

HEMISSON OS MANUAL

Usage and Functions

October 2008 Edition



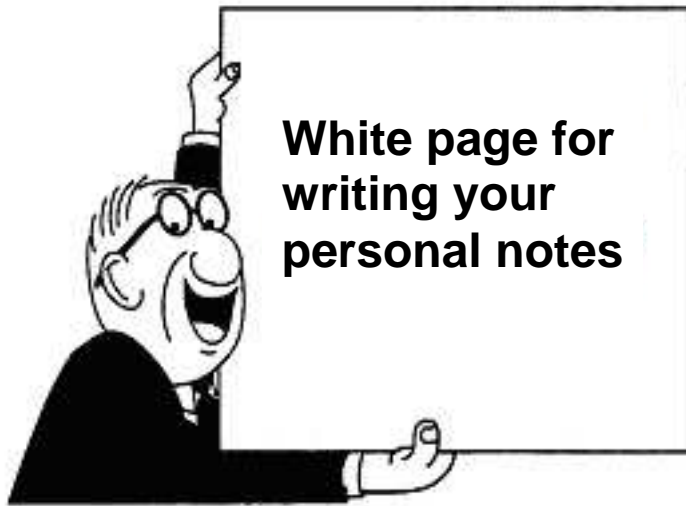
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1 – INTRODUCTION

Hemisson is provided with a processor from Microchip, the PIC16F877.

This processor is used in many applications; therefore there is already a big community with many users.

Microchip provides a free assembler for the PICs. But this low-level language is not well suitable for a fast development in robotics. It is rather a specific language for the low-level layers.

In this manual we will introduce the particular case of C language to you, which is to our opinion the most suitable.

The whole Hemisson OS (« Operating System », embedded system on the Hemisson) was developed in this language. We distribute the source codes under the LGPL license, which means that you can use it freely and without restraint (except for commercial purpose).

Let's see more in detail the programming part.

This document is suitable for people having already some basic knowledge in C language.

2 – THE COMPILER

Nowadays there are on the market many C compilers for PIC micro-processors on the market, more or less expensive but also more or less reliable.

After having tested many among others, K-Team recommends the « PCW » C compiler from CCS for its quality, support and price ratio and its multi-platforms support. It is one among the best in the market: it comprises many high-level integrated functions along with a friendly user interface.

Following commercial agreements with CCS, you can obtain a specific version of the PWC compiler, including a compiler/debugger (limited to the PIC 16F877 and 16F876) and an editor in full version.

You can obtain this version of the PCW compiler by contacting K-Team.

If you wish, you can obtain an external PIC « ICD_S » programmer to program again the microprocessor.

**Currently we do not assure any support for another C compiler.
If you already have another C compiler for PIC,
you need to adapt the source code of the « Hemisson OS ».**

3 – USAGE OF THE PIC C COMPILER

The following steps are required to install the PIC C compiler from CCS:

- create a directory « PICC » in the directory « *Program Files* » of Windows ;
- In this directory copy the licence « *pcm.crg* » you received;
- Run the setup file « *SetupPcw.exe* » you received or available in the directory « PCW CCS » of the CD-ROM « *Installation Professor* » delivered with the DIDAPACK from K-TEAM.

When the install procedure is finished, you may modify and compile the Hemisson OS as follows :

- Copy on your PC the directory « *HemissonOS_Sources* » from the CD-ROM « *Installation Professor* » (directory « *Professor / HemissonOS* » holding the sources of Hemisson OS;
- start the PIC C compiler (short-cut on the Windows desktop or in the menu bar « *Start / Programmes / PIC-C* » ;
- Click on « Project » then « Open » and select the file « *main.pjt* » in the directory « *HemissonOS / HemissonOS_Sources* » copied in your PC;
- Click on « Project » then « Open » and select the file « *main.c* » ;
- Add your code ;
- Click on the object « compile » or press the F9 key of your keyboard to compile.

If there is no error in your code, the compiler will generate a file « *main.hex* », compiled program that can be uploaded with the « *Hemisson Uploader* » into Hemisson (see next CHAPTER).

