; Reset TC0C.</b>
	<b>B0MOV</b>	<b>TC0C, A</b>	<b>; TC0 interrupt service routine</b>
	...		
	...		
EXIT_INT:			
	...		; Pop routine to load ACC and PFLAG from buffers.
	RETI		; Exit interrupt vector

## 6.9 TC1 INTERRUPT OPERATION

When the TC1C counter overflows, the TC1IRQ will be set to “1” no matter the TC1IEN is enable or disable. If the TC1IEN and the trigger event TC1IRQ is set to be “1”. As the result, the system will execute the interrupt vector. If the TC1IEN = 0, the trigger event TC1IRQ is still set to be “1”. Moreover, the system won’t execute interrupt vector even when the TC1IEN is set to be “1”. Users need to be cautious with the operation under multi-interrupt situation.

**Example: TC1 interrupt request setup. Fcpu = 16Mhz / 16.**

B0BCLR	FTC1IEN	; Disable TC1 interrupt service
B0BCLR	FTC1ENB	; Disable TC1 timer
MOV	A, #20H	;
B0MOV	TC1M, A	; Set TC1 clock = Fcpu / 64
MOV	A, #64H	; Set TC1C initial value = 64H
B0MOV	TC1C, A	; Set TC1 interval = 10 ms
B0BSET	FTC1IEN	; Enable TC1 interrupt service
B0BCLR	FTC1IRQ	; Clear TC1 interrupt request flag
B0BSET	FTC1ENB	; Enable TC1 timer
B0BSET	FGIE	; Enable GIE

**Example: TC1 interrupt service routine.**

	ORG	8	; Interrupt vector
	JMP	INT_SERVICE	
INT_SERVICE:			
	...		; Push routine to save ACC and PFLAG to buffers.
	<b>B0BTS1</b>	<b>FTC1IRQ</b>	<b>; Check TC1IRQ</b>
	<b>JMP</b>	<b>EXIT_INT</b>	<b>; TC1IRQ = 0, exit interrupt vector</b>
	<b>B0BCLR</b>	<b>FTC1IRQ</b>	<b>; Reset TC1IRQ</b>
	<b>MOV</b>	<b>A, #74H</b>	
	<b>B0MOV</b>	<b>TC1C, A</b>	<b>; Reset TC1C.</b>
	...		<b>; TC1 interrupt service routine</b>
	...		
EXIT_INT:			
	...		; Pop routine to load ACC and PFLAG from buffers.
	RETI		; Exit interrupt vector

## 6.10 T1 INTERRUPT OPERATION

When the T1C (T1CH, T1CL) counter occurs overflow, the T1IRQ will be set to "1" however the T1IEN is enable or disable. If the T1IEN = 1, the trigger event will make the T1IRQ to be "1" and the system enter interrupt vector. If the T1IEN = 0, the trigger event will make the T1IRQ to be "1" but the system will not enter interrupt vector. Users need to care for the operation under multi-interrupt situation.

### ➤ Example: T1 interrupt request setup.

```

B0BCLR    FT1IEN    ; Disable T1 interrupt service
B0BCLR    FT1ENB    ; Disable T1 timer
MOV       A, #20H   ;
B0MOV     T1M, A     ; Set T1 clock = Fcpu / 32 and falling edge trigger.
CLR       T1CH
CLR       T1CL

B0BSET    FT1IEN    ; Enable T1 interrupt service
B0BCLR    FT1IRQ    ; Clear T1 interrupt request flag
B0BSET    FT1ENB    ; Enable T1 timer

B0BSET    FGIE      ; Enable GIE

```

### Example: T1 interrupt service routine.

```

INT_SERVICE:
ORG       8          ; Interrupt vector
JMP       INT_SERVICE

PUSH      ; Push routine to save ACC and PFLAG to buffers.

B0BTS1    FT1IRQ    ; Check T1IRQ
JMP       EXIT_INT  ; T1IRQ = 0, exit interrupt vector

B0BCLR    FT1IRQ    ; Reset T1IRQ
B0MOV     A, T1CH
B0MOV     T1CHBUF, A
B0MOV     A, T1CL
B0MOV     T1CLBUF, A ; Save pulse width.
CLR       T1CH
CLR       T1CL

...       ; T1 interrupt service routine
...

EXIT_INT:
POP       ; Pop routine to load ACC and PFLAG from buffers.

RETI      ; Exit interrupt vector

```



## 6.11 SIO INTERRUPT OPERATION

When the SIO converting successfully, the SIOIRQ will be set to “1” no matter the SIOIEN is enable or disable. If the SIOIEN and the trigger event SIOIRQ is set to be “1”. As the result, the system will execute the interrupt vector. If the SIOIEN = 0, the trigger event SIOIRQ is still set to be “1”. Moreover, the system won’t execute interrupt vector even when the SIOIEN is set to be “1”. Users need to be cautious with the operation under multi-interrupt situation.

➤ **Example: SIO interrupt request setup.**

B0BSET	FSIOIEN	; Enable SIO interrupt service
B0BCLR	FSIOIRQ	; Clear SIO interrupt request flag
B0BSET	FGIE	; Enable GIE

➤ **Example: SIO interrupt service routine.**

	ORG	8	; Interrupt vector
	JMP	INT_SERVICE	
INT_SERVICE:			
	...		; Push routine to save ACC and PFLAG to buffers.
	<b>B0BTS1</b>	<b>FSIOIRQ</b>	<b>; Check SIOIRQ</b>
	<b>JMP</b>	<b>EXIT_INT</b>	<b>; SIOIRQ = 0, exit interrupt vector</b>
	<b>B0BCLR</b>	<b>FSIOIRQ</b>	<b>; Reset SIOIRQ</b>
	...		<b>; SIO interrupt service routine</b>
	...		
EXIT_INT:			
	...		; Pop routine to load ACC and PFLAG from buffers.
	RETI		; Exit interrupt vector

## 6.12 COMPARATOR INTERRUPT OPERATION (CMP0)

Sonix provides one comparator with interrupt function in the micro-controller. The comparator interrupt trigger edge direction depend on CM0G[1:0]. When the comparator output status transition occurs, the comparator interrupt request flag will be set to "1" no matter the comparator interrupt control bit status. The comparator interrupt flag doesn't active only when comparator control bit is disabled. When comparator interrupt control bit is enabled and comparator interrupt edge trigger is occurring, the program counter will jump to the interrupt vector (ORG 8) and execute interrupt service routine.

**Example: Setup comparator 0 interrupt request.**

B0BSET	FCM0IEN	; Enable comparator 0 interrupt service
B0BCLR	FCM0IRQ	; Clear comparator 0 interrupt request flag
B0BSET	FCM0EN	; Enable comparator 0.
B0BSET	FGIE	; Enable GIE

**Example: Comparator 0 interrupt service routine.**

	ORG	8	; Interrupt vector
	JMP	INT_SERVICE	
INT_SERVICE:			
	...		; Push routine to save ACC and PFLAG to buffers.
	B0BTS1	FCM0IRQ	; Check CM0IRQ
	JMP	EXIT_INT	; CM0IRQ = 0, exit interrupt vector
	B0BCLR	FCM0IRQ	; Reset CM0IRQ
	...		; Comparator 0 interrupt service routine
EXIT_INT:			
	...		; Pop routine to load ACC and PFLAG from buffers.
	RETI		; Exit interrupt vector

## 6.13 MULTI-INTERRUPT OPERATION

Under certain condition, the software designer uses more than one interrupt requests. Processing multi-interrupt request requires setting the priority of the interrupt requests. The IRQ flags of interrupts are controlled by the interrupt event. Nevertheless, the IRQ flag "1" doesn't mean the system will execute the interrupt vector. In addition, which means the IRQ flags can be set "1" by the events without enable the interrupt. Once the event occurs, the IRQ will be logic "1". The IRQ and its trigger event relationship is as the below table.

<b>Interrupt Name</b>	<b>Trigger Event Description</b>
P00IRQ	P0.0 trigger controlled by PEDGE
T0IRQ	T0C overflow
TC0IRQ	TC0C overflow
TC1IRQ	TC1C overflow
T1IRQ	T1C (T1CH, T1CL) overflow
SIOIRQ	SIO transmitter successfully.
CM0IRQ	Comparator 0 output level transition.

For multi-interrupt conditions, two things need to be taking care of. One is to set the priority for these interrupt requests. Two is using IEN and IRQ flags to decide which interrupt to be executed. Users have to check interrupt control bit and interrupt request flag in interrupt routine.

➤ **Example: Check the interrupt request under multi-interrupt operation**

```

ORG          8                ; Interrupt vector
JMP          INT_SERVICE
INT_SERVICE:

...                ; Push routine to save ACC and PFLAG to buffers.

INTP00CHK:        ; Check INT0 interrupt request
                  ; Check P00IEN
B0BTS1          FP00IEN
JMP             INTT0CHK    ; Jump check to next interrupt
B0BTS0          FP00IRQ    ; Check P00IRQ
JMP             INTP00

INTT0CHK:         ; Check T0 interrupt request
                  ; Check T0IEN
B0BTS1          FT0IEN
JMP             INTTC1CHK   ; Jump check to next interrupt
B0BTS0          FT0IRQ    ; Check T0IRQ
JMP             INTT0      ; Jump to T0 interrupt service routine

INTTC1CHK:        ; Check TC1 interrupt request
                  ; Check TC1IEN
B0BTS1          FTC1IEN
JMP             INTSIOHK    ; Jump check to next interrupt
B0BTS0          FTC1IRQ    ; Check TC1IRQ
JMP             INTTC1     ; Jump to TC1 interrupt service routine

INTSIOHK:         ; Check SIO interrupt request
                  ; Check SIOIEN
B0BTS1          FSIOIEN
JMP             ...        ; Jump check to next interrupt
B0BTS0          FSIOIRQ    ; Check SIOIRQ
JMP             INTSIO     ; Jump to SIO interrupt service routine

...
...

INT_EXIT:
...                ; Pop routine to load ACC and PFLAG from buffers.

RETI            ; Exit interrupt vector

```

# 7 I/O PORT

## 7.1 OVERVIEW

The micro-controller builds in 16 pin I/O. Most of the I/O pins are mixed with analog pins and special function pins. The I/O shared pin list is as following.

I/O Pin		Shared Pin		Shared Pin Control Condition
Name	Type	Name	Type	
P0.0	I/O	INT0	DC	P00IEN=1
P5.6	I	RST	DC	Reset_Pin code option = Reset
		VPP	HV	OTP Programming
P1.0	I/O	CM0N0	AC	CM0EN=1, CM0REF=0, CMCHS[2:0] = 0
		CM0P	AC	CM0EN=1, CM0REF=1
P1.1	I/O	CM0N1	AC	CM0EN=1, CMCHS[2:0] = 1
P1.2	I/O	CM0N2	AC	CM0EN=1, CMCHS[2:0] = 2
P1.3	I/O	CM0N3	AC	CM0EN=1, CMCHS[2:0] = 3
P1.4	I/O	CM0N4	AC	CM0EN=1, CMCHS[2:0] = 4
P1.5	I/O	CM0N5	AC	CM0EN=1, CMCHS[2:0] = 5
P1.6	I/O	CM0N6	AC	CM0EN=1, CMCHS[2:0] = 6
P1.7	I/O	CM0N7	AC	CM0EN=1, CMCHS[2:0] = 7
P5.0	I/O	SCK	DC	SENB=1.
P5.1	I/O	SI	DC	SENB=1.
P5.2	I/O	SO	DC	SENB=1.
P5.3	I/O	PWM1	DC	TC1ENB=1, PWM1OUT=1
P5.4	I/O	PWM0	DC	TC0ENB=1, PWM0OUT=1

\* DC: Digital Characteristic. AC: Analog Characteristic. HV: High Voltage Characteristic.

## 7.2 I/O PORT MODE

The port direction is programmed by PnM register. All I/O ports can select input or output direction.

0B8H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P0M</b>	-	-	-	-	-	-	-	P00M
Read/Write	-	-	-	-	-	-	-	R/W
After reset	-	-	-	-	-	-	-	0

0C1H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P1M</b>	P17M	P16M	P15M	P14M	P13M	P12M	P11M	P10M
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

0C5H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P5M</b>	-	-	P55M	P54M	P53M	P52M	P51M	P50M
Read/Write	-	-	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	-	0	0	0	0	0	0

Bit[7:0] **PnM[7:0]**: Pn mode control bits. (n = 0~5).  
 0 = Pn is input mode.  
 1 = Pn is output mode.

- \* **Note:**
1. Users can program them by bit control instructions (**B0BSET**, **B0BCLR**).
  2. P5.6 input only pin, and the P5M.6 keeps "1".

### ➤ Example: I/O mode selecting

```

CLR      P0M      ; Set all ports to be input mode.
CLR      P1M
CLR      P5M

MOV      A, #0FFH ; Set all ports to be output mode.
B0MOV    P0M, A
B0MOV    P1M, A
B0MOV    P5M, A

B0BCLR   P1M.0    ; Set P1.0 to be input mode.

B0BSET   P1M.0    ; Set P1.0 to be output mode.
```

## 7.3 I/O PULL UP REGISTER

0E0H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P0UR</b>	-	-	-	-	-	-	-	P00R
Read/Write	-	-	-	-	-	-	-	W
After reset	-	-	-	-	-	-	-	0

0E1H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P1UR</b>	P17R	P16R	P15R	P14R	P13R	P12R	P11R	P10R
Read/Write	W	W	W	W	W	W	W	W
After reset	0	0	0	0	0	0	0	0

0E5H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P5UR</b>	-	-	P55R	P54R	P53R	P52R	P51R	P50R
Read/Write	-	-	W	W	W	W	W	W
After reset	-	-	0	0	0	0	0	0

\* **Note:** P5.6 is input only pin and without pull-up resister. The P5UR.6 keeps "1".

### ➤ Example: I/O Pull up Register

```

MOV      A, #0FFH      ; Enable Port0, 1, 5 Pull-up register,
B0MOV    P0UR, A        ;
B0MOV    P1UR,A
B0MOV    P5UR, A

```

## 7.4 I/O PORT DATA REGISTER

0D0H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P0</b>	-	-	-	-	-	-	-	P00
Read/Write	-	-	-	-	-	-	-	R/W
After reset	-	-	-	-	-	-	-	0

0D1H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P1</b>	P17	P16	P15	P14	P13	P12	P11	P10
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

0D5H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P5</b>	-	P56	P55	P54	P53	P52	P51	P50
Read/Write	-	R	R/W	R/W	R/W	R/W	R/W	R/W
After reset	-	0	0	0	0	0	0	0

\* **Note:** The P56 keeps “1” when external reset enable by code option.

➤ **Example: Read data from input port.**

```

B0MOV      A, P0      ; Read data from Port 0
B0MOV      A, P1      ; Read data from Port 1
B0MOV      A, P5      ; Read data from Port 5

```

➤ **Example: Write data to output port.**

```

MOV        A, #0FFH   ; Write data FFH to all Port.
B0MOV      P0, A
B0MOV      P1, A
B0MOV      P5, A

```

➤ **Example: Write one bit data to output port.**

```

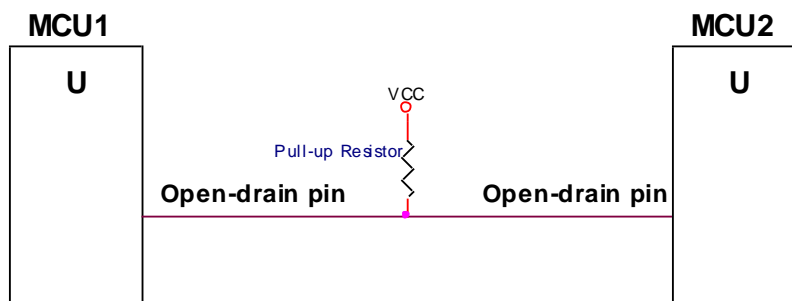
B0BSET     P1.0        ; Set P1.0 and P5.3 to be “1”.
B0BSET     P5.3

B0BCLR     P1.0        ; Set P1.0 and P5.3 to be “0”.
B0BCLR     P5.3

```

## 7.5 I/O OPEN-DRAIN REGISTER

P5.0~P5.4 built in open-drain function. These pins must be set as output mode when enable open-drain function. Open-drain external circuit is as following.



The pull-up resistor is necessary. Open-drain output high is driven by pull-up resistor. Output low is sunken by MCU's pin.

0E9H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>P10C</b>	-	P54OC	P53OC	P52OC	P51OC	P50OC	-	-
Read/Write	-	W	W	W	W	W	-	-
After reset	-	0	0	0	0	0	-	-

Bit 2     **P50OC**: P5.0 open-drain control bit  
 0 = Disable open-drain mode  
 1 = Enable open-drain mode

Bit 3     **P51OC**: P5.1 open-drain control bit  
 0 = Disable open-drain mode  
 1 = Enable open-drain mode

Bit 4     **P52OC**: P5.2 open-drain control bit  
 0 = Disable open-drain mode  
 1 = Enable open-drain mode

Bit 5     **P53OC**: P5.3 open-drain control bit  
 0 = Disable open-drain mode  
 1 = Enable open-drain mode

Bit 6     **P54OC**: P5.4 open-drain control bit  
 0 = Disable open-drain mode  
 1 = Enable open-drain mode



➤ **Example: Enable P5.0 to open-drain mode and output high.**

B0BSET	P5.0	; Set P5.0 buffer high.
B0BSET	P50M	; Enable P5.0 output mode.
MOV	A, #04H	; Enable P5.0 open-drain function.
B0MOV	P1OC, A	

\* **Note: P1OC is write only register. Setting P10OC must be used “MOV” instructions.**

➤ **Example: Disable open-drain mode.**

MOV	A, #0	; Disable open-drain function.
B0MOV	P1OC, A	

\* **Note: After disable open-drain function, I/O mode returns to last I/O mode.**

# 8 TIMERS

## 8.1 WATCHDOG TIMER

The watchdog timer (WDT) is a binary up counter designed for monitoring program execution. If the program goes into the unknown status by noise interference, WDT overflow signal raises and resets MCU. Watchdog clock controlled by code option and the clock source is internal low-speed oscillator.

**Watchdog overflow time = 8192 / Internal Low-Speed oscillator (sec).**

VDD	Internal Low RC Freq.	Watchdog Overflow Time
3V	16KHz	512ms
5V	32KHz	256ms

The watchdog timer has three operating options controlled “WatchDog” code option.

- **Disable:** Disable watchdog timer function.
- **Enable:** Enable watchdog timer function. Watchdog timer actives in normal mode and slow mode. In power down mode and green mode, the watchdog timer stops.
- **Always\_On:** Enable watchdog timer function. The watchdog timer actives and not stop in power down mode and green mode.

**In high noisy environment, the “Always\_On” option of watchdog operations is the strongly recommendation to make the system reset under error situations and re-start again.**

Watchdog clear is controlled by WDTR register. Moving **0x5A** data into WDTR is to reset watchdog timer.

0CCH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>WDTR</b>	WDTR7	WDTR6	WDTR5	WDTR4	WDTR3	WDTR2	WDTR1	WDTR0
Read/Write	W	W	W	W	W	W	W	W
After reset	0	0	0	0	0	0	0	0

- **Example: An operation of watchdog timer is as following. To clear the watchdog timer counter in the top of the main routine of the program.**

Main:

```

MOV      A, #5AH      ; Clear the watchdog timer.
B0MOV    WDTR, A
...
CALL     SUB1
CALL     SUB2
...
JMP      MAIN

```

- **Example: Clear watchdog timer by “@RST\_WDT” macro of Sonix IDE.**

Main:

```

@RST_WDT      ; Clear the watchdog timer.
...
CALL     SUB1
CALL     SUB2
...
JMP      MAIN

```

Watchdog timer application note is as following.

- Before clearing watchdog timer, check I/O status and check RAM contents can improve system error.
- Don't clear watchdog timer in interrupt vector and interrupt service routine. That can improve main routine fail.
- Clearing watchdog timer program is only at one part of the program. This way is the best structure to enhance the watchdog timer function.

➤ **Example: An operation of watchdog timer is as following. To clear the watchdog timer counter in the top of the main routine of the program.**

Main:

...

; Check I/O.

...

; Check RAM

Err:

JMP \$

; I/O or RAM error. Program jump here and don't  
; clear watchdog. Wait watchdog timer overflow to reset IC.

Correct:

; I/O and RAM are correct. Clear watchdog timer and  
; execute program.

**MOV           A, #5AH**  
**B0MOV       WDTR, A**

**; Clear the watchdog timer.**

...

CALL       SUB1

CALL       SUB2

...

...

...

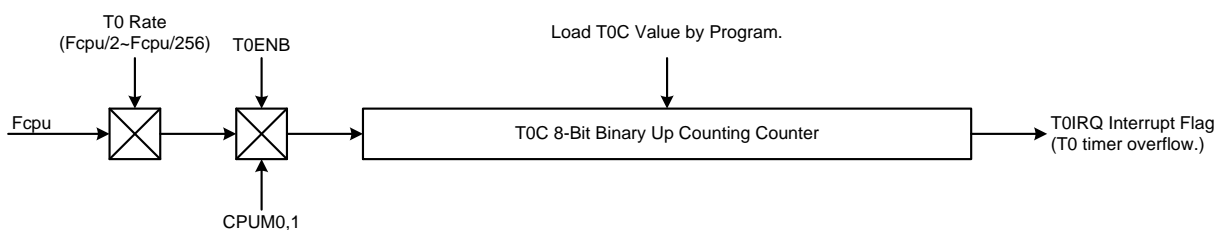
JMP       MAIN

## 8.2 T0 8-BIT BASIC TIMER

### 8.2.1 OVERVIEW

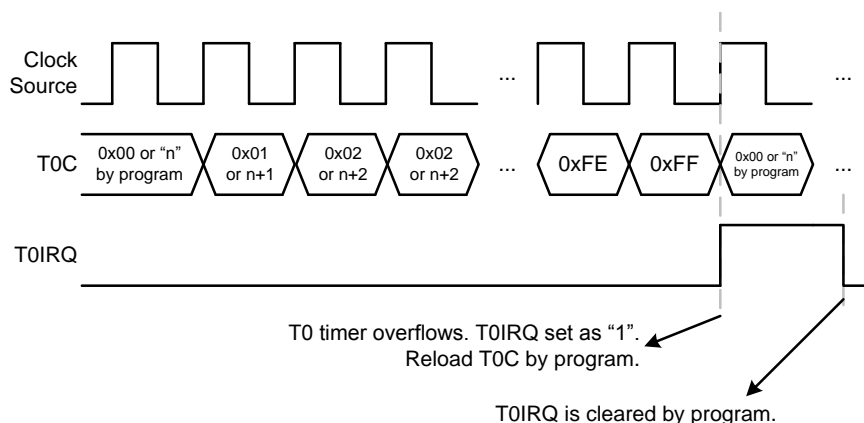
The T0 timer is an 8-bit binary up timer with basic timer function. The basic timer function supports flag indicator (T0IRQ bit) and interrupt operation (interrupt vector). The interval time is programmable through T0M, T0C registers. The T0 builds in green mode wake-up function. When T0 timer overflow occurs under green mode, the system will be waked-up to last operating mode.

- ☞ **8-bit programmable up counting timer:** Generate time-out at specific time intervals based on the selected clock frequency.
- ☞ **Interrupt function:** T0 timer function supports interrupt function. When T0 timer occurs overflow, the T0IRQ activates and the system points program counter to interrupt vector to do interrupt sequence.
- ☞ **Green mode function:** T0 timer keeps running in green mode and wakes up system when T0 timer overflows.



### 8.2.2 T0 TIMER OPERATION

T0 timer is controlled by T0ENB bit. When T0ENB=0, T0 timer stops. When T0ENB=1, T0 timer starts to count. T0C increases "1" by timer clock source. When T0 overflow event occurs, T0IRQ flag is set as "1" to indicate overflow and cleared by program. The overflow condition is T0C count from full scale (0xFF) to zero scale (0x00). T0 doesn't build in double buffer, so load T0C by program when T0 timer overflows to fix the correct interval time. If T0 timer interrupt function is enabled (T0IEN=1), the system will execute interrupt procedure. The interrupt procedure is system program counter points to interrupt vector (ORG 8) and executes interrupt service routine after T0 overflow occurrence. Clear T0IRQ by program is necessary in interrupt procedure. T0 timer can work in normal mode, slow mode and green mode. In green mode, T0 keeps counting, set T0IRQ and wakes up system when T0 timer overflows.



T0 clock source is Fcpu (instruction cycle) through T0rate[2:0] pre-scaler to decide Fcpu/2~Fcpu/256. T0 length is 8-bit (256 steps), and the one count period is each cycle of input clock.

T0rate[2:0]	T0 Clock	T0 Interval Time	
		Fhosc=16MHz, Fcpu=Fhosc/2	
		max. (ms)	Unit (us)
000b	Fcpu/256	8.192	32
001b	Fcpu/128	4.096	16
010b	Fcpu/64	2.048	8
011b	Fcpu/32	1.024	4
100b	Fcpu/16	0.512	2
101b	Fcpu/8	0.256	1
110b	Fcpu/4	0.128	0.5
111b	Fcpu/2	0.064	0.25

## 8.2.3 T0M MODE REGISTER

T0M is T0 timer mode control register to configure T0 operating mode including T0 pre-scaler, clock source... These configurations must be setup completely before enabling T0 timer.

0D8H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T0M</b>	T0ENB	T0rate2	T0rate1	T0rate0	-	-	-	-
Read/Write	R/W	R/W	R/W	R/W	-	-	-	-
After reset	0	0	0	0	-	-	-	-

Bit [6:4] **T0RATE[2:0]**: T0 timer clock source select bits.  
 000 = Fcpu/256, 001 = Fcpu/128, 010 = Fcpu/64, 011 = Fcpu/32, 100 = Fcpu/16, 101 = Fcpu/8, 110 = Fcpu/4, 111 = Fcpu/2.

Bit 7 **T0ENB**: T0 counter control bit.  
 0 = Disable T0 timer.  
 1 = Enable T0 timer.

## 8.2.4 T0C COUNTING REGISTER

T0C is T0 8-bit counter. When T0C overflow occurs, the T0IRQ flag is set as "1" and cleared by program. The T0C decides T0 interval time through below equation to calculate a correct value. It is necessary to write the correct value to T0C register, and then enable T0 timer to make sure the first cycle correct. After one T0 overflow occurs, the T0C register is loaded a correct value by program.

0D9H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T0C</b>	T0C7	T0C6	T0C5	T0C4	T0C3	T0C2	T0C1	T0C0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

The equation of T0C initial value is as following.

$$T0C \text{ initial value} = 256 - (T0 \text{ interrupt interval time} * T0 \text{ clock rate})$$

- **Example: To calculation T0C to obtain 10ms T0 interval time. T0 clock source is Fcpu = 16MHz/16 = 1MHz. Select T0RATE=001 (Fcpu/128).**  
 T0 interval time = 10ms. T0 clock rate = 16MHz/16/128

$$\begin{aligned}
 T0C \text{ initial value} &= 256 - (T0 \text{ interval time} * \text{input clock}) \\
 &= 256 - (10\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= 256 - (10^{-2} * 16\text{MHz} / 16 / 128) \\
 &= B2H
 \end{aligned}$$

## 8.2.5 T0 TIMER OPERATION EXPLAME

- T0 TIMER CONFIGURATION:

; Reset T0 timer.

```
CLR          T0M          ; Clear T0M register.
```

; Set T0 clock source and T0 rate.

```
MOV          A, #0nnn0000b
BO MOV       T0M, A
```

; Set T0C register for T0 Interval time.

```
MOV          A, #value
BO MOV       T0C, A
```

; Clear T0IRQ

```
BO BCLR      FT0IRQ
```

; Enable T0 timer and interrupt function.

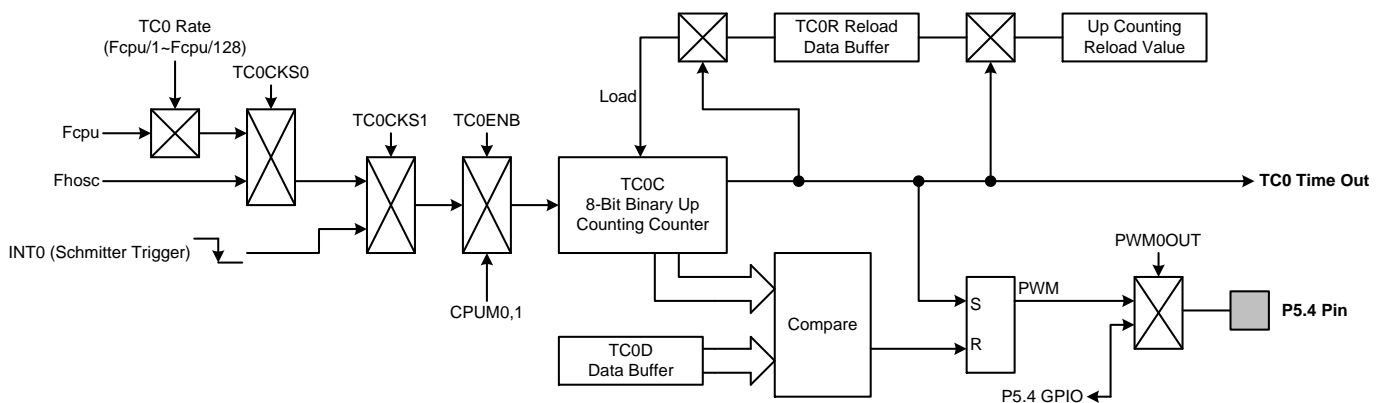
```
BO BSET      FT0IEN      ; Enable T0 interrupt function.
BO BSET      FT0ENB      ; Enable T0 timer.
```

## 8.3 TC0 8-BIT TIMER/COUNTER

### 8.3.1 OVERVIEW

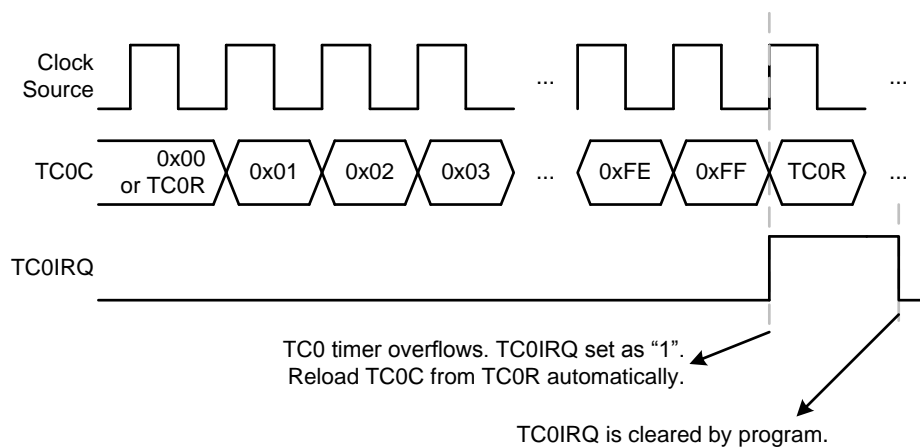
The TC0 timer is an 8-bit binary up timer with basic timer, event counter and PWM functions. The basic timer function supports flag indicator (TC0IRQ bit) and interrupt operation (interrupt vector). The interval time is programmable through TC0M, TC0C, TC0R registers. The event counter is changing TC0 clock source from system clock (Fcpu/Fhosc) to external clock like signal (e.g. continuous pulse, R/C type oscillating signal...). TC0 becomes a counter to count external clock number to implement measure application. TC0 also builds in duty/cycle programmable PWM. The PWM cycle and resolution are controlled by TC0 timer clock rate, TC0R and TC0D registers, so the PWM with good flexibility to implement IR carry signal, motor control and brightness adjuster...The main purposes of the TC0 timer are as following.

- ☞ **8-bit programmable up counting timer:** Generate time-out at specific time intervals based on the selected clock frequency.
- ☞ **Interrupt function:** TC0 timer function supports interrupt function. When TC0 timer occurs overflow, the TC0IRQ activates and the system points program counter to interrupt vector to do interrupt sequence.
- ☞ **Event Counter:** The event counter function counts the external clock counts.
- ☞ **Duty/cycle programmable PWM:** The PWM is duty/cycle programmable controlled by TC0R and TC0D registers.
- ☞ **Green mode function:** All TC0 functions (timer, PWM, event counter, auto-reload) keep running in green mode and no wake-up function.



### 8.3.2 TC0 TIMER OPERATION

TC0 timer is controlled by TC0ENB bit. When TC0ENB=0, TC0 timer stops. When TC0ENB=1, TC0 timer starts to count. Before enabling TC0 timer, setup TC0 timer's configurations to select timer function modes, e.g. basic timer, interrupt function...TC0C increases "1" by timer clock source. When TC0 overflow event occurs, TC0IRQ flag is set as "1" to indicate overflow and cleared by program. The overflow condition is TC0C count from full scale (0xFF) to zero scale (0x00). In difference function modes, TC0C value relates to operation. If TC0C value changing effects operation, the transition of operations would make timer function error. So TC0 builds in double buffer to avoid these situations happen. The double buffer concept is to flash TC0C during TC0 counting, to set the new value to TC0R (reload buffer), and the new value will be loaded from TC0R to TC0C after TC0 overflow occurrence automatically. In the next cycle, the TC0 timer runs under new conditions, and no any transitions occur. The auto-reload function is no any control interface and always actives as TC0 enables. If TC0 timer interrupt function is enabled (TC0IEN=1), the system will execute interrupt procedure. The interrupt procedure is system program counter points to interrupt vector (ORG 8) and executes interrupt service routine after TC0 overflow occurrence. Clear TC0IRQ by program is necessary in interrupt procedure. TC0 timer can works in normal mode, slow mode and green mode. But in green mode, TC0 keep counting, set TC0IRQ and outputs PWM, but can't wake-up system.



TC0 provides different clock sources to implement different applications and configurations. TC0 clock source includes Fcpu (instruction cycle), Fhosc (high speed oscillator) and external input pin (P0.0) controlled by TC0CKS[1:0] bits. TC0CKS0 bit selects the clock source is from Fcpu or Fhosc. If TC0CKS0=0, TC0 clock source is Fcpu through TC0rate[2:0] pre-scaler to decide Fcpu/1~Fcpu/128. If TC0CKS0=1, TC0 clock source is Fhosc without any divider. TC0CKS1 bit controls the clock source is external input pin or controlled by TC0CKS0 bit. If TC0CKS1=0, TC0 clock source is selected by TC0CKS0 bit. If TC0CKS1=1, TC0 clock source is external input pin that means to enable event counter function. TC0rate[2:0] pre-scaler is unless when TC0CKS0=1 or TC0CKS1=1 conditions. TC0 length is 8-bit (256 steps), and the one count period is each cycle of input clock.

TC0CKS0	TC0rate[2:0]	TC0 Clock	TC0 Interval Time	
			Fhosc=16MHz, Fcpu=Fhosc/2	
			max. (ms)	Unit (us)
0	000b	Fcpu/128	4.096	16
0	001b	Fcpu/64	2.048	8
0	010b	Fcpu/32	1.024	4
0	011b	Fcpu/16	0.512	2
0	100b	Fcpu/8	0.256	1
0	101b	Fcpu/4	0.128	0.5
0	110b	Fcpu/2	0.064	0.25
0	111b	Fcpu/1	0.032	0.125
1	useless	Fhosc	0.016	0.0625



### 8.3.3 TC0M MODE REGISTER

TC0M is TC0 timer mode control register to configure TC0 operating mode including TC0 pre-scaler, clock source, PWM function... These configurations must be setup completely before enabling TC0 timer.

0DAH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC0M</b>	TC0ENB	TC0rate2	TC0rate1	TC0rate0	TC0CKS1	TC0CKS0	-	PWM0OUT
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	-	R/W
After reset	0	0	0	0	0	0	-	0

- Bit 0     **PWM0OUT**: PWM output control bit.  
0 = Disable PWM output function, and P5.4 is GPIO mode.  
1 = Enable PWM output function, and P5.4 outputs PWM signal.
- Bit 2     **TC0CKS0**: TC0 clock source select bit.  
0 = Fcpu.  
1 = Fhosc. **TC0rate[2:0] bits are useless.**
- Bit 3     **TC0CKS1**: TC0 clock source select bit.  
0 = Internal clock (Fcpu and Fhosc controlled by TC0CKS0 bit).  
1 = External input pin (P0.0/INT0) and enable event counter function. **TC0rate[2:0] bits are useless.**
- Bit [6:4]     **TC0RATE[2:0]**: TC0 timer clock source select bits.  
000 = Fcpu/128, 001 = Fcpu/64, 010 = Fcpu/32, 011 = Fcpu/16, 100 = Fcpu/8, 101 = Fcpu/4, 110 = Fcpu/2, 111 = Fcpu/1.
- Bit 7     **TC0ENB**: TC0 counter control bit.  
0 = Disable TC0 timer.  
1 = Enable TC0 timer.

### 8.3.4 TC0C COUNTING REGISTER

TC0C is TC0 8-bit counter. When TC0C overflow occurs, the TC0IRQ flag is set as "1" and cleared by program. The TC0C decides TC0 interval time through below equation to calculate a correct value. It is necessary to write the correct value to TC0C register and TC0R register first time, and then enable TC0 timer to make sure the first cycle correct. After one TC0 overflow occurs, the TC0C register is loaded a correct value from TC0R register automatically, not program.

0DBH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC0C</b>	TC0C7	TC0C6	TC0C5	TC0C4	TC0C3	TC0C2	TC0C1	TC0C0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

The equation of TC0C initial value is as following.

$$TC0C \text{ initial value} = 256 - (TC0 \text{ interrupt interval time} * TC0 \text{ clock rate})$$

### 8.3.5 TC0R AUTO-RELOAD REGISTER

TC0 timer builds in auto-reload function, and TC0R register stores reload data. When TC0C overflow occurs, TC0C register is loaded data from TC0R register automatically. Under TC0 timer counting status, to modify TC0 interval time is to modify TC0R register, not TC0C register. New TC0C data of TC0 interval time will be updated after TC0 timer overflow occurrence, TC0R loads new value to TC0C register. But at the first time to setup TC0M, TC0C and TC0R must be set the same value before enabling TC0 timer. TC0 is double buffer design. If new TC0R value is set by program, the new value is stored in 1<sup>st</sup> buffer. Until TC0 overflow occurs, the new value moves to real TC0R buffer. This way can avoid any transitional condition to effect the correctness of TC0 interval time and PWM output signal.

0CDH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC0R</b>	TC0R7	TC0R6	TC0R5	TC0R4	TC0R3	TC0R2	TC0R1	TC0R0
Read/Write	W	W	W	W	W	W	W	W
After reset	0	0	0	0	0	0	0	0

The equation of TC0R initial value is as following.

$$TC0R \text{ initial value} = 256 - (TC0 \text{ interrupt interval time} * TC0 \text{ clock rate})$$

☞ **Example: To calculation TC0C and TC0R value to obtain 10ms TC0 interval time. TC0 clock source is Fcpu = 16MHz/16 = 1MHz. Select TC0RATE=000 (Fcpu/128).**

TC0 interval time = 10ms. TC0 clock rate = 16MHz/16/128

$$\begin{aligned}
 TC0C/TC0R \text{ initial value} &= 256 - (TC0 \text{ interval time} * \text{input clock}) \\
 &= 256 - (10\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= 256 - (10^{-2} * 16 * 10^6 / 16 / 128) \\
 &= B2H
 \end{aligned}$$

### 8.3.6 TC0D PWM DUTY REGISTER

TC0D register's purpose is to decide PWM duty. In PWM mode, TC0R controls PWM's cycle, and TC0D controls the duty of PWM. The operation is base on timer counter value. When TC0C = TC0D, the PWM high duty finished and exchange to low level. It is easy to configure TC0D to choose the right PWM's duty for application.

0E8H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC0D</b>	TC0D7	TC0D6	TC0D5	TC0D4	TC0D3	TC0D2	TC0D1	TC0D0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After Reset	0	0	0	0	0	0	0	0

The equation of TC0D initial value is as following.

$$TC0D \text{ initial value} = TC0R + (PWM \text{ high pulse width period} / TC0 \text{ clock rate})$$

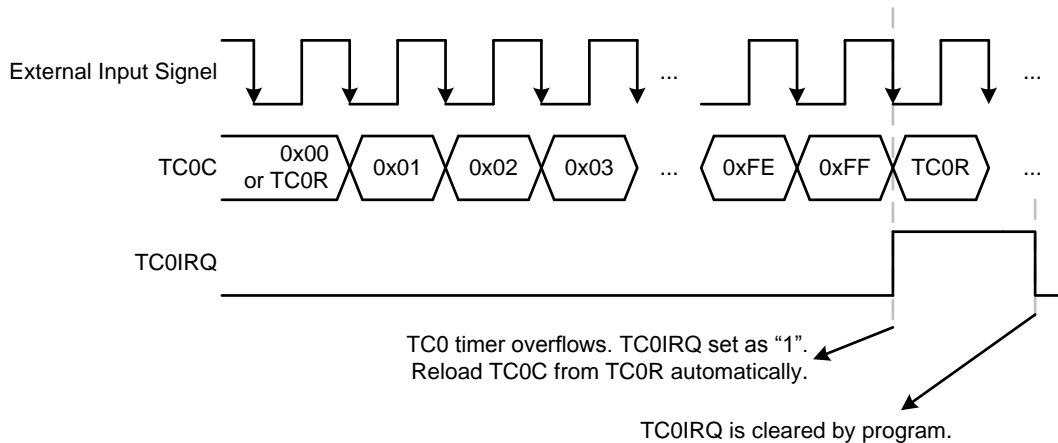
☞ **Example: To calculate TC0D value to obtain 1/3 duty PWM signal. The TC0 clock source is Fcpu = 16MHz/16 = 1MHz. Select TC0RATE=000 (Fcpu/128).**

TC0R = B2H. TC0 interval time = 10ms. So the PWM cycle is 100Hz. In 1/3 duty condition, the high pulse width is about 3.33ms.

$$\begin{aligned}
 TC0D \text{ initial value} &= B2H + (PWM \text{ high pulse width period} / TC0 \text{ clock rate}) \\
 &= B2H + (3.33\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= B2H + 1AH \\
 &= CCH
 \end{aligned}$$

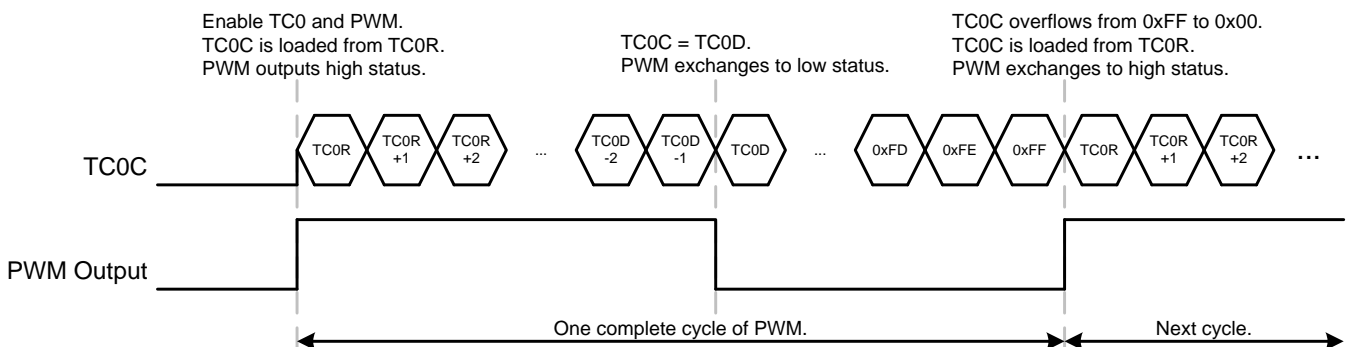
### 8.3.7 TC0 EVENT COUNTER

TC0 event counter is set the TC0 clock source from external input pin (P0.0). When TC0CKS1=1, TC0 clock source is switch to external input pin (P0.0). TC0 event counter trigger direction is falling edge. When one falling edge occurs, TC0C will up one count. When TC0C counts from 0xFF to 0x00, TC0 triggers overflow event. The external event counter input pin's wake-up function of GPIO mode is disabled when TC0 event counter function enabled to avoid event counter signal trigger system wake-up and not keep in power saving mode. The external event counter input pin's external interrupt function is also disabled when TC0 event counter function enabled, and the P00IRQ bit keeps "0" status. The event counter usually is used to measure external continuous signal rate, e.g. continuous pulse, R/C type oscillating signal...These signal phase don't synchronize with MCU's main clock. Use TC0 event to measure it and calculate the signal rate in program for different applications.