4 – USAGE OF THE HEMISSON UPLOADER

Once your program is compiled, find the file « main.hex » created by the compiler.

Use the « HEMISSON Uploader » to upload this OS (compiled program) into the « Flash » memory of the microprocessor of the Hемisson robot.

With the "HEMISSON Uploader", you can upload a program through the serial port into the microprocessor of the Hемisson robot.

The data (program uploading) sent from the "Hемisson Uploader" are processed and saved by a software named "Bootloader" that K-Team loaded into the Flash memory of the PIC when the Hемisson was assembled.

4.1 Safety usage

A bad manipulation may erase the "Bootloader" program from the memory.

In this case, the upload through the serial port will not be possible anymore (usage "HEMISSON Uploader").

If you load a program you compiled (C compiler, Assembly, etc.), make sure you respect following rule:

The memory zone from 0x1F00 to 0x1FFF ("Bootloader" reserved zone)
must never be written.

The compiled filed (".hex") issued from K-TEAM respect this rule.

If you erase by mistake this memory zone during a bad manipulation and you have an external programmer, reload the "bootloader.hex" file included in the directory "Professor / HемissonOS" of your CD-ROM (see next CHAPTER).

Refer to the « Hемisson Uploader » tutorial in « Programming tools » of the CD-ROM to do this upload.

4.2 Reloading the « BootLoader » by the means of an external programmer

If you have a serial programmer for the PIC16F876 microprocessor (« PicStart © » from Microchip or « ICD-S » from CCS for example) you can reflash the memory of the PIC of Hемisson and reload the "bootloader.hex" file included in the "Professor / HемissonOS" directory of your CD-ROM and recover the serial upload functionality.

If you have a serial programmer of the « PicStart © Plus » type from Microchip, refer to the file :
[HemChargerBootloaderPicStart.pdf](#)

If you have a serial programmer of the « ICD-S » type from CCS, refer to the file :
[HemChargerBootloaderICD.pdf](#)

5. HEMISSON OS

5.1 What's that?

We can say that:

« Hemisson OS is for Hemisson, what Windows or Linux is for your PC ».

The Hemisson OS manages the resources of Hemisson and it enables you to access the embedded hardware.

5.2 It's structure

The source code of the Hemisson OS is located in the directory « *HemissonOS / HemissonOS_Sources* » of the CD-ROM « *Installation Professor* ».

This OS is composed of several files :

- « *main.c* », main file containing the « main » ; in this file, you declare your variables, your functions and you write your code;
- « *hemisson.c* », file containing the sources of the control and access function to the Hemisson robot hardware (*) ;
- « *hemisson.h* », file containing the functions prototypes you use and the Hemisson parameters (quartz frequency, baudrate...) (*) ;
- « *16f877.h* », file containing the registers addresses of the processor (*) ;
- « *variables.c* », file containing the internal variables (*) ;
- « *constantes.h* », file containing the constants definitions (*) ;
- « *versions.txt* », description of the modifications done at every version.

(*) : these files must not be modified by “ordinary” users programming the behaviours of Hemisson, but “expert” users who would like to modify and improve the functions of « Hemisson OS ».

Other files are available in the directory « *Librairies_Modules* » for using the extension modules (I/O interface board, linear camera, etc.).

6 – FUNCTIONS

6.1 Definition

Here's a small explanation before starting with the list of the available functions for the Hemisson OS.

General notation of the available functions « $a = f(b)$; »

- a is the returned value;
- f is the function;
- b is the parameter;

Variable notations:

- **char** is a 8bits signed integer variable, 1 octet (-128 to 127) ;
- **unsigned char** is a 8 bits unsigned variable, 1 octet (0 to 255) ;
- **int1** is a bit variable (boolean, 0 or 1) ;
- **int** is a 16bits signed integer variable (-32768 to 32767) ;
- **unsigned int** is a 16bits unsigned integer variable (0 to 65535) ;
- **unsigned int16** is a 16bits unsigned integer variable (0 to 65535) ;
- **signed int8** is a 8bits signed integer variable (-128 to 127) ;

6.2 Configuration functions of the robot

void hemisson_init(**void**)