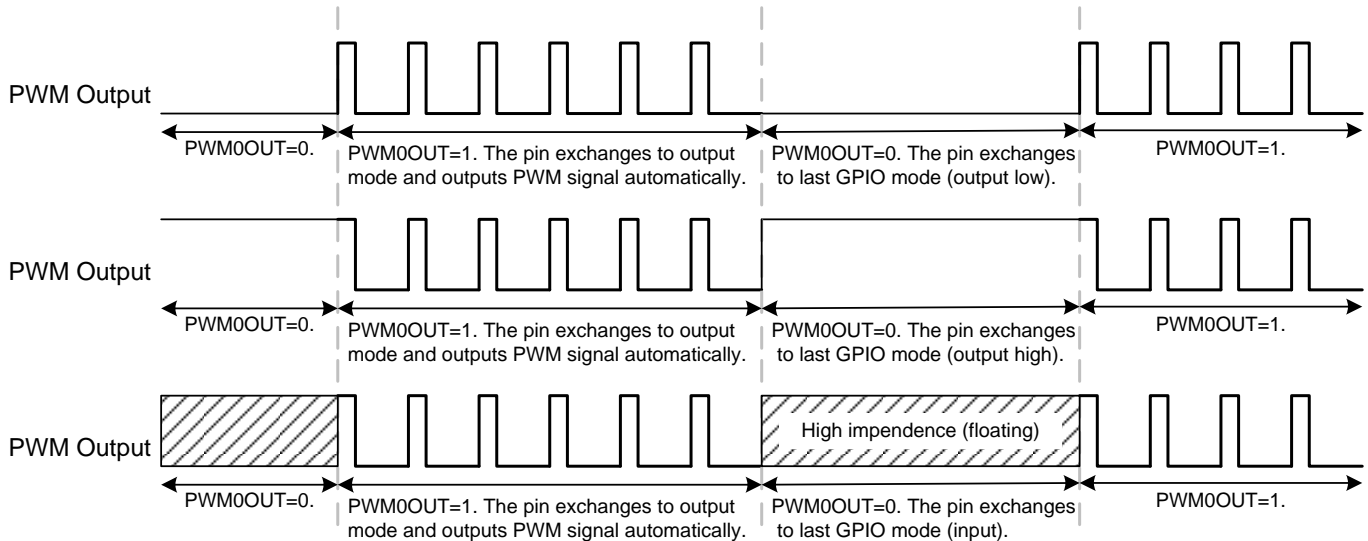


### 8.3.8 PULSE WIDTH MODULATION (PWM)

The PWM is duty/cycle programmable design to offer various PWM signals. When TC0 timer enables and PWM0OUT bit sets as "1" (enable PWM output), the PWM output pin (P5.4) outputs PWM signal. One cycle of PWM signal is high pulse first, and then low pulse outputs. TC0R register controls the cycle of PWM, and TC0D decides the duty (high pulse width length) of PWM. TC0C initial value is TC0R reloaded when TC0 timer enables and TC0 timer overflows. When TC0C count is equal to TC0D, the PWM high pulse finishes and exchanges to low level. When TC0 overflows (TC0C counts from 0xFF to 0x00), one complete PWM cycle finishes. The PWM exchanges to high level for next cycle. The PWM is auto-reload design to load TC0C from TC0R automatically when TC0 overflows and the end of PWM's cycle, to keeps PWM continuity. If modify the PWM cycle by program as PWM outputting, the new cycle occurs at next cycle when TC0C loaded from TC0R.



The resolution of PWM is decided by TC0R. TC0R range is from 0x00~0xFF. If TC0R = 0x00, PWM's resolution is 1/256. If TC0R = 0x80, PWM's resolution is 1/128. TC0D controls the high pulse width of PWM for PWM's duty. When TC0C = TC0D, PWM output exchanges to low status. TC0D must be greater than TC0R, or the PWM signal keeps low status. When PWM outputs, TC0IRQ still actives as TC0 overflows, and TC0 interrupt function actives as TC0IEN = 1. But strongly recommend be careful to use PWM and TC0 timer together, and make sure both functions work well. The PWM output pin is shared with GPIO and switch to output PWM signal as PWM0OUT=1 automatically. If PWM0OUT bit is cleared to disable PWM, the output pin exchanges to last GPIO mode automatically. It easily to implement carry signal on/off operation, not to control TC0ENB bit.



### 8.3.9 TC0 TIMER OPERATION EXPLAME

#### ● TC0 TIMER CONFIGURATION:

; Reset TC0 timer.

```
CLR          TC0M          ; Clear TC0M register.
```

; Set TC0 clock source and TC0 rate.

```
MOV          A, #0nnn0n00b
B0MOV        TC0M, A
```

; Set TC0C and TC0R register for TC0 Interval time.

```
MOV          A, #value          ; TC0C must be equal to TC0R.
B0MOV        TC0C, A
B0MOV        TC0R, A
```

; Clear TC0IRQ

```
B0BCLR       FTC0IRQ
```

; Enable TC0 timer and interrupt function.

```
B0BSET       FTC0IEN          ; Enable TC0 interrupt function.
B0BSET       FTC0ENB          ; Enable TC0 timer.
```

### ● TC0 EVENT COUNTER CONFIGURATION:

```

; Reset TC0 timer.
CLR          TC0M          ; Clear TC0M register.

; Enable TC0 event counter.
B0BSET      FTC0CKS1      ; Set TC0 clock source from external input pin (P0.0).

; Set TC0C and TC0R register for TC0 Interval time.
MOV         A, #value      ; TC0C must be equal to TC0R.
B0MOV      TC0C, A
B0MOV      TC0R, A

; Clear TC0IRQ
B0BCLR      FTC0IRQ

; Enable TC0 timer and interrupt function.
B0BSET      FTC0IEN      ; Enable TC0 interrupt function.
B0BSET      FTC0ENB      ; Enable TC0 timer.

```

### ● TC0 PWM CONFIGURATION:

```

; Reset TC0 timer.
CLR          TC0M          ; Clear TC0M register.

; Set TC0 clock source and TC0 rate.
MOV         A, #0nnn0n00b
B0MOV      TC0M, A

; Set TC0C and TC0R register for PWM cycle.
MOV         A, #value1     ; TC0C must be equal to TC0R.
B0MOV      TC0C, A
B0MOV      TC0R, A

; Set TC0D register for PWM duty.
MOV         A, #value2     ; TC0D must be greater than TC0R.
B0MOV      TC0D, A

; Enable PWM and TC0 timer.
B0BSET      FTC0ENB      ; Enable TC0 timer.
B0BSET      FPWM0OUT     ; Enable PWM.

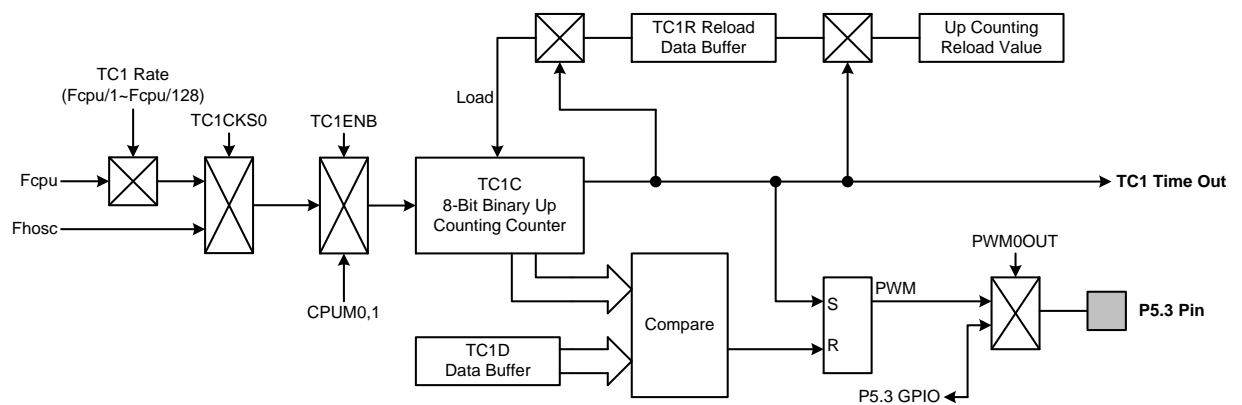
```

## 8.4 TC1 8-BIT TIMER

### 8.4.1 OVERVIEW

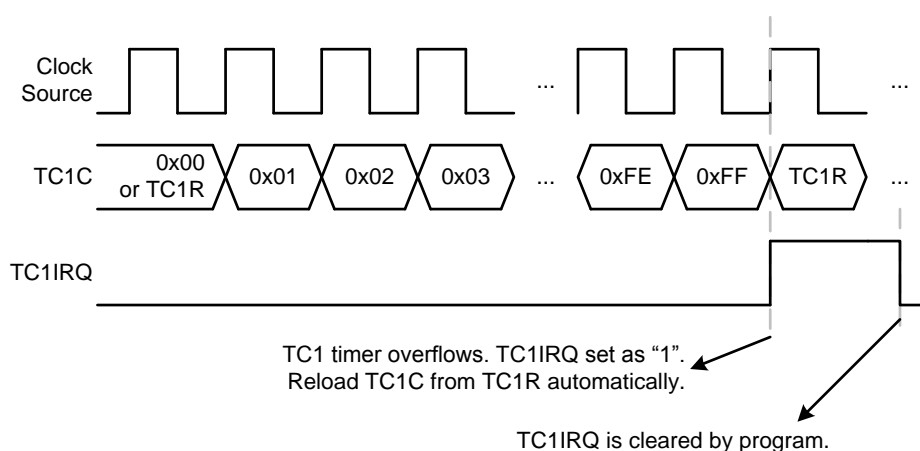
The TC1 timer is an 8-bit binary up timer with basic timer and PWM functions. The basic timer function supports flag indicator (TC1IRQ bit) and interrupt operation (interrupt vector). The interval time is programmable through TC1M, TC1C, TC1R registers. TC1 builds in duty/cycle programmable PWM. The PWM cycle and resolution are controlled by TC1 timer clock rate, TC1R and TC1D registers, so the PWM with good flexibility to implement IR carry signal, motor control and brightness adjuster...The main purposes of the TC1 timer are as following.

- ☞ **8-bit programmable up counting timer:** Generate time-out at specific time intervals based on the selected clock frequency.
- ☞ **Interrupt function:** TC1 timer function supports interrupt function. When TC1 timer occurs overflow, the TC1IRQ activates and the system points program counter to interrupt vector to do interrupt sequence.
- ☞ **Duty/cycle programmable PWM:** The PWM is duty/cycle programmable controlled by TC1R and TC1D registers.
- ☞ **Green mode function:** All TC1 functions (timer, PWM, auto-reload) keep running in green mode and no wake-up function.



## 8.4.2 TC1 TIMER OPERATION

TC1 timer is controlled by TC1ENB bit. When TC1ENB=0, TC1 timer stops. When TC1ENB=1, TC1 timer starts to count. Before enabling TC1 timer, setup TC1 timer's configurations to select timer function modes, e.g. basic timer, interrupt function...TC1C increases "1" by timer clock source. When TC1 overflow event occurs, TC1IRQ flag is set as "1" to indicate overflow and cleared by program. The overflow condition is TC1C count from full scale (0xFF) to zero scale (0x00). In difference function modes, TC1C value relates to operation. If TC1C value changing effects operation, the transition of operations would make timer function error. So TC1 builds in double buffer to avoid these situations happen. The double buffer concept is to flash TC1C during TC1 counting, to set the new value to TC1R (reload buffer), and the new value will be loaded from TC1R to TC1C after TC1 overflow occurrence automatically. In the next cycle, the TC1 timer runs under new conditions, and no any transitions occur. The auto-reload function is no any control interface and always actives as TC1 enables. If TC1 timer interrupt function is enabled (TC1IEN=1), the system will execute interrupt procedure. The interrupt procedure is system program counter points to interrupt vector (ORG 8) and executes interrupt service routine after TC1 overflow occurrence. Clear TC1IRQ by program is necessary in interrupt procedure. TC1 timer can works in normal mode, slow mode and green mode. But in green mode, TC1 keep counting, set TC1IRQ and outputs PWM, but can't wake-up system.



TC1 provides different clock sources to implement different applications and configurations. TC1 clock source includes Fcpu (instruction cycle) and Fhosc (high speed oscillator) controlled by TC1CKS0 bits. TC1CKS0 bit selects the clock source is from Fcpu or Fhosc. If TC1CKS0=0, TC1 clock source is Fcpu through TC1rate[2:0] pre-scaler to decide Fcpu/1~Fcpu/128. If TC1CKS0=1, TC1 clock source is Fhosc without any divider. TC1rate[2:0] pre-scaler is unless when TC1CKS0=1 condition. TC1 length is 8-bit (256 steps), and the one count period is each cycle of input clock.

TC1CKS0	TC1rate[2:0]	TC1 Clock	TC1 Interval Time	
			Fhosc=16MHz, Fcpu=Fhosc/2	
			max. (ms)	Unit (us)
0	000b	Fcpu/128	4.096	16
0	001b	Fcpu/64	2.048	8
0	010b	Fcpu/32	1.024	4
0	011b	Fcpu/16	0.512	2
0	100b	Fcpu/8	0.256	1
0	101b	Fcpu/4	0.128	0.5
0	110b	Fcpu/2	0.064	0.25
0	111b	Fcpu/1	0.032	0.125
1	useless	Fhosc	0.016	0.0625

### 8.4.3 TC1M MODE REGISTER

TC1M is TC1 timer mode control register to configure TC1 operating mode including TC1 pre-scaler, clock source, PWM function... These configurations must be setup completely before enabling TC1 timer.

0DDH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC1M</b>	TC1ENB	TC1rate2	TC1rate1	TC1rate0	-	TC1CKS0	-	PWM1OUT
Read/Write	R/W	R/W	R/W	R/W	-	R/W	-	R/W
After reset	0	0	0	0	-	0	-	0

Bit 0 **PWM1OUT**: PWM output control bit.  
0 = Disable PWM output function, and P5.3 is GPIO mode.  
1 = Enable PWM output function, and P5.3 outputs PWM signal.

Bit 2 **TC1CKS0**: TC1 clock source select bit.  
0 = Fcpu.  
1 = Fhosc. **TC1rate[2:0] bits are useless.**

Bit [6:4] **TC1RATE[2:0]**: TC1 timer clock source select bits.  
000 = Fcpu/128, 001 = Fcpu/64, 010 = Fcpu/32, 011 = Fcpu/16, 100 = Fcpu/8, 101 = Fcpu/4, 110 = Fcpu/2, 111 = Fcpu/1.

Bit 7 **TC1ENB**: TC1 counter control bit.  
0 = Disable TC1 timer.  
1 = Enable TC1 timer.

### 8.4.4 TC1C COUNTING REGISTER

TC1C is TC1 8-bit counter. When TC1C overflow occurs, the TC1IRQ flag is set as "1" and cleared by program. The TC1C decides TC1 interval time through below equation to calculate a correct value. It is necessary to write the correct value to TC1C register and TC1R register first time, and then enable TC1 timer to make sure the first cycle correct. After one TC1 overflow occurs, the TC1C register is loaded a correct value from TC1R register automatically, not program.

0DDH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC1C</b>	TC1C7	TC1C6	TC1C5	TC1C4	TC1C3	TC1C2	TC1C1	TC1C0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

The equation of TC1C initial value is as following.

$$TC1C \text{ initial value} = 256 - (TC1 \text{ interrupt interval time} * TC1 \text{ clock rate})$$



### 8.4.5 TC1R AUTO-RELOAD REGISTER

TC1 timer builds in auto-reload function, and TC1R register stores reload data. When TC1C overflow occurs, TC1C register is loaded data from TC1R register automatically. Under TC1 timer counting status, to modify TC1 interval time is to modify TC1R register, not TC1C register. New TC1C data of TC1 interval time will be updated after TC1 timer overflow occurrence, TC1R loads new value to TC1C register. But at the first time to setup T0M, TC1C and TC1R must be set the same value before enabling TC1 timer. TC1 is double buffer design. If new TC1R value is set by program, the new value is stored in 1<sup>st</sup> buffer. Until TC1 overflow occurs, the new value moves to real TC1R buffer. This way can avoid any transitional condition to effect the correctness of TC1 interval time and PWM output signal.

0DEH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC1R</b>	TC1R7	TC1R6	TC1R5	TC1R4	TC1R3	TC1R2	TC1R1	TC1R0
Read/Write	W	W	W	W	W	W	W	W
After reset	0	0	0	0	0	0	0	0

The equation of TC1R initial value is as following.

$$TC1R \text{ initial value} = 256 - (TC1 \text{ interrupt interval time} * TC1 \text{ clock rate})$$

- **Example: To calculation TC1C and TC1R value to obtain 10ms TC1 interval time. TC1 clock source is Fcpu = 16MHz/16 = 1MHz. Select TC1RATE=000 (Fcpu/128).**  
TC1 interval time = 10ms. TC1 clock rate = 16MHz/16/128

$$\begin{aligned}
 TC1C/TC1R \text{ initial value} &= 256 - (TC1 \text{ interval time} * \text{input clock}) \\
 &= 256 - (10\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= 256 - (10^{-2} * 16 * 10^6 / 16 / 128) \\
 &= B2H
 \end{aligned}$$

### 8.4.6 TC1D PWM DUTY REGISTER

TC1D register's purpose is to decide PWM duty. In PWM mode, TC1R controls PWM's cycle, and TC1D controls the duty of PWM. The operation is base on timer counter value. When TC1C = TC1D, the PWM high duty finished and exchange to low level. It is easy to configure TC1D to choose the right PWM's duty for application.

0EAH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>TC1D</b>	TC1D7	TC1D6	TC1D5	TC1D4	TC1D3	TC1D2	TC1D1	TC1D0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After Reset	0	0	0	0	0	0	0	0

The equation of TC1D initial value is as following.

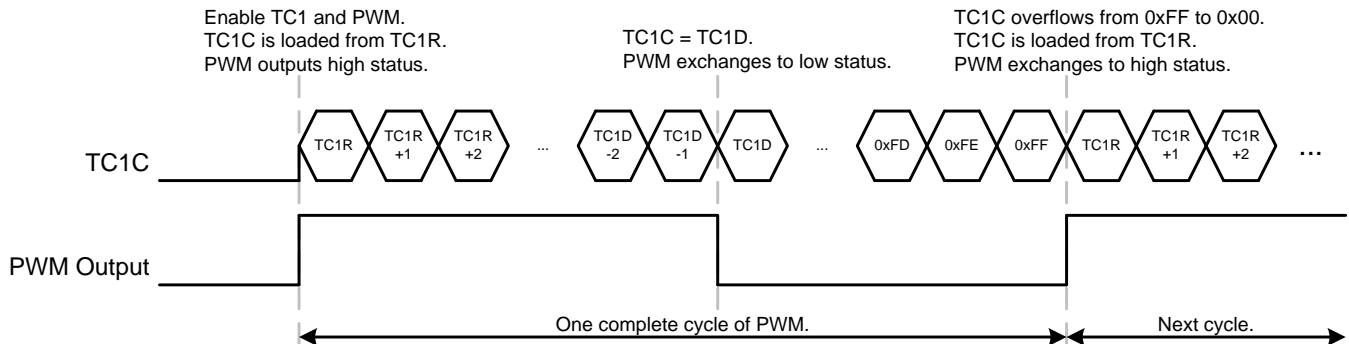
$$TC1D \text{ initial value} = TC1R + (PWM \text{ high pulse width period} / TC1 \text{ clock rate})$$

- **Example: To calculate TC1D value to obtain 1/3 duty PWM signal. The TC1 clock source is Fcpu = 16MHz/16 = 1MHz. Select TC1RATE=000 (Fcpu/128).**  
TC1R = B2H. TC1 interval time = 10ms. So the PWM cycle is 100Hz. In 1/3 duty condition, the high pulse width is about 3.33ms.

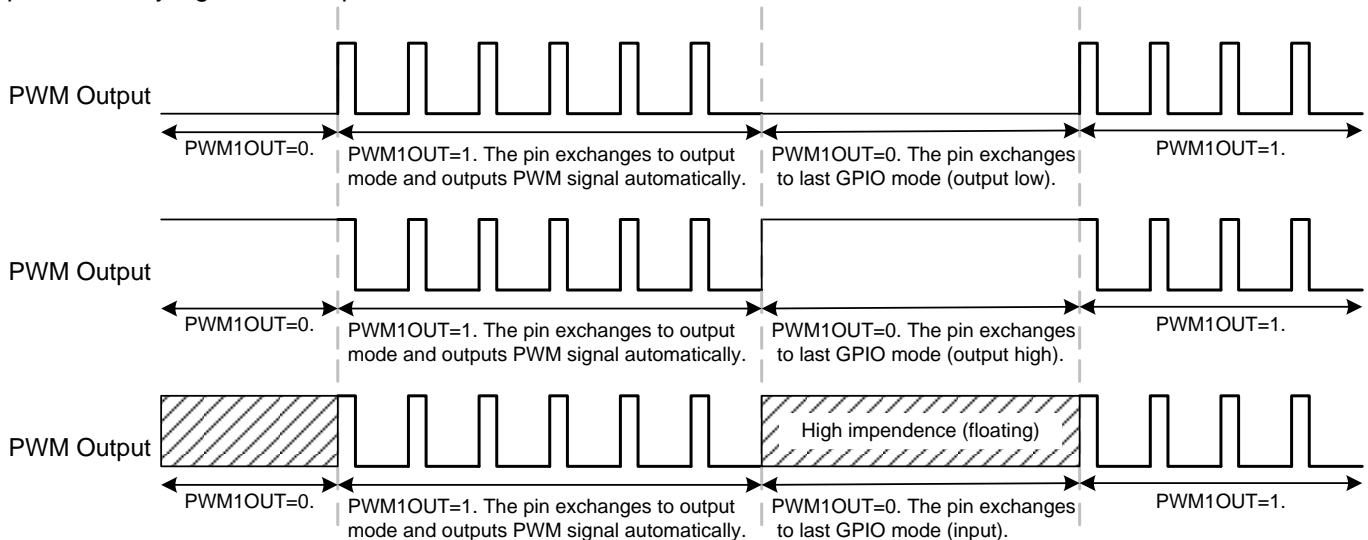
$$\begin{aligned}
 TC1D \text{ initial value} &= B2H + (PWM \text{ high pulse width period} / TC1 \text{ clock rate}) \\
 &= B2H + (3.33\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= B2H + 1AH \\
 &= CCH
 \end{aligned}$$

### 8.4.7 PULSE WIDTH MODULATION (PWM)

The PWM is duty/cycle programmable design to offer various PWM signals. When TC1 timer enables and PWM1OUT bit sets as "1" (enable PWM output), the PWM output pin (P5.3) outputs PWM signal. One cycle of PWM signal is high pulse first, and then low pulse outputs. TC1R register controls the cycle of PWM, and TC1D decides the duty (high pulse width length) of PWM. TC1C initial value is TC1R reloaded when TC1 timer enables and TC1 timer overflows. When TC1C count is equal to TC1D, the PWM high pulse finishes and exchanges to low level. When TC1 overflows (TC1C counts from 0xFF to 0x00), one complete PWM cycle finishes. The PWM exchanges to high level for next cycle. The PWM is auto-reload design to load TC1C from TC1R automatically when TC1 overflows and the end of PWM's cycle, to keeps PWM continuity. If modify the PWM cycle by program as PWM outputting, the new cycle occurs at next cycle when TC1C loaded from TC1R.



The resolution of PWM is decided by TC1R. TC1R range is from 0x00~0xFF. If TC1R = 0x00, PWM's resolution is 1/256. If TC1R = 0x80, PWM's resolution is 1/128. TC1D controls the high pulse width of PWM for PWM's duty. When TC1C = TC1D, PWM output exchanges to low status. TC1D must be greater than TC1R, or the PWM signal keeps low status. When PWM outputs, TC1IRQ still activates as TC1 overflows, and TC1 interrupt function activates as TC1IEN = 1. But strongly recommend be careful to use PWM and TC1 timer together, and make sure both functions work well. The PWM output pin is shared with GPIO and switch to output PWM signal as PWM1OUT=1 automatically. If PWM1OUT bit is cleared to disable PWM, the output pin exchanges to last GPIO mode automatically. It easily to implement carry signal on/off operation, not to control TC1ENB bit.



## 8.4.8 TC1 TIMER OPERATION EXPLAME

### ● TC1 TIMER CONFIGURATION:

```

; Reset TC1 timer.
CLR          TC1M          ; Clear TC1M register.

; Set TC1 clock source and TC1 rate.
MOV          A, #0nnn0n00b
B0MOV        TC1M, A

; Set TC1C and TC1R register for TC1 Interval time.
MOV          A, #value     ; TC1C must be equal to TC1R.
B0MOV        TC1C, A
B0MOV        TC1R, A

; Clear TC1IRQ
B0BCLR       FTC1IRQ

; Enable TC1 timer and interrupt function.
B0BSET       FTC1IEN        ; Enable TC1 interrupt function.
B0BSET       FTC1ENB        ; Enable TC1 timer.

```

### ● TC1 PWM CONFIGURATION:

```

; Reset TC1 timer.
CLR          TC1M          ; Clear TC1M register.

; Set TC1 clock source and TC1 rate.
MOV          A, #0nnn0n00b
B0MOV        TC1M, A

; Set TC1C and TC1R register for PWM cycle.
MOV          A, #value1    ; TC1C must be equal to TC1R.
B0MOV        TC1C, A
B0MOV        TC1R, A

; Set TC1D register for PWM duty.
MOV          A, #value2    ; TC1D must be greater than TC1R.
B0MOV        TC1D, A

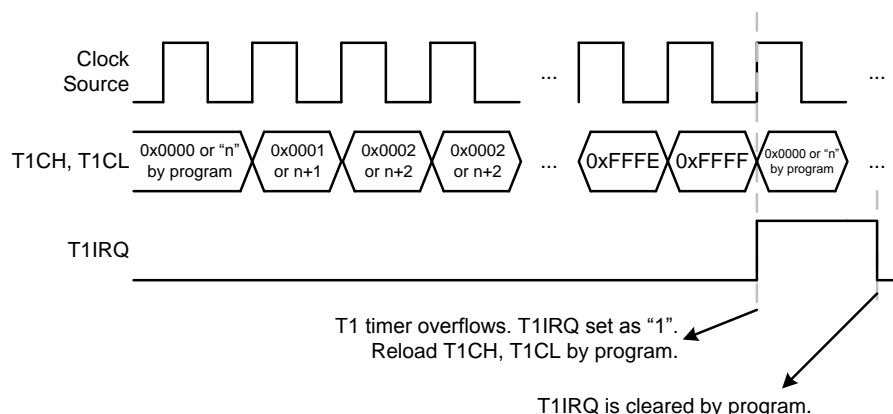
; Enable PWM and TC1 timer.
B0BSET       FTC1ENB        ; Enable TC1 timer.
B0BSET       FPWM1OUT       ; Enable PWM.

```



## 8.5.2 T1 TIMER OPERATION

T1 timer is controlled by T1ENB bit. When T1ENB=0, T1 timer stops. When T1ENB=1, T1 timer starts to count. Before enabling T1 timer, setup T1 timer's configurations to select timer function modes, e.g. basic timer, interrupt function...T1 16-bit counter (T1CH, T1CL) increases "1" by timer clock source. When T1 overflow event occurs, T1IRQ flag is set as "1" to indicate overflow and cleared by program. The overflow condition is T1CH, T1CL count from full scale (0xFFFF) to zero scale (0x0000). T1 doesn't build in double buffer, so load T1CH, T1CL by program when T1 timer overflows to fix the correct interval time. If T1 timer interrupt function is enabled (T1IEN=1), the system will execute interrupt procedure. The interrupt procedure is system program counter points to interrupt vector (ORG 8) and executes interrupt service routine after T1 overflow occurrence. Clear T1IRQ by program is necessary in interrupt procedure. T1 timer can works in normal mode, slow mode and green mode. In green mode, T1 keeps counting, set T1IRQ and wakes up system when T1 timer overflows.



T1 clock source is Fcpu (instruction cycle) through T1rate[2:0] pre-scaler to decide Fcpu/1~Fcpu/128. T1 length is 16-bit (65536 steps), and the one count period is each cycle of input clock.

T1rate[2:0]	T1 Clock	T1 Interval Time	
		Fhosc=16MHz, Fcpu=Fhosc/2	
		max. (ms)	Unit (us)
000b	Fcpu/128	1048.576	16
001b	Fcpu/64	524.288	8
010b	Fcpu/32	262.144	4
011b	Fcpu/16	131.072	2
100b	Fcpu/8	65.536	1
101b	Fcpu/4	32.768	0.5
110b	Fcpu/2	16.384	0.25
111b	Fcpu/1	8.192	0.125

### 8.5.3 T1M MODE REGISTER

T1M is T1 timer mode control register to configure T1 operating mode including T1 pre-scaler, clock source, capture parameters...These configurations must be setup completely before enabling T1 timer.

0A0H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1M</b>	T1ENB	T1rate2	T1rate1	T1rate0	CPTCKS	CPTStart	CPTG1	CPTG0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

- Bit [1:0] **CPTG[1:0]**: T1 capture timer function control bit.  
 00 = Disable capture timer function.  
 01 = High pulse width measurement.  
 10 = Low pulse width measurement  
 11 = Cycle measurement.
- Bit 2 **CPTStart**: T1 capture timer operating control bit.  
 0 = Process end.  
 1 = Start to count and processing.
- Bit 3 **CPTCKS**: T1 capture timer input source select bit.  
 0 = External input pin (P0.0/INT0) and enable capture timer function.  
 1 = Comparator output terminal and enable capture timer function.
- Bit [6:4] **T1RATE[2:0]**: T1 timer clock source select bits.  
 000 = Fcpu/128, 001 = Fcpu/64, 010 = Fcpu/32, 011 = Fcpu/16, 100 = Fcpu/8, 101 = Fcpu/4, 110 = Fcpu/2, 111 = Fcpu/1.
- Bit 7 **T1ENB**: T1 counter control bit.  
 0 = Disable T1 timer.  
 1 = Enable T1 timer.

### 8.5.4 T1CH, T1CL 16-bit COUNTING REGISTERS

T1 counter is 16-bit counter combined with T1CH and T1CL registers. When T1 timer overflow occurs, the T1IRQ flag is set as "1" and cleared by program. The T1CH, T1CL decide T1 interval time through below equation to calculate a correct value. It is necessary to write the correct value to T1CH and T1CL registers, and then enable T1 timer to make sure the first cycle correct. After one T1 overflow occurs, the T1CH and T1CL registers are loaded correct values by program.

0A1H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1CL</b>	T1CL7	T1CL6	T1CL5	T1CL4	T1CL3	T1CL2	T1CL1	T1CL0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

0A2H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1CH</b>	T1CH7	T1CH6	T1CH5	T1CH4	T1CH3	T1CH2	T1CH1	T1CH0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After Reset	0	0	0	0	0	0	0	0

The T1 timer counter length is 16-bit and points to T1CH and T1CL registers. The timer counter is double buffer design. The core bus is 8-bit, so access 16-bit data needs a latch flag to avoid the transient status affect the 16-bit data mistake occurrence. Under write mode, the write T1CL is the latch control flag. Under read mode, the read T1CL is the latch control flag. So, write T1 16-bit counter is to write T1CH first, and then write T1CL. The 16-bit data is written to 16-bit counter buffer after executing writing T1CL. Read T1 16-bit counter is to read T1CL first, and then read T1CH. The 16-bit data is dumped to T1CH, T1CL after executing reading T1CL.

- **Read T1 counter buffer sequence is to read T1CL first, and then read T1CH.**
- **Write T1 counter buffer sequence is to write T1CH first, and then write T1CL.**

The equation of T1 16-bit counter (T1CH, T1CL) initial value is as following.

$$T1CH, T1CL \text{ initial value} = 65536 - (T1 \text{ interrupt interval time} * T1 \text{ clock rate})$$

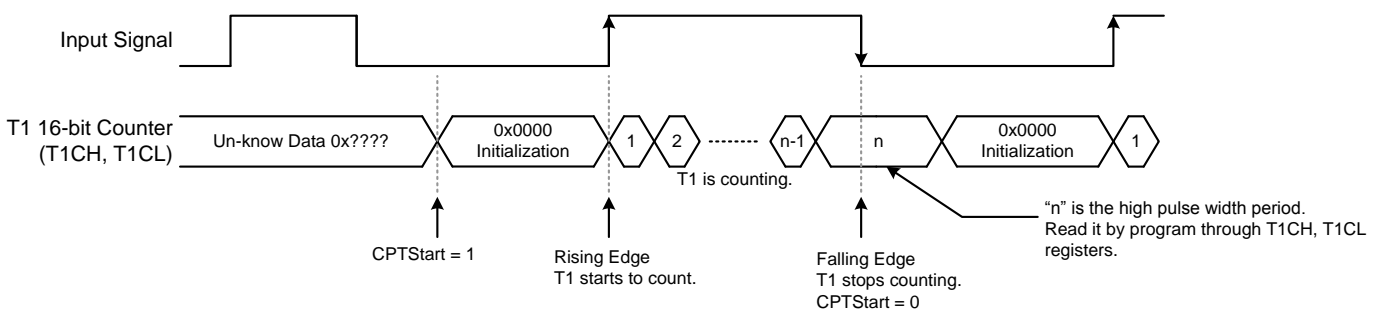
- **Example: To calculation T1CH and T1CL values to obtain 500ms T1 interval time. T1 clock source is Fcpu = 16MHz/16 = 1MHz. Select T1RATE=000 (Fcpu/128).**  
T1 interval time = 500ms. T1 clock rate = 16MHz/16/128

$$\begin{aligned}
 T1 \text{ 16-bit counter initial value} &= 65536 - (T1 \text{ interval time} * \text{input clock}) \\
 &= 65536 - (500\text{ms} * 16\text{MHz} / 16 / 128) \\
 &= 65536 - (500 * 10^{-3} * 16 * 10^6 / 16 / 128) \\
 &= F0BDH \text{ (T1CH = F0H, T1CL = BDH)}
 \end{aligned}$$

### 8.5.5 T1 CPATURE TIMER

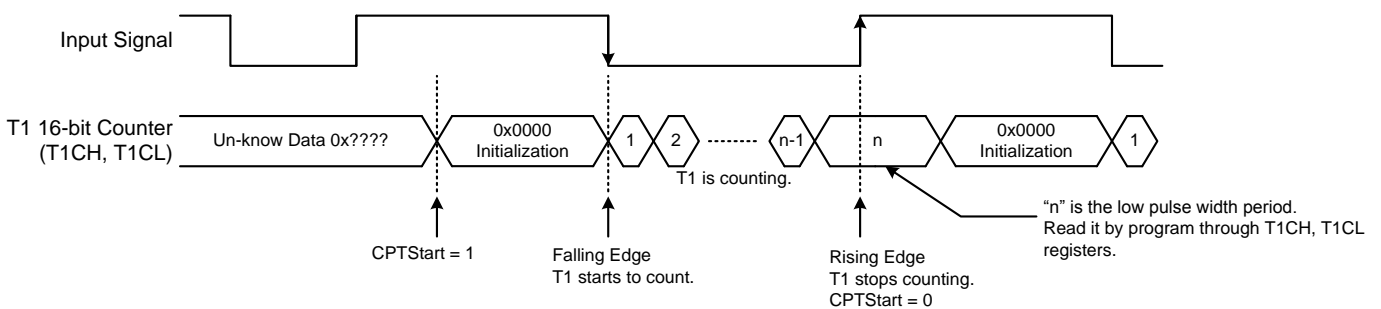
The 16-bit capture timer purpose is to measure input signal pulse width and cycle. The measurement is through T1 timer by trigger selection. The concept is using T1 to measure input signal like a meter. When trigger condition exists, the T1 timer starts and stops following signal condition. The capture timer is controlled by CPTG[1:0] bits. When CPTG[1:0] = 00, the capture timer is disabled. When CPTG[1:0] = 01/10/11, the capture timer is enabled, but the T1ENB must be enabled first. The capture timer can measure input high pulse width, input low pulse width and the cycle of input signal controlled by CPTG[1:0]. CPTG[1:0] = 01, measure input high pulse width. CPTG[1:0] = 10, measure input low pulse width. CPTG[1:0] = 11, measure the cycle of input signal. The CPTG[1:0] only selects the capture timer function, not execute the capture timer. CPTStart bit is capture timer execution control bit. When CPTStart is set as "1", the capture timer waits the right trigger edge to active 16-bit counter. If the trigger edge finds, the T1 16-bit counter starts to count which clock source is T1. When the second right edge finds, the 16-counter stops, CPTStart is cleared and the T1IRQ activates. Before setting CPTStart bit, the T1 16-bit counter is cleared for capture timer initialization automatically.

- **High Pulse Width Measurement (T1ENB = 1. CPTG[1:0] = 01.)**



The high pulse width measurement is using rising edge to trigger T1 timer counting and falling edge to stop T1 timer. If set CPTStart bit at high pulse duration, the capture timer will measure next high pulse until the rising edge occurrence. When the falling edge occurs and T1 timer stops, the T1CH, T1CL 16-bit counter is the period of high pulse width.

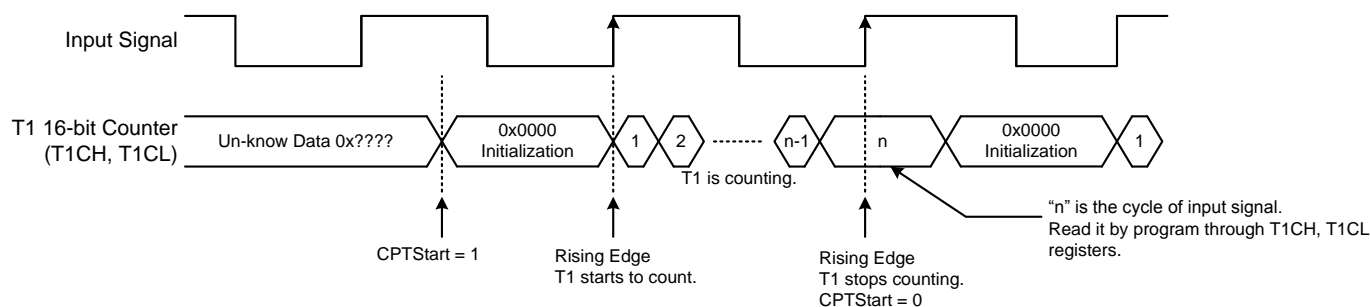
- **Low Pulse Width Measurement (T1ENB = 1. CPTG[1:0] = 10.)**



The low pulse width measurement is using falling edge to start T1 timer counting and rising edge to stop T1 timer. If set CPTStart bit at low pulse duration, the capture timer will measure next low pulse until the falling edge occurrence. When the rising edge occurs and T1 timer stops, the T1CH, T1CL 16-bit counter is the period of low pulse width.



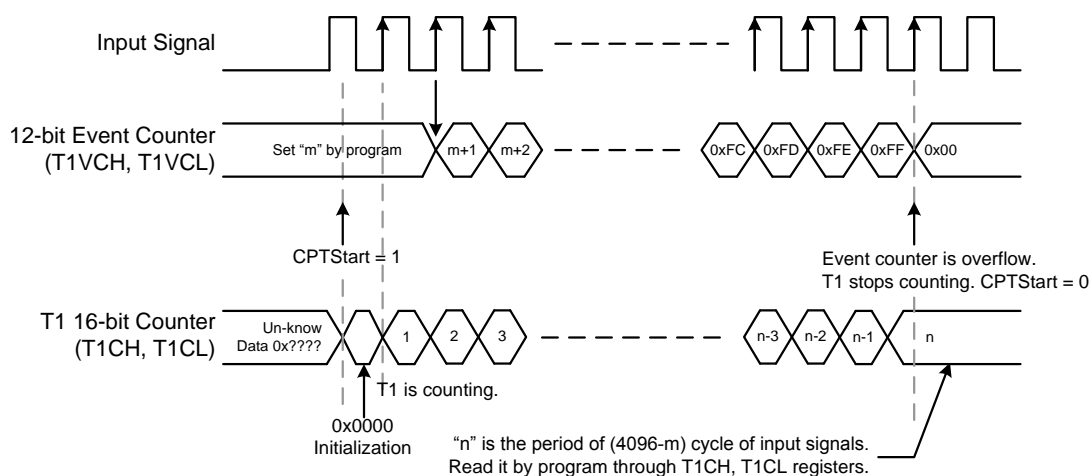
● **Input Cycle Measurement (T1ENB = 1. CPTG[1:0] = 11.)**



The cycle measurement is using rising edge to start and stop T1 timer. If set CPTStart bit at high or low pulse duration, the capture timer will measure next cycle until the rising edge occurrence. When the rising edge occurs and T1 timer stops, the T1CH, T1CL 16-bit counter is the period of low pulse width.

### 8.5.6 T1 12-BIT EVENT COUNTER

The 12-bit event counter is the extra function for continuous signal measurement through T1 capture timer function. The concept is input a number of input signal clock to 12-bit event counter which decide the number, and then set start bit to enable capture timer function. When the trigger edge is found, the T1 timer starts to count until the event counter overflows. The purpose is to measure the period of a continuous oscillating signal. Use 12-bit T1VC counter buffer (T1VCH, T1VCL) to setup the sampling number. Set CPTSatrt bit, the oscillating signal inputs into 12-bit event counter through event detector. The event counter trigger edge is the rising edge of input signal. The event counter function only supports T1 capture timer mode.



0A5H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1CKM</b>	CPTVC	-	-	-	-	-	-	-
Read/Write	R/W	-	-	-	-	-	-	-
After Reset	0	-	-	-	-	-	-	-

Bit 7 **CPTVC**: T1 12-bit event counter control bit.  
 0 = Disable.  
 1 = Enable and the T1 capture timer must be enabled.