Goal : Initialize Hemisson

Parameter : None

Return : Nothing

Example : hemisson_init();

Notice : This function must be at the beginning of every program to initialize the Hemisson robot with this default configuration:

- automatic reading of the IR sensor activated
- RS232 management activated
- Automatic reading of the TV receiver activated
- TV remote control activated.

void hemisson_config_auto_refresh_sensors(**int1** Bit)

Goal : Configure the IR sensor reading

Parameter : MANUAL or REFRESH (by default)

Return : Nothing

Example : hemisson_config_auto_refresh_sensors(MANUAL);

Notice : This function configures if the automatic reading of the IR sensors are activated (parameter REFRESH) or not (parameter MANUAL).

void hemisson_config_auto_refresh_tv_remote(**int1** Bit)

Goal : Configure the automatic reading of the TV remote receiver.

Parameter : MANUAL or REFRESH (by default)

Return : Nothing

Example : hemisson_config_auto_refresh_tv_remote(MANUAL);

Notice : This function configures if the TV remote receiver is refreshing automatically (Parameter REFRESH) or not (Parameter MANUAL).

void hemisson_config_rs232_control(**int1** Bit)

Goal : Activate or note the "Serial Remote Control"

Parameter : DISABLE or ENABLE(by default)

Return : Nothing

Example : hemisson_config_rs232_control(DISABLE);

Notice : This function activates (parameter ENABLE) or not (parameter DISABLE) the RS232 "Serial Remote Control".

Warning: if this mode is activated, you can use the "printf" function (i.e. to view some values with a terminal) Goal you can't read anything from the serial port (getc, gets, etc.. are not available), all the data will be read by the "Serial Remote Control" process.

void hemisson_config_tv_remote_control(**int1** Bit)

Goal : Activate or not the "TV Remote Control" mode

Parameter : DISABLE or ENABLE(by default)

Return : Nothing

Example : hemisson_config_tv_remote_control(DISABLE);

Notice : This function activates (parameter ENABLE) or not (parameter DISABLE) the "TV Remote Control" mode (remote control of the motors with a TV remote).

6.3 « Flags » reading function

int1 hemisson_flag_sensors_refreshed(void)

Goal : To know if the IR sensors were refreshed

Parameter : None

Return : The bit is set if the sensors just have been refreshed.

Example : i = hemisson_flag_sensors_refreshed();

Notice : You must reset the flag after with the « hemisson_flag_sensors_reset » function.

void hemisson_flag_sensors_reset(void)

Goal : Reset the IR sensor flag

Parameter : None

Return : Nothing

Example : hemisson_flag_sensors_reset();

int1 hemisson_flag_rs232_filtering(void)

Goal: To know if the “Serial Remote Control” mode is activated or not

Parameter : None

Return : 1 if the mode is activated and 0 if not.

Example : i = hemisson_flag_rs232_filtering();

int1 hemisson_flag_tv_data_refreshed(void)

Goal: To know if the TV receiver was refreshed or not.

Parameter : None

Return : 1 if some data was received on the TV receiver.

Example : i = hemisson_flag_tv_data_refreshed();

Notice : You must reset the flag after with the “hemisson_flag_tv_data_reset” function.

void hemisson_flag_tv_data_reset(void)

Goal : Reset the TV receiver flag.

Parameter : None

Return : None

Example : hemisson_flag_tv_data_reset();

6.4 Input and Output functions

unsigned char hemisson_get_proximity(**char** Sensor)

Goal : Get the value of the proximity sensor

Parameter : FRONT, FRONTLEFT, FRONTRIGHT, LEFT, RIGHT, REAR, GROUNDLEFT, GROUNDRIGHT

Return : Unsigned char (0(nothing) to 255(an obstacle is very near))

Example : i = hemisson_get_proximity(FRONT); Return the proximity value of the "Front" IR sensor.

unsigned char hemisson_get_brightness(**char** Sensor)

Goal : Get the brightness value of a IR sensor.