0A3H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1VCL</b>	T1VC7	T1VC6	T1VC5	T1VC4	T1VC3	T1VC2	T1VC1	T1VC0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After Reset	0	0	0	0	0	0	0	0

0A4H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>T1VCH</b>	-	-	-	-	T1VC11	T1VC10	T1VC9	T1VC8
Read/Write	-	-	-	-	R/W	R/W	R/W	R/W
After Reset	-	-	-	-	0	0	0	0

The T1 event counter length is 12-bit and points to T1VCH and T1VCL registers. To access 12-bit data needs a latch flag to avoid the transient status affect the 12-bit data mistake is occurrence. Under write mode, the write T1VCL is the latch control flag. Under read mode, the read T1VCL is the latch control flag. So, write T1 12-bit event counter is to write T1VCH first, and then write T1VCL. The 12-bit data is written to 12-bit counter buffer after executing writing T1VCL. Read T1 12-bit event counter is to read T1VCL first, and then read T1VCH. The 12-bit data is dumped to T1VCH, T1VCL after executing reading T1VCL.

- Read T1 12-bit event counter buffer sequence is to read T1VCL first, and then read T1VCH.
- Write T1 12-bit event counter buffer sequence is to write T1VCH first, and then write T1VCL.

The equation of T1 12-bit counter (T1VCH, T1VCL) initial value is as following.

$$T1VCH, T1VCL \text{ initial value} = 4096 - (\text{The number of sampled input signal})$$

➤ **Example: To calculation T1VCH and T1VCL values to obtain 1000 clocks of input signal.**

$$\begin{aligned}
 T1 \text{ 12-bit event counter initial value} &= 4096 - 1000 \\
 &= 3096 \\
 &= C18H \text{ (T1VCH = 0CH, T1VCL = 18H)}
 \end{aligned}$$

## 8.5.7 T1 TIMER OPERATION EXPLAME

### ● T1 TIMER CONFIGURATION:

; Reset T1 timer.

```
CLR          T1M          ; Clear T1M register.
```

; Set T1 clock rate.

```
MOV          A, #0nnn0000b
BO MOV       T1M, A
```

; Set T1CH, T1CL registers for T1 Interval time.

```
MOV          A, #value1    ; Set high byte first.
BO MOV       T1CH, A
MOV          A, #value2    ; Set low byte.
BO MOV       T1CL, A
```

; Clear T1IRQ

```
BO BCLR      FT1IRQ
```

; Enable T1 timer and interrupt function.

```
BO BSET      FT1IEN        ; Enable T1 interrupt function.
BO BSET      FT1ENB        ; Enable T1 timer.
```

### ● T1 CAPTURE TIMER FOR SINGLE CYCLE MEASUREMENT CONFIGURATION:

; Reset T1 timer.

```
CLR          T1M          ; Clear T1M register.
```

; Set T1 clock rate, select input source, and select/enable T1 capture timer.

```
MOV          A, #0nnn00mmb ; "nnn" is T1rate[2:0] for T1 clock rate selection.
BO MOV       T1M, A         ; "mm" is CPTG[1:0] for T1 capture timer selection.
                        ; CPTG[1:0] = 00b, disable T1 capture timer.
                        ; CPTG[1:0] = 01b, high pulse width measurement.
                        ; CPTG[1:0] = 10b, low pulse width measurement.
                        ; CPTG[1:0] = 11b, cycle measurement.
```

; Select T1 capture source.

```
BO BCLR      FCPTCKS       ; Capture source is P0.0.
```

; or

```
BO BSET      FCPTCKS       ; Capture source is comparator output.
```

; Clear T1CH, T1CL.

```
CLR          T1CH          ; Clear high byte first.
CLR          T1CL          ; Clear low byte.
```

; Clear T1IRQ

```
BO BCLR      FT1IRQ
```

; Enable T1 timer and interrupt function.

```
BO BSET      FT1IEN        ; Enable T1 interrupt function.
BO BSET      FT1ENB        ; Enable T1 timer.
```

; Set capture timer start bit.

```
BO BSET      FCPTStart
```

● **T1 EVENT COUNTER FOR COUNTINIOUS SIGNAL MEASUREMENT CONFIGURATION:**

**; Reset T1 timer.**

```
CLR          T1M          ; Clear T1M register.
```

**; Set T1 clock rate and select/enable T1 event counter.**

```
MOV          A, #0nnn00mmB ; "nnn" is T1rate[2:0] for T1 clock rate selection.
BO MOV       T1M, A         ; "mm" is CPTG[1:0] for T1 capture timer selection.
                                ; CPTG[1:0] = 00b, disable T1 capture timer.
                                ; CPTG[1:0] = 01b/10b/11b, enable event counter trigger.
```

**; Select T1 event counter source.**

```
B0BCLR       FCPTCKS      ; Event counter source is P0.0.
```

**; or**

```
B0BSET       FCPTCKS      ; Event counter source is comparator output.
```

**; Clear T1CH, T1CL.**

```
CLR          T1CH          ; Clear high byte first.
CLR          T1CL          ; Clear low byte.
```

**; Set T1VCH, T1VCL 12-bit event counter for the number of event counter measurement.**

```
MOV          A, #value1    ; Set high nibble first.
BO MOV       T1VCH, A
MOV          A, #value2    ; Set low byte.
BO MOV       T1VCL, A
```

**; Clear T1IRQ**

```
B0BCLR       FT1IRQ
```

**; Enable T1 timer, interrupt function and T1 event counter function.**

```
B0BSET       FT1IEN        ; Enable T1 interrupt function.
B0BSET       FT1ENB        ; Enable T1 timer.
B0BSET       FCPTVC        ; Enable T1 event counter function.
```

**; Set event counter start bit.**

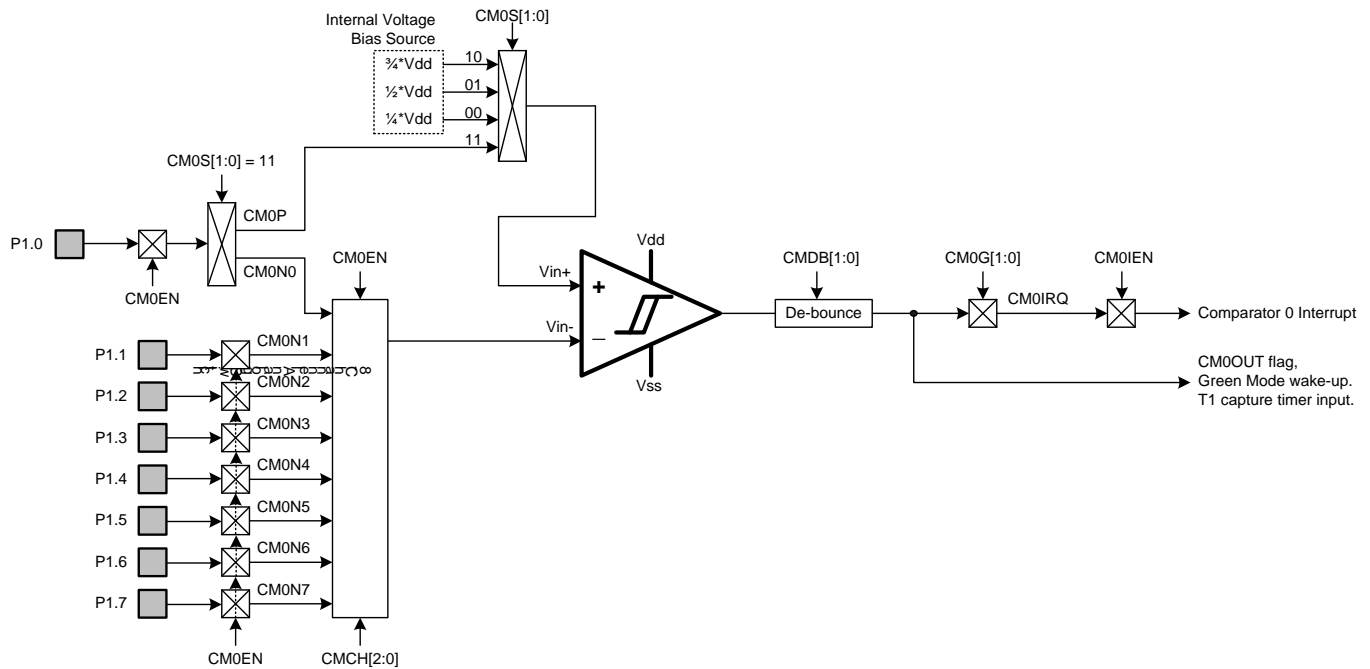
```
B0BSET       FCPTStart
```

# 9 8-CHANNEL ANALOG COMPARATOR

## 9.1 OVERVIEW

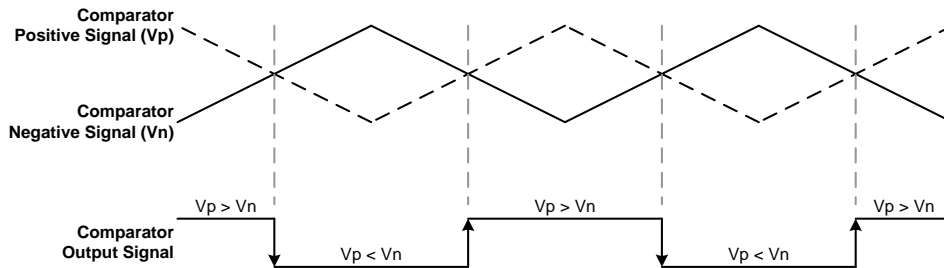
The analog comparator compares negative input voltage and positive input voltage, and then output the result to comparator output terminal. The comparator has multi-input selection for different applications. The comparator negative input terminal is up to 8-channel controlled by CMCH[2:0]. The comparator positive input terminal has four selections controlled by CM0S[1:0] bits. The comparator output terminal doesn't connect to external pin and connects to internal path. There is a programmable direction function to decide comparator trigger edge for indicator function. The comparator has flag indicator, interrupt function and green mode weak-up function for different application.

- 8-channel negative input selection.
- 1 external positive input pin.
- Programmable internal reference voltage connected to comparator's positive terminal.
- Programmable trigger direction.
- Interrupt function.
- Green mode wake-up function.



## 9.2 COMPARATOR OPERATION

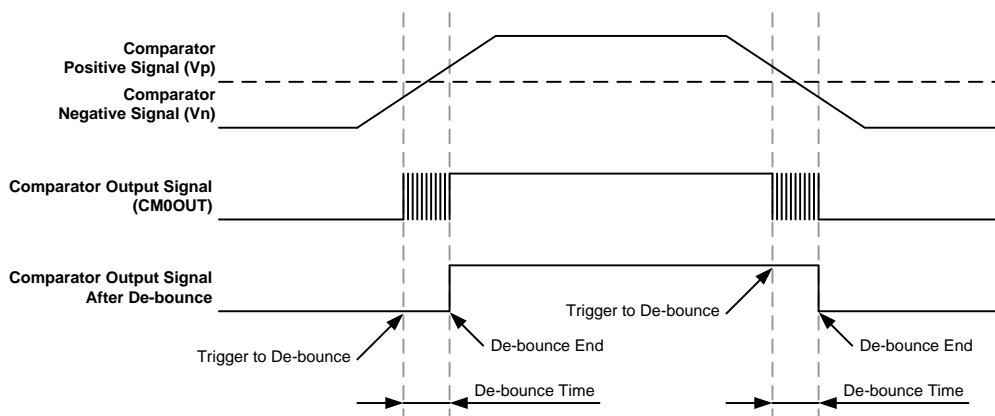
The comparator operation is to compare the voltage between comparator positive input and negative input terminals. When the positive input voltage is greater than the negative input voltage, the comparator output is high status. When the positive input voltage is smaller than the negative input voltage, the comparator output is low status.



The comparator builds in interrupt function. The interrupt function trigger edge is selected by CM0G[1:0]. The trigger edge supports rising edge (CM0G[1:0]=01b), falling edge (CM0G[1:0]=10b) and bi-direction level change (CM0G[1:0]=11b). If the trigger edge condition is found, the CM0IRQ is set as "1". If the comparator interrupt function enables, the system will execute interrupt routine. The CM0IRQ must be cleared by program.

The comparator builds in green mode wake-up function. The comparator green mode wake-up trigger edge is bi-direction. The comparator's wake-up function only supports green mode, not power down mode. If the trigger edge condition (comparator output status exchanging) is found, the system will be wake-up from green mode. If the trigger edge direction is interrupt trigger condition, the CM0IRQ is set as "1". Of course the interrupt routine is executed if the interrupt function enabled. When the wake-up trigger edge direction is equal to interrupt trigger condition, the system will execute interrupt operation after green mode wake-up immediately.

The critical condition is comparator positive voltage equal to comparator negative voltage, and the voltage range is decided comparator offset parameter of input common mode. In the voltage range, the comparator output signal is unstable and keeps oscillating until the differential voltage exits the range. In the condition, the comparator flag (CM0IRQ) latches the first exchanging and issue the status, but the status is a transient, not a stable condition. So the comparator builds in a filter to de-bounce the transient condition. The comparator output signal is through a de-bounce circuit to filter comparator transient status. The de-bounce time is controlled by CMDDB[1:0] bits that means the comparator minimum response time is zero, 1\*Fcpu, 2\*Fcpu or 3\*Fcpu. The de-bounce time depends on the signal slew rate and selected by program.

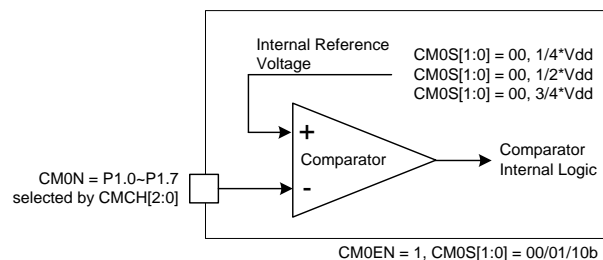
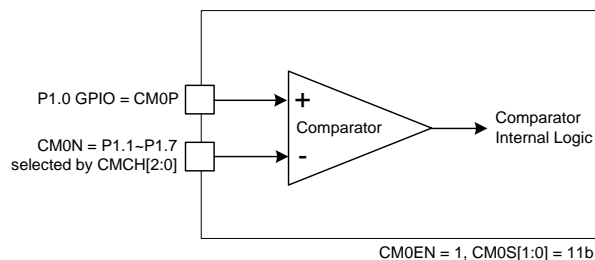


The comparator positive input terminal includes internal reference voltage source and external input pin (P1.0) controlled by CM0S[1:0] bits of CMP0M register. The internal reference voltage source supports three levels which are  $1/4 \cdot V_{dd}$  (CM0S[1:0] = 00),  $1/2 \cdot V_{dd}$  (CM0S[1:0] = 01) and  $3/4 \cdot V_{dd}$  (CM0S[1:0] = 10). When CM0S[1:0] = 11, the comparator positive input is from external input pin (P1.0). P1.0 is set input mode automatically. When CM0S[1:0] is other status, the comparator positive input is from internal reference voltage source and the P1.0 is GPIO function.

The comparator negative input terminal supports maximum 8-channel controlled by CMCH[2:0]. 000=P1.0. 001=P1.1. 010=P1.2. 011=P1.3. 100=P1.4. 101=P1.5. 110=P1.6. 111=P1.7. These channels selected is only when the comparator enables (CM0EN=1), the 8-channel analog switch works, or not workable. If one pin is selected to be comparator negative input pin, the pin is switched to input mode and connected to comparator negative input terminal. When the system selects to other pin or comparator disables, the original channel will returns to last GPIO mode automatically.

\* **Note: P1.0 is channel 0 of comparator 8-channel negative input and also shared with comparator external positive input pin. When the P1.0 is selected to comparator external positive pin (CM0S[1:0]=11) and comparator negative input pin (CMCH[2:0]=000), the both of comparator positive and negative input terminals are from P1.0.**

The comparator output terminal doesn't connect to external pin and connects to internal path. The CM0OUT flag is The CM0OUT shows the comparator result immediately, but the CM0IRQ only indicates the event of the comparator result. The comparator output terminal through de-bounce circuit generates the comparator trigger edge controlled by CM0G[1:0]. The even condition is controlled by register and includes rising edge (CM0OUT changes from low to high), falling edge (CM0OUT changes from high to low) and bi-direction (Any CM0OUT transition occurrence) controlled by CM0G[1:0] bits. The CM0IRQ = 1 condition makes the comparator interrupt service executed when CM0IEN (comparator interrupt control bit) set.



### 9.3 COMPARATOR CONTROL REGISTER

09CH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>CMP0M</b>	CM0EN	CM0OUT	-	CM0S1	CM0S0	CMCH2	CMCH1	CMCH0
Read/Write	R/W	R	-	R/W	R/W	R/W	R/W	R/W
After Reset	0	1	-	0	0	0	0	0

- Bit 7 **CM0EN**: Comparator 0 control bit.  
0 = Disable. P1[7:0] are GPIO mode.  
1 = Enable. Comparator negative input pins P1[7:0] are controlled by CMCH[2:0] bits, and positive input pin P1.0 is controlled when CM0S[1:0] = 11.
- Bit 6 **CM0OUT**: Comparator 0 output flag bit. **The comparator output status is “1” as comparator disabled.**  
0 = CM0P voltage or comparator internal reference voltage is less than CM0N voltage.  
1 = CM0P voltage or comparator internal reference voltage is larger than CM0N voltage.
- Bit [4:3] **CM0S[1:0]**: Comparator 0 positive input voltage control bit.  
00 = Internal  $1/4 \cdot V_{dd}$  and enable internal reference voltage generator.  
01 = Internal  $1/2 \cdot V_{dd}$  and enable internal reference voltage generator.  
10 = Internal  $3/4 \cdot V_{dd}$  and enable internal reference voltage generator.  
11 = Comparator positive input voltage is from external input pin (P1.0). Switch P1.0 to input mode and disable internal reference voltage generator for power saving.
- Bit [2:0] **CMCH[2:0]**: Comparator 0 negative input pin control bit.  
000 = Comparator negative input pin is P1.0, and the CM0S[1:0] can't be “11”.  
001 = Comparator negative input pin is P1.1.  
010 = Comparator negative input pin is P1.2.  
011 = Comparator negative input pin is P1.3.  
100 = Comparator negative input pin is P1.4.  
101 = Comparator negative input pin is P1.5.  
110 = Comparator negative input pin is P1.6.  
111 = Comparator negative input pin is P1.7.

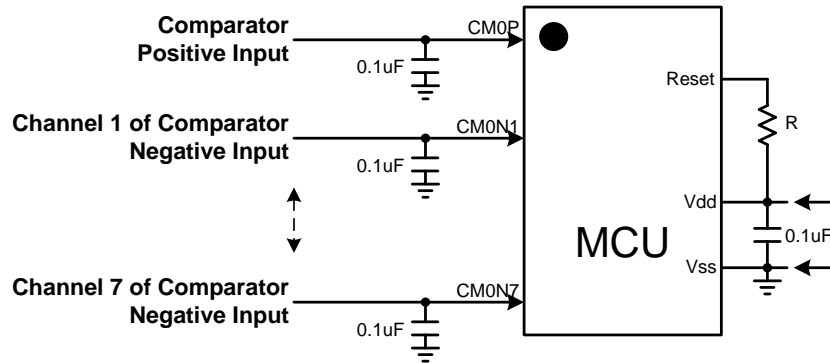
09DH	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>CMP0M1</b>	-	-	-	-	CMDB1	CMDB0	CM0G1	CM0G0
Read/Write	-	-	-	-	R/W	R/W	R/W	R/W
After Reset	-	-	-	-	0	0	0	0

- Bit [3:2] **CMDB[1:0]**: Comparator output denounce time select bit.  
00 =  $1 \cdot F_{cpu}$ .  
01 =  $2 \cdot F_{cpu}$ .  
10 =  $3 \cdot F_{cpu}$ .  
11 = No de-bounce.
- Bit [1:0] **CM0G[1:0]**: Comparator interrupt trigger direction control bit.  
00 = Reserved.  
01 = Rising edge trigger. CM0P (or comparator internal reference voltage) > CM0N.  
10 = Falling edge trigger. CM0P (or comparator internal reference voltage) < CM0N.  
11 = Both rising and falling edge trigger (Level change trigger).



## 9.4 COMPARATOR APPLICATION NOTICE

The comparator is to compares the positive voltage and negative voltage to output result. The positive and negative sources are analog signal. In hardware application circuit, the comparator input pins must be connected a 0.1uF capacitor to reduce power noise and make the input signal more stable. The application circuit is as following.



- **Example: Use comparator 0 to measure the external analog signal. When the analog signal is smaller than  $1/2 \cdot V_{dd}$ , to execute interrupt service routine.**  
**In the case, use comparator internal  $1/2 \cdot V_{dd}$  reference voltage to be the comparator positive voltage source. The interrupt trigger condition is comparator output from low to high rising edge.**

; The comparator 0 initialize.

```
MOV      A, #00001000b      ; CM0S[1:0]=01b, enable comparator internal 1/2*Vdd
B0MOV    CM0M, A             ; reference voltage to be comparator positive source.
                                ; CMCH[2:0]=000b, select comparator negative input pin
                                ; is CM0N0.
MOV      A, #00000001b      ; CM0G[1:0]=01b, set comparator interrupt request as
B0MOV    CM0M1, A            ; rising edge.
                                ; CMDB[1:0]=00b, no de-bounce.
B0BSET   FCM0IEN              ; CM0IEN=1, enable comparator 0 interrupt function.
B0BCLR   FCM0IRQ              ; CM0IRQ=0, clear comparator 0 interrupt request flag.

B0BSET   FCM0EN               ; Enable comparator 0.
```

Main: ; Main loop.

```
...
JMP      MAIN
...
```

; Interrupt service routine. Jump from interrupt vector (ORG 8).

ISR:

```
PUSH     ; Save ACC and PFLAG.
B0BTS1   FCM0IRQ              ; Check comparator 0 interrupt request flag.
JMP      ISR_EXIT             ; No interrupt request, exit interrupt service routine.

B0BCLR   FCM0IRQ              ; Clear comparator 0 interrupt request flag.
...      ; Execute comparator 0 interrupt service routine.
...
JMP      ISR_EXIT             ; End of comparator 0 interrupt service routine.
```

ISR\_EXIT: ; Exit interrupt service routine.

```
POP      ; Reload ACC and PFLAG.
RETI     ; Return to main loop.
```

# 10 SERIAL INPUT/OUTPUT TRANSCEIVER (SIO)

## 10.1 OVERVIEW

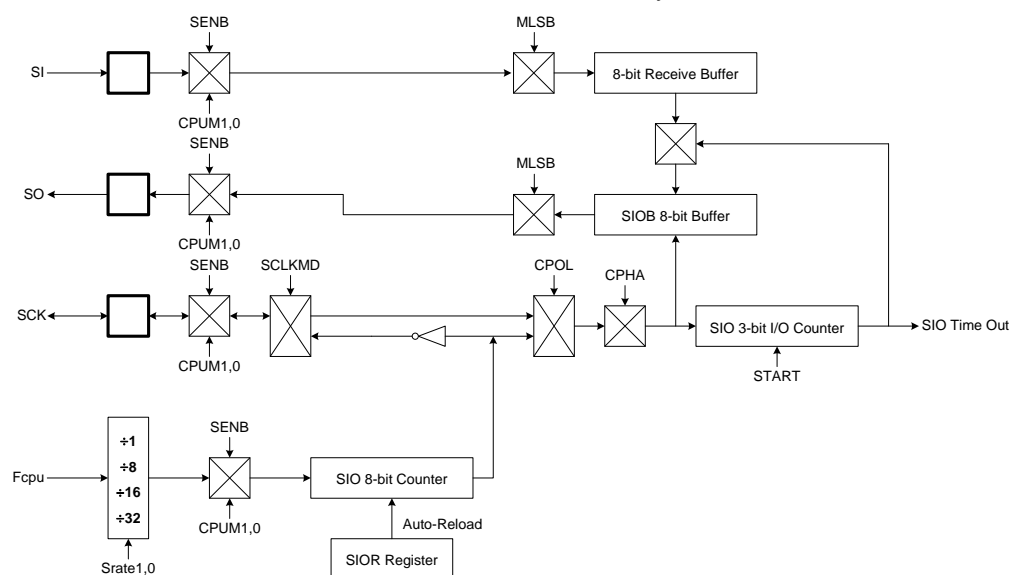
The SIO (serial input/output) transceiver is a serial communicate interface for data exchanging from one MCU to one MCU or other hardware peripherals. It is a simple 8-bit interface without a major definition of protocol, packet or control bits. The SIO transceiver includes three pins, clock (SCK), data input (SI) and data output (SO) to send data between master and slaver terminals. The SIO interface builds in 8-mode which are the clock idle status, the clock phases and data first bit direction. The 8-bit mode supports most of SIO/SPI communicate format.

The SIO features include the following:

- Full-duplex, 3-wire synchronous data transfer.
- Master (SCK is clock output) or Slave (SCK is clock input) operation.
- MSB/LSB first data transfer.
- The start phase of data sampling location selection is 1<sup>st</sup>-phase or 2<sup>nd</sup>-phase controlled register.
- SCK, SI, SO are programmable open-drain output pin for multiple salve devices application.
- Two programmable bit rates (Only in master mode).
- End-of-Transfer interrupt.

## 10.2 SIO OPERATION

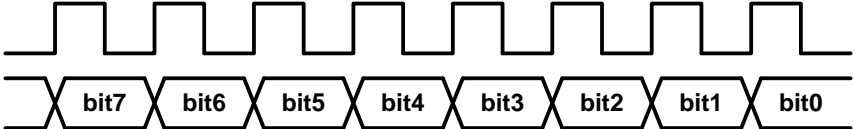
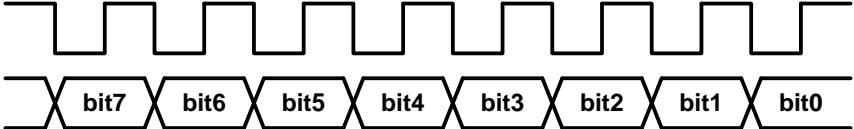
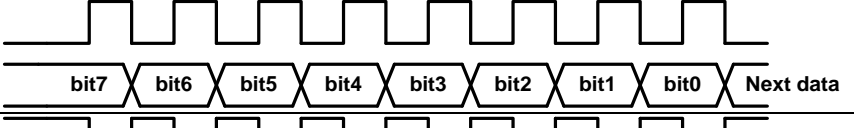
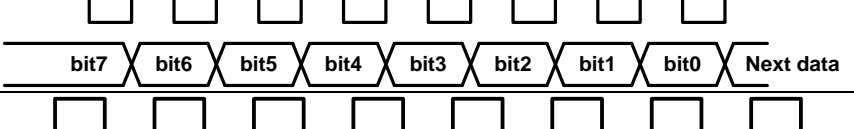
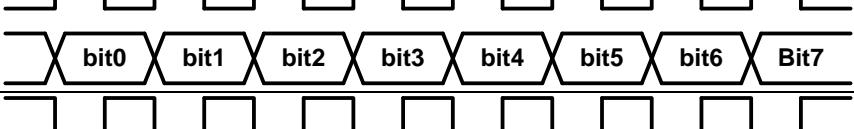
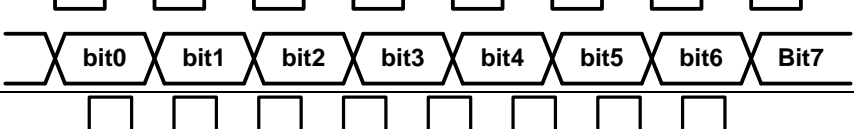
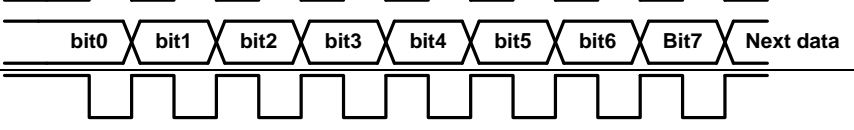
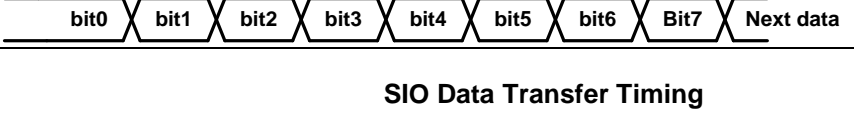
The SIOM register can control SIO operating function, such as: transmit/receive, clock rate, data transfer direction, SIO clock idle status and clock control phase and starting this circuit. This SIO circuit will transmit or receive 8-bit data automatically by setting SENB and START bits in SIOM register. The SIO data buffer is double buffer design. When the SIO operating, the SIOB register stores transfer data and one internal buffer stores receive data. When SIO operation is successfully, the internal buffer reloads into SIOB register automatically. The SIO 8-bit counter and SIOR register are designed to generate SIO's clock source with auto-reload function. The 3-bit I/O counter can monitor the operation of SIO and announce an interrupt request after transmitting/ receiving 8-bit data. After transferring 8-bit data, this circuit will be disabled automatically and re-transfer data by programming SIOM register. CPOL bit is designed to control SIO clock idle status. CPHA bit is designed to control the clock edge direction of data receive. CPOL and CPHA bits decide the SIO format. The SIO data transfer direction is controlled by MLSB bit to decide MSB first or LSB first.



SIO Interface Circuit Diagram

The SIO supports 8-mode format controlled by MLSB, CPOL and CPHA bits. The edge direction is “Data Transfer Edge”. When setting rising edge, that means to receive and transmit one bit data at SCK rising edge, and data transition is at SCK falling edge. When setting falling edge, that means to receive and transmit one bit data at SCK falling edge, and data transition is at SCK rising edge.

“CPHA” is the clock phase bit controls the phase of the clock on which data is sampled. When CPHA=1, the SCK first edge is for data transition, and receive and transmit data is at SCK 2<sup>nd</sup> edge. When CPHA=0, the 1<sup>st</sup> bit is fixed already, and the SCK first edge is to receive and transmit data. The SIO data transfer timing as following figure:

M L S B	C P O L	C P H A	Diagrams	Description
0	0	1		SCK idle status = Low. The transfer first bit = MSB. SCK data transfer edge = Falling edge.
0	1	1		SCK idle status = High. The transfer first bit = MSB. SCK data transfer edge = Rising edge.
0	0	0		SCK idle status = Low. The transfer first bit = MSB. SCK data transfer edge = Rising edge.
0	1	0		SCK idle status = High. The transfer first bit = MSB. SCK data transfer edge = Falling edge.
1	0	1		SCK idle status = Low. The transfer first bit = LSB. SCK data transfer edge = Falling edge.
1	1	1		SCK idle status = High. The transfer first bit = LSB. SCK data transfer edge = Rising edge.
1	0	0		SCK idle status = Low. The transfer first bit = LSB. SCK data transfer edge = Rising edge.
1	1	0		SCK idle status = High. The transfer first bit = LSB. SCK data transfer edge = Falling edge.

**SIO Data Transfer Timing**

The SIO supports interrupt function. SIOIEN is SIO interrupt function control bit. SIOIEN=0, disable SIO interrupt function. SIOIEN=1, enable SIO interrupt function. When SIO interrupt function enable, the program counter points to interrupt vector (ORG 8) to do SIO interrupt service routine after SIO operating. SIOIRQ is SIO interrupt request flag, and also to be the SIO operating status indicator when SIOIEN = 0, but cleared by program. When SIO operation finished, the SIOIRQ would be set to "1", and the operation is the inverse status of SIO "START" control bit.

The SIOIRQ and SIO START bit indicating the end status of SIO operation is after one 8-bit data transferring. The duration from SIO transfer end to SIOIRQ/START active is about " $\frac{1}{2} \times \text{SIO clock}$ ", means the SIO end indicator doesn't active immediately.

\* **Note:** The first step of SIO operation is to setup the SIO pins' mode. Enable SENB, select CPOL and CPHA bits. These bits control SIO pins' mode.

## 10.3 SIOM MODE REGISTER

0B4H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>SIOM</b>	SENB	START	SRATE1	SRATE0	MLSB	SCKMD	CPOL	CPHA
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

- Bit 7     **SENB:** SIO function control bit.  
0 = Disable SIO function. P5.0~P5.2 are GPIO.  
1 = Enable SIO function. P5.0~P5.2 are SIO pins. **SIO pin structure can be push-pull structure and open-drain structure controlled by P1OC register.**
- Bit 6     **START:** SIO progress control bit.  
0 = End of transfer.  
1 = SIO transmitting.
- Bit [5:4] **SRATE1,0:** SIO's transfer rate select bit. **These 2-bits are workless when SCKMD=1.**  
00 = fcpu.  
01 = fcpu/32  
10 = fcpu/16  
11 = fcpu/8.
- Bit 3     **MLSB:** MSB/LSB transfer first.  
0 = MSB transmit first.  
1 = LSB transmit first.
- Bit 2     **SCKMD:** SIO's clock mode select bit.  
0 = Internal. (Master mode)  
1 = External. (Slave mode)
- Bit 1     **CPOL:** SCK idle status control bit.  
0 = SCK idle status is low status.  
1 = SCK idle status is high status.
- Bit 0     **CPHA:** The Clock Phase bit controls the phase of the clock on which data is sampled.  
0 = Data receive at the first clock phase.  
1 = Data receive at the second clock phase.

Because SIO function is shared with Port5 for P5.0 as SCK, P5.1 as SI and P5.2 as SO. The following table shows the Port5[2:0] I/O mode behavior and setting when SIO function enable and disable.

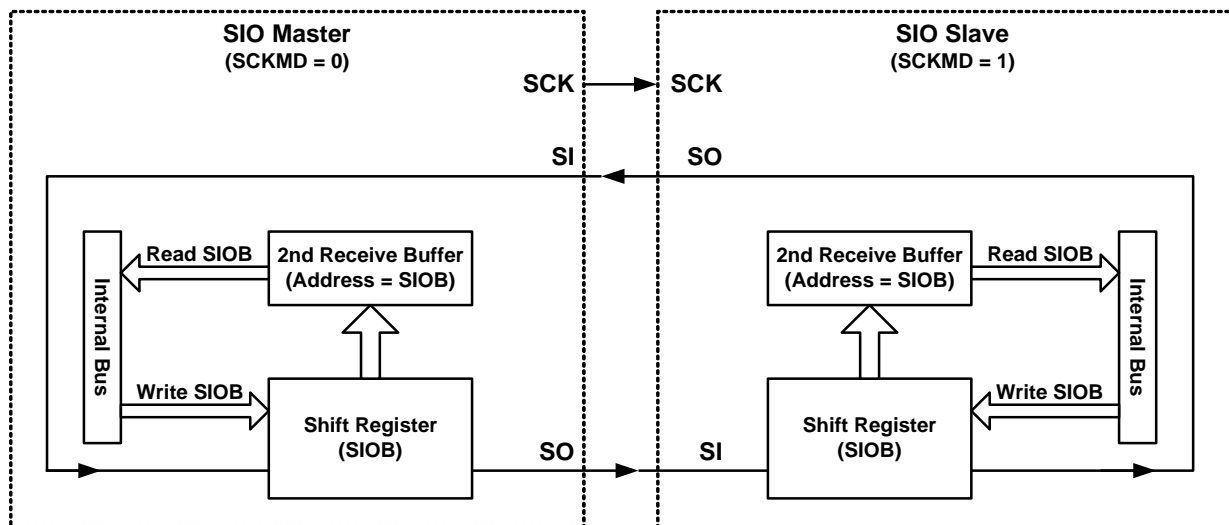
<b>SENB=1 (SIO Function Enable)</b>		
P5.0/SCK	(SCKMD=1) SIO source = External clock	P5.0 will change to Input mode automatically, no matter what P5M setting.
	(SCKMD=0) SIO source = Internal clock	P5.0 will change to Output mode automatically, no matter what P5M setting.
P5.1/SI	P5.1 must be set as Input mode in P5M ,or the SIO function will be abnormal	
P5.2/SO	SIO = Transmitter/Receiver	P5.2 will change to Output mode automatically, no matter what P5M setting.
<b>SENB=0 (SIO Function Disable)</b>		
P5.0/P5.1/P5.2	Port5[2:0] I/O mode are fully controlled by P5M when SIO function Disable	

- ★ **Note:**
1. If SCKMD=1 for external clock, the SIO is in SLAVE mode. If SCKMD=0 for internal clock, the SIO is in MASTER mode.
  2. Don't set SENB and START bits in the same time. That makes the SIO function error.
  3. SIO pin can be push-pull structure and open-drain structure controlled by P10C register.

## 10.4 SIOB DATA BUFFER

0B6H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>SIOB</b>	SIOB7	SIOB6	SIOB5	SIOB4	SIOB3	SIOB2	SIOB1	SIOB0
Read/Write	R/W	R/W	R/W	R/W	R/W	R/W	R/W	R/W
After reset	0	0	0	0	0	0	0	0

SIOB is the SIO data buffer register. It stores serial I/O transmit and receive data. The system is single-buffered in the transmit direction and double-buffered in the receive direction. This means that bytes to be transmitted cannot be written to the SIOB Data Register before the entire shift cycle is completed. When receiving data, however, a received byte must be read from the SIOB Data Register before the next byte has been completely shifted in. Otherwise, the first byte is lost. Following figure shows a typical SIO transfer between two micro-controllers. Master MCU sends SCK for initial the data transfer. Both master and slave MCU must work in the same clock edge direction, and then both controllers would send and receive data at the same time.



**SIO Data Transfer Diagram**

## 10.5 SIOR REGISTER DESCRIPTION

0B5H	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
<b>SIOR</b>	SIOR7	SIOR6	SIOR5	SIOR4	SIOR3	SIOR2	SIOR1	SIOR0
Read/Write	W	W	W	W	W	W	W	W
After reset	0	0	0	0	0	0	0	0

The SIOR is designed for the SIO counter to reload the counted value when end of counting. It is like a post-scaler of SIO clock source and let SIO has more flexible to setting SCK range. Users can set the SIOR value to setup SIO transfer time. To setup SIOR value equation to desire transfer time is as following.

$$\text{SCK frequency} = (\text{SIO rate} / (256 - \text{SIOR})) / 2$$

$$\text{SIOR} = 256 - (1 / (2 * \text{SCK frequency}) * \text{SIO rate})$$

➤ **Example: Setup the SIO clock to be 5KHz. Fhosc = 16MHz. SIO's rate = Fcpu = Fhosc/16.**

$$\begin{aligned} \text{SIOR} &= 256 - (1 / (2 * 5\text{KHz}) * 16\text{MHz} / 16) \\ &= 256 - (0.0001 * 1000000) \\ &= 256 - 100 \\ &= 156 \end{aligned}$$

# 11 INSTRUCTION TABLE

Field	Mnemonic	Description	C	DC	Z	Cycle
MOV O V E	MOV A,M	$A \leftarrow M$	-	-	√	1
	MOV M,A	$M \leftarrow A$	-	-	-	1
	B0MOV A,M	$A \leftarrow M$ (bank 0)	-	-	√	1
	B0MOV M,A	$M$ (bank 0) $\leftarrow A$	-	-	-	1
	MOV A,I	$A \leftarrow I$	-	-	-	1
	B0MOV M,I	$M \leftarrow I$ , "M" only supports 0x80~0x87 registers (e.g. PFLAG,R,Y,Z...)	-	-	-	1
	XCH A,M	$A \leftrightarrow M$	-	-	-	1+N
	B0XCH A,M	$A \leftrightarrow M$ (bank 0)	-	-	-	1+N
	MOVC	$R, A \leftarrow ROM[Y,Z]$	-	-	-	2
A R I T H M E T I C	ADC A,M	$A \leftarrow A + M + C$ , if occur carry, then $C=1$ , else $C=0$	√	√	√	1
	ADC M,A	$M \leftarrow A + M + C$ , if occur carry, then $C=1$ , else $C=0$	√	√	√	1+N
	ADD A,M	$A \leftarrow A + M$ , if occur carry, then $C=1$ , else $C=0$	√	√	√	1
	ADD M,A	$M \leftarrow A + M$ , if occur carry, then $C=1$ , else $C=0$	√	√	√	1+N
	B0ADD M,A	$M$ (bank 0) $\leftarrow M$ (bank 0) + A, if occur carry, then $C=1$ , else $C=0$	√	√	√	1+N
	ADD A,I	$A \leftarrow A + I$ , if occur carry, then $C=1$ , else $C=0$	√	√	√	1
	SBC A,M	$A \leftarrow A - M - /C$ , if occur borrow, then $C=0$ , else $C=1$	√	√	√	1
	SBC M,A	$M \leftarrow A - M - /C$ , if occur borrow, then $C=0$ , else $C=1$	√	√	√	1+N
	SUB A,M	$A \leftarrow A - M$ , if occur borrow, then $C=0$ , else $C=1$	√	√	√	1
	SUB M,A	$M \leftarrow A - M$ , if occur borrow, then $C=0$ , else $C=1$	√	√	√	1+N
	SUB A,I	$A \leftarrow A - I$ , if occur borrow, then $C=0$ , else $C=1$	√	√	√	1
L O G I C	AND A,M	$A \leftarrow A$ and $M$	-	-	√	1
	AND M,A	$M \leftarrow A$ and $M$	-	-	√	1+N
	AND A,I	$A \leftarrow A$ and $I$	-	-	√	1
	OR A,M	$A \leftarrow A$ or $M$	-	-	√	1
	OR M,A	$M \leftarrow A$ or $M$	-	-	√	1+N
	OR A,I	$A \leftarrow A$ or $I$	-	-	√	1
	XOR A,M	$A \leftarrow A$ xor $M$	-	-	√	1
	XOR M,A	$M \leftarrow A$ xor $M$	-	-	√	1+N
	XOR A,I	$A \leftarrow A$ xor $I$	-	-	√	1
P R O C E S S	SWAP M	$A(b3-b0, b7-b4) \leftarrow M(b7-b4, b3-b0)$	-	-	-	1
	SWAPM M	$M(b3-b0, b7-b4) \leftarrow M(b7-b4, b3-b0)$	-	-	-	1+N
	RRC M	$A \leftarrow RRC M$	√	-	-	1
	RRCM M	$M \leftarrow RRC M$	√	-	-	1+N
	RLC M	$A \leftarrow RLC M$	√	-	-	1
	RLCM M	$M \leftarrow RLC M$	√	-	-	1+N
	CLR M	$M \leftarrow 0$	-	-	-	1
	BCLR M.b	$M.b \leftarrow 0$	-	-	-	1+N
	BSET M.b	$M.b \leftarrow 1$	-	-	-	1+N
	B0BCLR M.b	$M(bank\ 0).b \leftarrow 0$	-	-	-	1+N
	B0BSET M.b	$M(bank\ 0).b \leftarrow 1$	-	-	-	1+N
B R A N C H	CMPS A,I	$ZF, C \leftarrow A - I$ , If $A = I$ , then skip next instruction	√	-	√	1 + S
	CMPS A,M	$ZF, C \leftarrow A - M$ , If $A = M$ , then skip next instruction	√	-	√	1 + S
	INCS M	$A \leftarrow M + 1$ , If $A = 0$ , then skip next instruction	-	-	-	1 + S
	INCMS M	$M \leftarrow M + 1$ , If $M = 0$ , then skip next instruction	-	-	-	1+N+S
	DECS M	$A \leftarrow M - 1$ , If $A = 0$ , then skip next instruction	-	-	-	1 + S
	DECMS M	$M \leftarrow M - 1$ , If $M = 0$ , then skip next instruction	-	-	-	1+N+S
	BTS0 M.b	If $M.b = 0$ , then skip next instruction	-	-	-	1 + S
	BTS1 M.b	If $M.b = 1$ , then skip next instruction	-	-	-	1 + S
	B0BTS0 M.b	If $M(bank\ 0).b = 0$ , then skip next instruction	-	-	-	1 + S
	B0BTS1 M.b	If $M(bank\ 0).b = 1$ , then skip next instruction	-	-	-	1 + S
M I S C	JMP d	$PC15/14 \leftarrow RomPages1/0, PC13-PC0 \leftarrow d$	-	-	-	2
	CALL d	$Stack \leftarrow PC15-PC0, PC15/14 \leftarrow RomPages1/0, PC13-PC0 \leftarrow d$	-	-	-	2
	RET	$PC \leftarrow Stack$	-	-	-	2
	RETI	$PC \leftarrow Stack$ , and to enable global interrupt	-	-	-	2
	PUSH	To push ACC and PFLAG (except NT0, NPD bit) into buffers.	-	-	-	1
	POP	To pop ACC and PFLAG (except NT0, NPD bit) from buffers.	√	√	√	1
	NOP	No operation	-	-	-	1

Note: 1. "M" is system register or RAM. If "M" is system registers then "N" = 0, otherwise "N" = 1.  
2. If branch condition is true then "S = 1", otherwise "S = 0".