Parameter : FRONT, FRONTLEFT, FRONTRIGHT, LEFT, RIGHT, REAR, GROUNDLEFT, GROUNDRIGHT

Return : Unsigned char (0(big luminosity) to 255(dark))

Example : i = hemisson_get_brightness(REAR); Return the brightness value of the "Rear" sensor.

int1 hemisson_get_switch_state(**char** Switch_Number)

Goal : Read the state of a switch

Parameter : 0, 1, 2 or 3 (number of the switch)

Return : 0 (switch open) ou 1 (switch closed)

Example : i = hemisson_get_switch_state(2); Return the state (0 or 1) of the superior switch number 2.

unsigned char hemisson_get_tv_data(**void**)

Goal : Get the data received on the TV receiver.

Parameter : None

Return : Unsigned char (0 à 255)

Example : i = hemisson_get_tv_data(); Return the coded value of the pressed TV remote button. i.e. the value will be 2 if the button 2 of the numeric pad is pressed.

void hemisson_set_speed(**signed int8** LeftSpeed, **signed int8** RightSpeed)

Goal : Set the speed of the motor left (first value) and right (second value)

Parameter : -15 to 15 (0 = Stop)

Return : None

Example : hemisson_set_speed(5 , -5); set a speed of +5 on the left motor and -5 on the right motor. The robot will turn on itself in this example.

Notice : The PWM command has a fixed frequency of 300Hz and variable duty cycle from 0 to 100% fixed by the consigne, where 15 set a PWM ratio of 100%.

Try to avoid the using of too big instructions (>9) to keep a reasonable consumption and keep a good autonomy.

void hemisson_beep(int1 State)

Goal : Make a continuous sound with the « Buzzer »

Parameter : ON (1) or OFF (0)

Return : None

Example : hemisson_beep(ON); Activate the « Buzzer » of the Hemisson.

void hemisson_led_frontright(int1 State)

Goal : turn ON or OFF the LED “Front Left”

Parameter : ON (1) or OFF (0)

Return : None

Example : hemisson_led_frontright(ON); Turn ON the “Front Left” LED of the robot.

void hemisson_led_frontright(int1 State)

Goal : turn ON or OFF the LED “Front Right”

Parameter : ON (1) or OFF (0)

Return : None

Example : hemisson_led_frontright(ON); Turn ON the “Front Right” LED of the robot.

void hemisson_led_pgmexec(int1 State)

Goal : turn ON or OFF the LED « Pgm »

Parameter : ON (1) or OFF (0)

Return : None

Example : hemisson_led_pgmexec(ON); Turn ON the « Pgm » of the robot.

void hemisson_led_onoff(int1 State)

Goal : turn ON or OFF the LED « On/Off »

Parameter : ON (1) or OFF (0)

Return : None

Example : hemisson_led_onoff(ON); Turn ON the « On/Off » of the robot.

void hemisson_manual_refresh_sensors(char Zone)

Goal : Refresh manually an area of sensor.

Parameter : FRONTZONE (sensors « Front », « Front Right » and « Front Left » ;

REARZONE (sensors « Right », « Left » et « Rear ») ;

GROUNDZONE (Sensors « Ground Right » et « Ground Left »).

Return : None

Example : hemisson_manual_refresh_sensors(GROUNDZONE); refresh the value of the ground sensors.

Notice : This function can read only one area (saving time) of IR sensors, and is useful only after disabling the automatic refresh sensor mode with the function

« hemisson_config_auto_refresh_sensors ».

Then use one of the two functions to read the IR sensors (« hemisson_get_proximity » or « hemisson_get_brightness »).

6.5 Delay and « Timer » functions

void hemisson_delay_s(**unsigned int** Delay)

Goal : Put a delay in second (temporization).

Parameter : Time to wait in seconds (0 to 65535)

Return : None

Example : hemisson_delay_s(120); Wait 2 minutes.

void hemisson_delay_ms(**unsigned int** Delay)

Goal : Put a delay in millisecond (temporization).

Parameter : Time to wait in ms (0 to 65535)

Return : None

Example : hemisson_delay_ms(5000); Wait 5s.

void hemisson_delay_us(**unsigned int** Delay)

Goal : Put a delay in microsecond (temporization).