# 12 ELECTRICAL CHARACTERISTIC

## 12.1 ABSOLUTE MAXIMUM RATING

Supply voltage (Vdd).....	- 0.3V ~ 6.0V
Input in voltage (Vin).....	Vss – 0.2V ~ Vdd + 0.2V
Operating ambient temperature (Topr)	
SN8P2522P, SN8P2522S, SN8P2522X, SN8P2521P, SN8P2521S.....	-20°C ~ + 85°C
SN8P2522PD, SN8P2522SD, SN8P2522XD, SN8P2521PD, SN8P2521SD.....	-40°C ~ + 85°C
Storage ambient temperature (Tstor) .....	-40°C ~ + 125°C

## 12.2 ELECTRICAL CHARACTERISTIC

(All of voltages refer to Vss, Vdd = 5.0V, fosc = 16MHz, fcpu=1MHz, ambient temperature is 25°C unless otherwise note.)

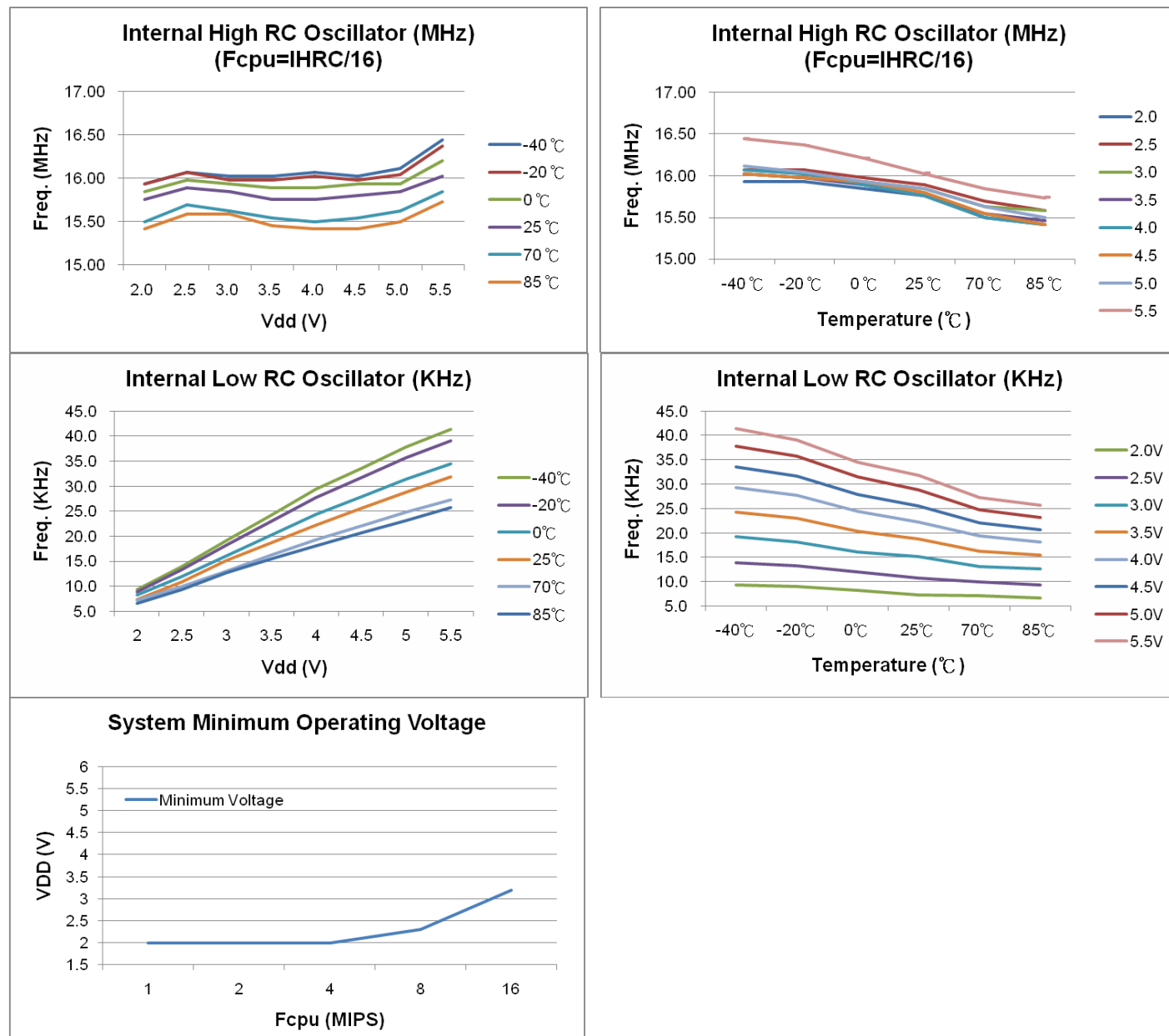
PARAMETER	SYM.	DESCRIPTION		MIN.	TYP.	MAX.	UNIT
Operating voltage	Vdd	Normal mode, Vpp = Vdd, 25°C, Fcpu = 1MHz.		2.2	-	5.5	V
		Normal mode, Vpp = Vdd, -40°C~85°C		2.4	-	5.5	V
RAM Data Retention voltage	Vdr			1.5	-	-	V
*Vdd rise rate	Vpor	Vdd rise rate to ensure internal power-on reset		0.05	-	-	V/ms
Input Low Voltage	ViL1	All input ports		Vss	-	0.3Vdd	V
	ViL2	Reset pin		Vss	-	0.2Vdd	V
Input High Voltage	ViH1	All input ports		0.7Vdd	-	Vdd	V
	ViH2	Reset pin		0.9Vdd	-	Vdd	V
Reset pin leakage current	Ilekg	Vin = Vdd		-	-	2	uA
I/O port input leakage current	Ilekg	Pull-up resistor disable, Vin = Vdd		-	-	2	uA
I/O port pull-up resistor	Rup	Vin = Vss , Vdd = 3V		100	200	300	KΩ
		Vin = Vss , Vdd = 5V		50	100	150	
I/O output source current sink current	IoH	Vop = Vdd – 0.5V		8	-	-	mA
	IoL1	Vop = Vss + 0.5V		8	-	-	mA
	IoL2	Vop = Vss + 1.5V, P5.3, P5.4 only.		150	200	250	mA
*INTn trigger pulse width	Tint0	INT0 interrupt request pulse width		2/fcpu	-	-	cycle
Supply Current (Disable Comparator)	Idd1	Run Mode (No loading, IHRC)	Vdd= 3V, Fcpu = 16MHz/2	-	5	-	mA
			Vdd= 5V, Fcpu = 16MHz/2	-	7	-	mA
			Vdd= 3V, Fcpu = 16MHz/4	-	2	-	mA
			Vdd= 5V, Fcpu = 16MHz/4	-	4	-	mA
			Vdd= 3V, Fcpu = 16MHz/16	-	1.5	-	mA
			Vdd= 5V, Fcpu = 16MHz/16	-	3	-	mA
	Idd2	Slow Mode (Internal low RC, Stop high clock)	Vdd= 3V, ILRC=16KHz	-	3.5	-	uA
			Vdd= 5V, ILRC=32KHz	-	10	-	uA
	Idd3	Sleep Mode	Vdd= 5V/3V	-	1	2	uA
	Idd4	Green Mode (No loading, Watchdog Disable)	Vdd= 3V, IHRC=16MHz	-	0.35	-	mA
			Vdd= 5V, IHRC=16MHz	-	0.55	-	mA
			Vdd= 3V, ILRC=16KHz	-	2	-	uA
Vdd= 5V, ILRC=32KHz			-	5.5	-	uA	
Internal High Oscillator Freq.	Fihrc	Internal High RC (IHRC)	25°C, Vdd=2.2V~ 5.5V Fcpu=Fhosc/2~Fhosc/16	15.68	16	16.32	MHz
			-40°C~85°C,Vdd=2.4V~ 5.5V Fcpu=Fhosc/2~Fhosc/16	15.2	16	16.8	MHz
*LVD Voltage	Vdet0	Low voltage reset level. 25°C		1.9	2.0	2.1	V
		Low voltage reset level. -40°C~85°C		1.8	2.0	2.3	V
	Vdet1	Low voltage reset/indicator level. 25°C		2.3	2.4	2.5	V
		Low voltage reset/indicator level. -40°C~85°C		2.2	2.4	2.7	V
	Vdet2	Low voltage reset/indicator level. 25°C		3.5	3.6	3.7	V
		Low voltage reset/indicator level. -40°C~85°C		3.3	3.6	3.9	V
Comparator Quiescent Current	Icmq	Iout=0		-	-	1	uA
Comparator Operating Current	Icmop	Internal reference disables. Vdd = 3V		-	30	-	uA
		Internal reference disables. Vdd = 5V		-	40	-	uA
		Internal reference enables. Vdd = 3V		-	50	-	uA
		Internal reference enables. Vdd = 5V		-	65	-	uA
Comparator Input Offset Voltage	Vcmof	Vcm=Vss		-10	-	+10	mV
Common Mode Input Voltage Range	Vcm	Vdd=5.0V		Vss-0.3	-	Vdd+0.3	V

\*These parameters are for design reference, not tested.



## 12.3 CHARACTERISTIC GRAPHS

The Graphs in this section are for design guidance, not tested or guaranteed. In some graphs, the data presented are outside specified operating range. This is for information only and devices are guaranteed to operate properly only within the specified range.



# 13 DEVELOPMENT TOOL

SONiX provides ICE (in circuit emulation), IDE (Integrated Development Environment) and EV-kit for SN8P2522 development. ICE and EV-kit are external hardware devices, and IDE is a friendly user interface for firmware development and emulation. These development tools' version is as following.

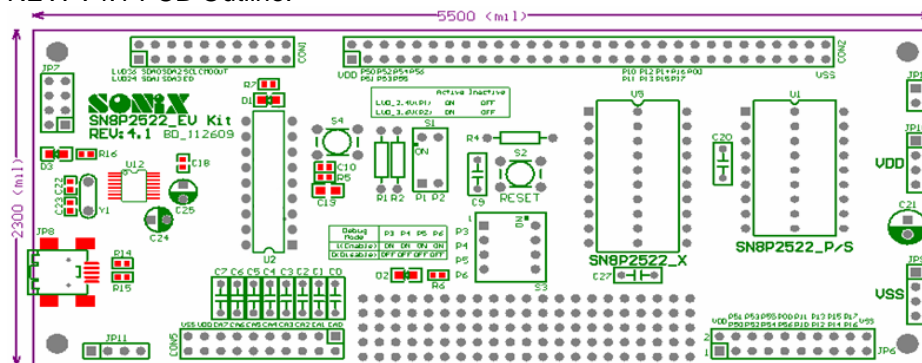
- ICE: SN8ICE2K Plus II. (Please install 16MHz crystal in ICE to implement IHRC emulation.).
- ICE emulation speed maximum: 8 MIPS @ 5V (e.g. 16Mhz crystal, Fcpu = Fosc/2).
- EV-KIT: SN8P2522 EV Kit REV: V4.1 or SN8P2522 EV Kit REV: V5.0
- IDE: SONiX IDE M2IDE\_V129 or greater.
- Writer: MPIII writer.
- Writer transition board: SN8P2522

## 13.1 SN8P2522 EV-KIT

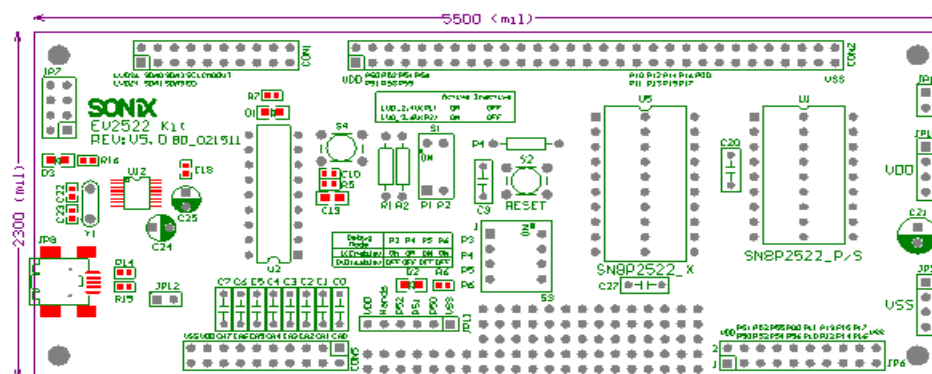
SN8P2522 EV- KIT includes ICE interface, GPIO interface and EV-chip module.

**EV-chip module:** Emulate 8 channel comparator function.

SN8P2522 EV- KIT REV: V4.1 PCB Outline:



SN8P2522 EV- KIT REV: V5.0 PCB Outline:



- CON1, CON2: ICE interface connected to SN8ICE2K Plus.
- JP6: GPIO connector.
- U2: SN8P2522 EV-chip for comparator emulation.
- U1: SN8P2522 DIP/SOP form connector for connecting to user's target board.
- U5: SN8P2522 SSOP form connector for connecting to user's target board.
- S1: LVD24 and LVD36 emulating switch.
- CON5 (CA0~CA7): 8 channel comparator connectors.
- C0~C7: 8 channel comparator capacitors.

## 13.2 ICE and EV-KIT APPLICATION NOTIC

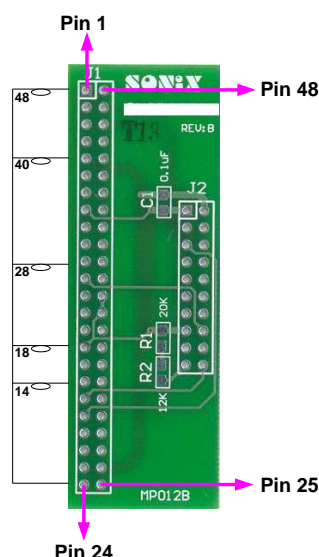
1. SN8P2522 EV- KIT includes comparator emulation module.
2. The SN8P2522 EV-chip programmed emulating code to emulate comparator function.
3. For comparator emulation, input comparator signals are from CA0~CA7 pins.
4. For the GPIO function emulation is from connector JP6.
5. SN8P2522 EV- KIT power switch selection table as follows:

	JP1	JP12	JP10
ICE Power	<b>SHORT</b>	OPEN	OPEN
External Power	OPEN	OPEN	<b>SHORT</b>
USB Power	OPEN	<b>SHORT</b>	OPEN

6. The different of version 4.1 and version 5.0 is JP12 jumper. If JP12 **SHORT**, the EV-Kit can supply from USB power source. But in this time JP1 and JP10 jumpers must be **OPEN**.

# 14 OTP PROGRAMMING PIN

## 14.1 WRITER TRANSITION BOARD SOCKET PIN ASSIGNMENT



### JP3 (Mapping to 48-pin text tool)

DIP 1	1	48	DIP48
DIP 2	2	47	DIP47
DIP 3	3	46	DIP46
DIP 4	4	45	DIP45
DIP 5	5	44	DIP44
DIP 6	6	43	DIP43
DIP 7	7	42	DIP42
DIP 8	8	41	DIP41
DIP 9	9	40	DIP40
DIP10	10	39	DIP39
DIP11	11	38	DIP38
DIP12	12	37	DIP37
DIP13	13	36	DIP36
DIP14	14	35	DIP35
DIP15	15	34	DIP34
DIP16	16	33	DIP33
DIP17	17	32	DIP32
DIP18	18	31	DIP31
DIP19	19	30	DIP30
DIP20	20	29	DIP29
DIP21	21	28	DIP28
DIP22	22	27	DIP27
DIP23	23	26	DIP26
DIP24	24	25	DIP25

### Writer JP1/JP2

VDD	1	2	VSS
CLK/PGCLK	3	4	CE
PGM/OTPClk	5	6	OE/ShiftDat
D1	7	8	D0
D3	9	10	D2
D5	11	12	D4
D7	13	14	D6
VDD	15	16	VPP
HLS	17	18	RST
-	19	20	ALSB/PDB

JP1 for Writer transition board  
JP2 for dice and >48 pin package

## 14.2 PROGRAMMING PIN MAPPING:

Programming Pin Information of SN8P2522 Series							
Chip Name		SN8P2522P/S(DIP/SOP)			SN8P2522X(SSOP)		
Writer Connector		IC and JP3 48-pin text tool Pin Assignment					
JP1/JP2 Pin Number	JP1/JP2 Pin Name	IC Pin Number	IC Pin Name	JP3 Pin Number	IC Pin Number	IC Pin Name	JP3 Pin Number
1	VDD	5	VDD	20	1,20	VDD	15,34
2	GND	14	VSS	29	10,11	VSS	24,25
3	CLK	10	P5.0	25	6	P5.0	20
4	CE		-	-		-	-
5	PGM	4	P1.0	19	19	P1.0	33
6	OE	8	P5.2	23	4	P5.2	18
7	D1		-	-		-	-
8	D0		-	-		-	-
9	D3		-	-		-	-
10	D2		-	-		-	-
11	D5		-	-		-	-
12	D4		-	-		-	-
13	D7		-	-		-	-
14	D6		-	-		-	-
15	VDD		-	-		-	-
16	VPP	6	RST	21	2	RST	16
17	HLS		-	-		-	-
18	RST		-	-		-	-
19	-		-	-		-	-
20	ALSB/PDB	3	P1.1	18	18	P1.1	32

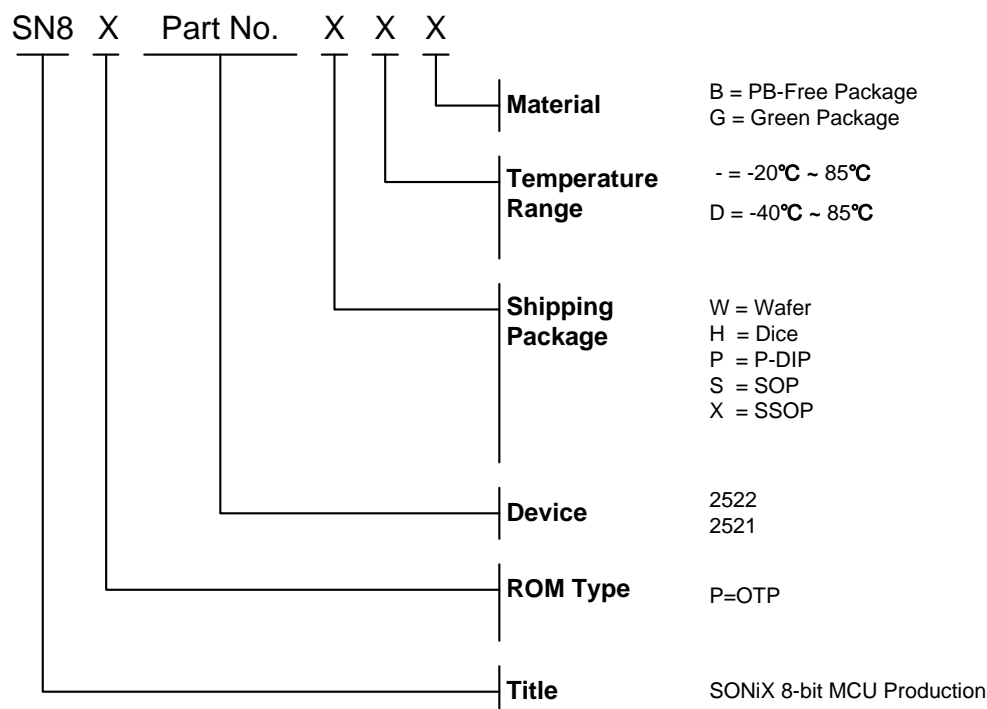
Programming Pin Information of SN8P2522 Series							
Chip Name		SN8P2521P/S(DIP/SOP)					
Writer Connector		IC and JP3 48-pin text tool Pin Assignment					
JP1/JP2 Pin Number	JP1/JP2 Pin Name	IC Pin Number	IC Pin Name	JP3 Pin Number			
1	VDD	4	VDD	21			
2	GND	12	VSS	29			
3	CLK	8	P5.0	25			
4	CE		-	-			
5	PGM	3	P1.0	20			
6	OE	6	P5.2	23			
7	D1		-	-			
8	D0		-	-			
9	D3		-	-			
10	D2		-	-			
11	D5		-	-			
12	D4		-	-			
13	D7		-	-			
14	D6		-	-			
15	VDD		-	-			
16	VPP	5	RST	22			
17	HLS		-	-			
18	RST		-	-			
19	-		-	-			
20	ALSB/PDB	2	P1.1	19			

# 15 Marking Definition

## 15.1 INTRODUCTION

There are many different types in Sonix 8-bit MCU production line. This note listed the production definition of all 8-bit MCU for order or obtain information. This definition is only for Blank OTP MCU.

## 15.2 MARKING INDETIFICATION SYSTEM



## 15.3 MARKING EXAMPLE

- Wafer, Dice:

Name	ROM Type	Device	Package	Temperature	Material
SN8P2522W	OTP	2522	Wafer	-20°C ~85°C	-
SN8P2522H	OTP	2522	Dice	-20°C ~85°C	-

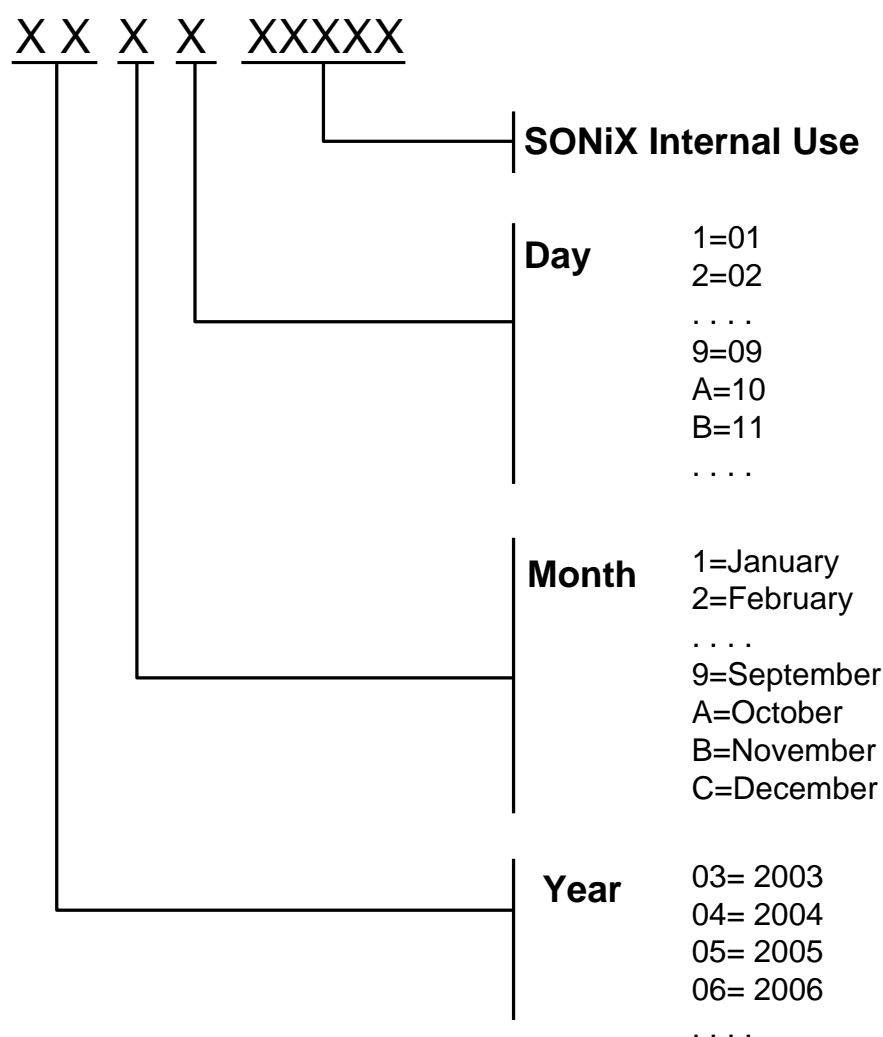
- Green Package:

Name	ROM Type	Device	Package	Temperature	Material
SN8P2522PG	OTP	2522	P-DIP	-20°C ~85°C	Green Package
SN8P2522SG	OTP	2522	SOP	-20°C ~85°C	Green Package
SN8P2522XG	OTP	2522	SSOP	-20°C ~85°C	Green Package
SN8P2521PG	OTP	2522	P-DIP	-20°C ~85°C	Green Package
SN8P2521SG	OTP	2522	SOP	-20°C ~85°C	Green Package
SN8P2522PDG	OTP	2522	P-DIP	-40°C ~85°C	Green Package
SN8P2522SDG	OTP	2522	SOP	-40°C ~85°C	Green Package
SN8P2522XDG	OTP	2522	SSOP	-40°C ~85°C	Green Package
SN8P2521PDG	OTP	2522	P-DIP	-40°C ~85°C	Green Package
SN8P2521SDG	OTP	2522	SOP	-40°C ~85°C	Green Package

● **PB-Free Package:**

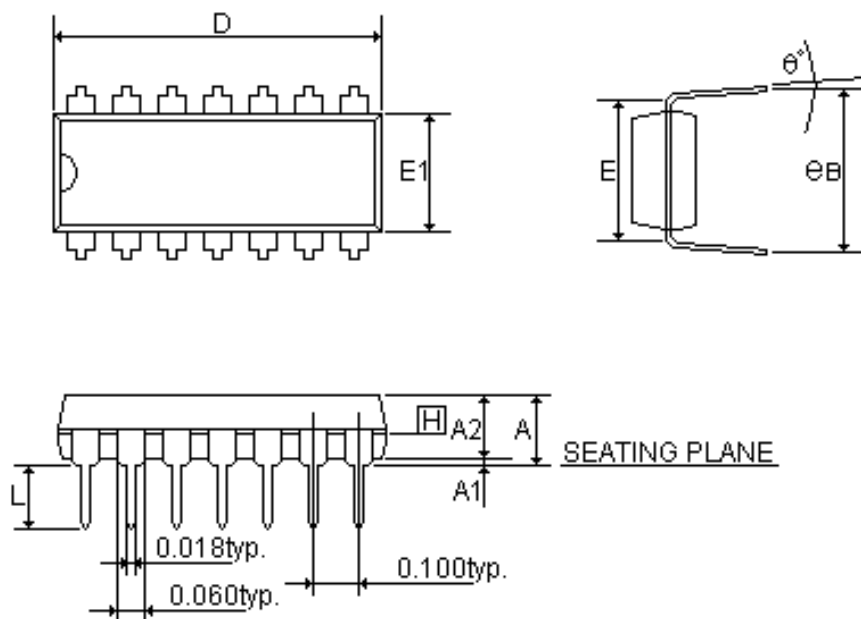
Name	ROM Type	Device	Package	Temperature	Material
SN8P2522PB	OTP	2522	P-DIP	-20°C~85°C	PB-Free Package
SN8P2522SB	OTP	2522	SOP	-20°C~85°C	PB-Free Package
SN8P2522XB	OTP	2522	SSOP	-20°C~85°C	PB-Free Package
SN8P2521PB	OTP	2522	P-DIP	-20°C~85°C	PB-Free Package
SN8P2521SB	OTP	2522	SOP	-20°C~85°C	PB-Free Package
SN8P2522PDB	OTP	2522	P-DIP	-40°C~85°C	PB-Free Package
SN8P2522SDB	OTP	2522	SOP	-40°C~85°C	PB-Free Package
SN8P2522XDB	OTP	2522	SSOP	-40°C~85°C	PB-Free Package
SN8P2521PDB	OTP	2522	P-DIP	-40°C~85°C	PB-Free Package
SN8P2521SDB	OTP	2522	SOP	-40°C~85°C	PB-Free Package

## 15.4 DATECODE SYSTEM



# 16 PACKAGE INFORMATION

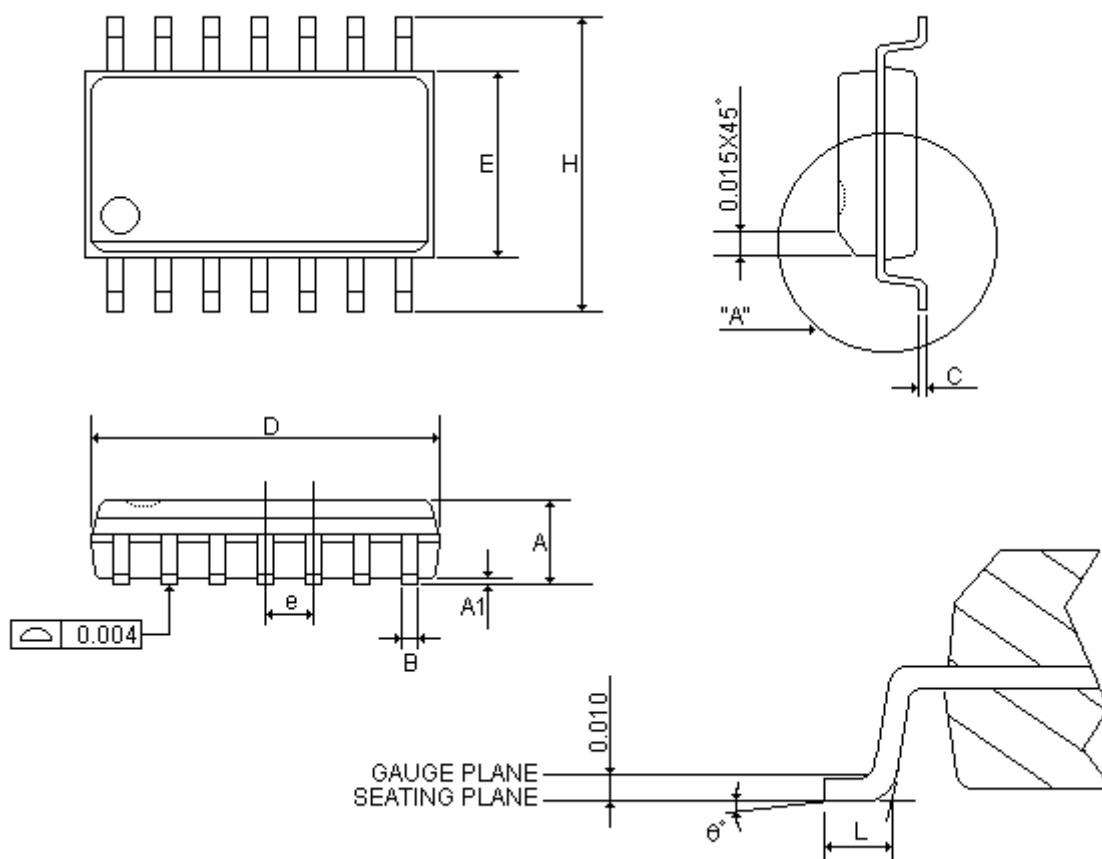
## 16.1 P-DIP 14 PIN



SYMBOLS	MIN	NOR	MAX	MIN	NOR	MAX
	(inch)			(mm)		
A	-	-	0.210	-	-	5.334
A1	0.015	-	-	0.381	-	-
A2	0.125	0.130	0.135	3.175	3.302	3.429
D	0.735	0.075	0.775	18.669	1.905	19.685
E	0.300			7.62		
E1	0.245	0.250	0.255	6.223	6.35	6.477
L	0.115	0.130	0.150	2.921	3.302	3.810
eB	0.335	0.355	0.375	8.509	9.017	9.525
θ°	0°	7°	15°	0°	7°	15°

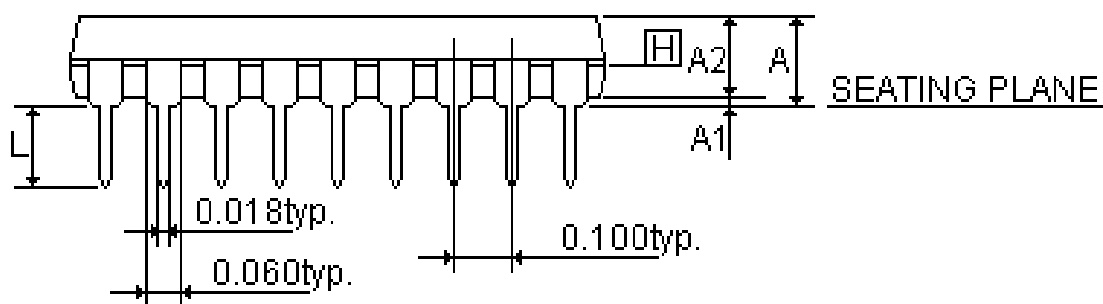
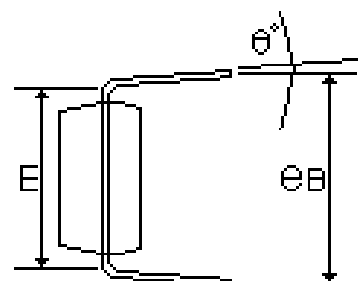
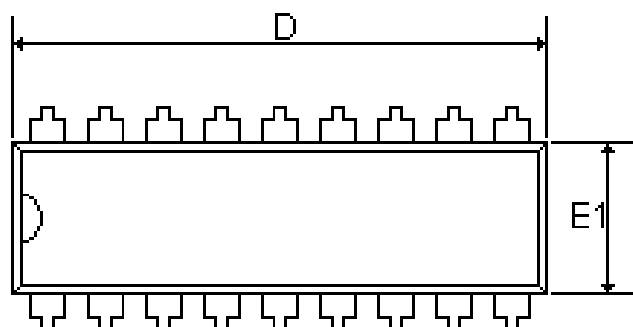


## 16.2 SOP 14 PIN



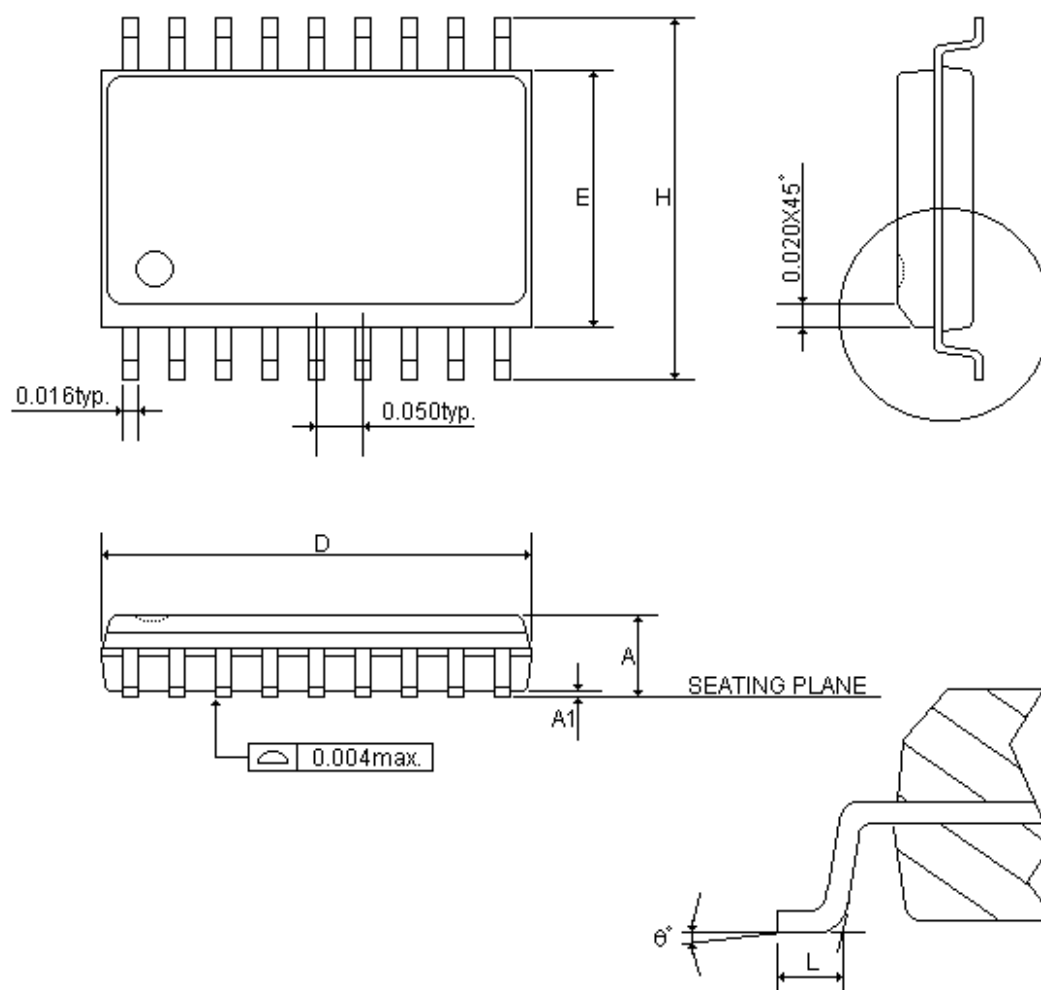
SYMBOLS	MIN	NOR	MAX	MIN	NOR	MAX
	(inch)			(mm)		
A	0.058	0.064	0.068	1.4732	1.6256	1.7272
A1	0.004	-	0.010	0.1016	-	0.254
B	0.013	0.016	0.020	0.3302	0.4064	0.508
C	0.0075	0.008	0.0098	0.1905	0.2032	0.2490
D	0.336	0.341	0.344	8.5344	8.6614	8.7376
E	0.150	0.154	0.157	3.81	3.9116	3.9878
e	-	0.050	-	-	1.27	-
H	0.228	0.236	0.244	5.7912	5.9944	6.1976
L	0.015	0.025	0.050	0.381	0.635	1.27
θ°	0°	-	8°	0°	-	8°

## 16.3 P-DIP 18 PIN



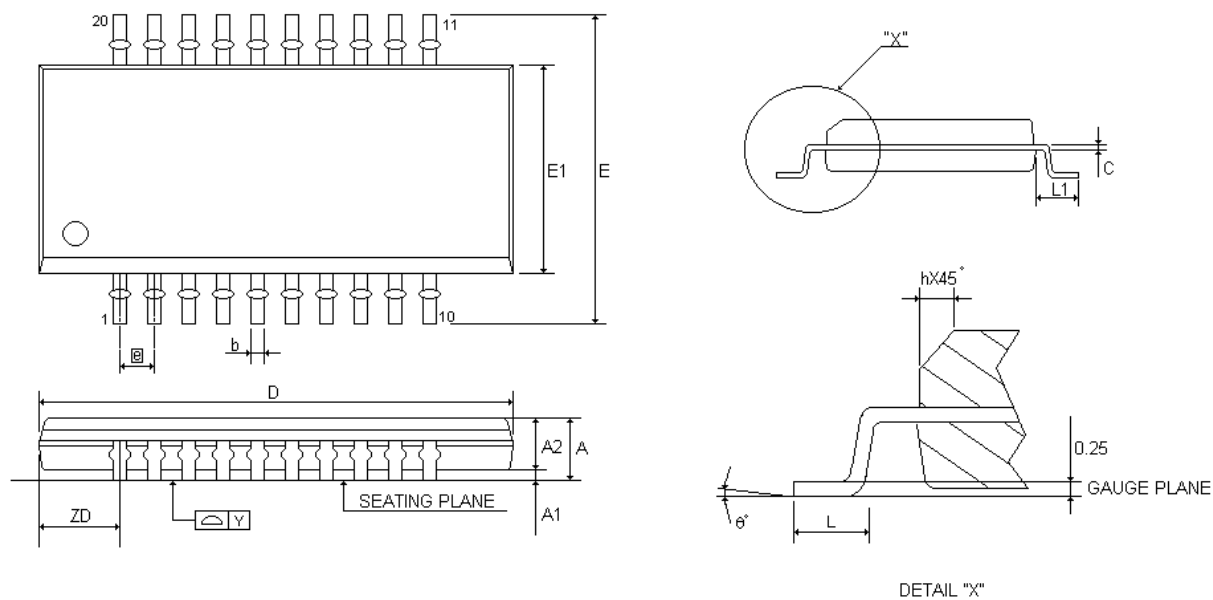
SYMBOLS	MIN	NOR	MAX	MIN	NOR	MAX
	(inch)			(mm)		
A	-	-	0.210	-	-	5.334
A1	0.015	-	-	0.381	-	-
A2	0.125	0.130	0.135	3.175	3.302	3.429
D	0.880	0.900	0.920	22.352	22.860	23.368
E	0.300			7.620		
E1	0.245	0.250	0.255	6.223	6.350	6.477
L	0.115	0.130	0.150	2.921	3.302	3.810
eB	0.335	0.355	0.375	8.509	9.017	9.525
θ°	0°	7°	15°	0°	7°	15°

## 16.4 SOP 18 PIN



SYMBOLS	MIN	NOR	MAX	MIN	NOR	MAX
	(inch)			(mm)		
A	0.093	0.099	0.104	2.362	2.502	2.642
A1	0.004	0.008	0.012	0.102	0.203	0.305
D	0.447	0.455	0.463	11.354	11.557	11.760
E	0.291	0.295	0.299	7.391	7.493	7.595
H	0.394	0.407	0.419	10.008	10.325	10.643
L	0.016	0.033	0.050	0.406	0.838	1.270
$\theta^\circ$	0°	4°	8°	0°	4°	8°

## 16.5 SSOP 20 PIN



SYMBOLS	MIN	NOR	MAX	MIN	NOR	MAX
	(inch)			(mm)		
A	0.053	0.063	0.069	1.350	1.600	1.750
A1	0.004	0.006	0.010	0.100	0.150	0.250
A2	-	-	0.059	-	-	1.500
b	0.008	0.010	0.012	0.200	0.254	0.300
c	0.007	0.008	0.010	0.180	0.203	0.250
D	0.337	0.341	0.344	8.560	8.660	8.740
E	0.228	0.236	0.244	5.800	6.000	6.200
E1	0.150	0.154	0.157	3.800	3.900	4.000
[e]	0.025			0.635		
h	0.010	0.017	0.020	0.250	0.420	0.500
L	0.016	0.025	0.050	0.400	0.635	1.270
L1	0.039	0.041	0.043	1.000	1.050	1.100
ZD	0.059			1.500		
Y	-	-	0.004	-	-	0.100
θ°	0°	-	8°	0°	-	8°

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