Parameter : Time to wait in us (0 to 65535)

Return : None

Example : hemisson_delay_us(500); wait 500 us.

A 32 bits timer provides the time (in millisecond) elapsed since the robot is turned on.

unsigned int32 hemisson_get_time(**void**)

Goal : Get the value of the elapsed time in ms.

Parameter : None

Return : Unsigned int32 (0 to 4294967295)

Example : Timer = hemisson_get_time(); Timer = elapsed time in ms.

void hemisson_set_time(**unsigned int32** Time)

Goal : Initialize or force the elapsed time of the timer for the « hemisson_get_time » function.

Parameter : Unsigned int32 (0 to 4294967295)

Return : None

Example : hemisson_set_time(0); Initialize the timer to 0 ms.

6.6 I/O functions of the external connectors

int1 hemisson_ext_read_PINB0(**void**)

Goal : Read the digital Input/Output RB0 of the microcontroller.

Parameter : None

Return : 0 or 1

Example : `i = hemisson_ext_read_PINB0();` Return the state (0 or 1) of RB0 pin.

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

int1 hemisson_ext_read_PINB6(**void**)

Goal : Read the digital Input/Output RB6 of the microcontroller.

Parameter : None

Return : 0 or 1

Example : `i = hemisson_ext_read_PINB6();` Return the state (0 or 1) of RB6 pin.

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

int1 hemisson_ext_read_PINB7(**void**)

Goal : Read the digital Input/Output RB7 of the microcontroller.

Parameter : None

Return : 0 or 1

Example : `i = hemisson_ext_read_PINB7();` Return the state (0 or 1) of RB7 pin.

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

void hemisson_ext_write_PINB0(**int1** Bit)

Goal : Set the value of the digital output RB0 of the microcontroller.

Parameter : 0 or 1

Return : None

Example : `i = hemisson_ext_write_PINB0(1);` set the RB0 pin to 1 (+5V)

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

void hemisson_ext_write_PINB6(**int1** Bit)

Goal : Set the value of the digital output RB6 of the microcontroller.

Parameter : 0 or 1

Return : None

Example : `i = hemisson_ext_write_PINB6(1);` set the RB6 pin to 1 (+5V)

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

void hemisson_ext_write_PINB7(**int1** Bit)

Goal : Set the value of the digital output RB7 of the microcontroller.

Parameter : 0 or 1

Return : None

Example : `i = hemisson_ext_write_PINB7(1);` set the RB7 pin to 1 (+5V)

Notice : This Input/Output is connected to the external connector "Power supply and I²C Bus" (see Hemisson schematics).

6.7 Real time tasks

Some functions which are called every 40ms are available for your software to realize different real time tasks in addition to the real time monitor (« scheduler ») used in the Hemisson OS.

To use it, put your code in these functions:

`void hemisson_task1(void)` , `void hemisson_task2(void)` ,

`void hemisson_task3(void)` and `void hemisson_task4(void)`,

available in the these four files « `hemisson_task1.c` », « `hemisson_task2.c` », « `hemisson_task3.c` » and « `hemisson_task4.c` » of the Hemisson OS.

Be careful, the time of each task must not be bigger than 200 µs

6.8 C compiler specific functions

Like any C compiler, the CCS compiler has a very big set of functions in addition of the « ANSY » functions, like the I²C bus access, random number generation, delay, etc...

You can find the details of these functions in the user manual of the CCS compiler.

7 – EXAMPLES

Many examples with comments are available (free to use in your project) in the « *HemissonOS/HemissonOS_Sources/Examples* » directory of the CD-rom.

A RTF file « *HemissonGlossaireFonctionsC.rtf* » are available too in the « *HemissonOS/HemissonOS_Sources* » directory, it allows you to quickly choose the needed function and to copy it to your code (See the C compilation tutorial in the « *programming tools* » Section of the CD-rom.

8 – MODULES LIBRARIES

8.1 Definition

In your own Hemisson OS code, you can use some management and access functions of the turrets (GenIO, LinCam, USsensor, etc..) via the I²C bus of the Robot.

These functions are defined in the « **.h* » files available in the « *HemissonOS/HemissonOS_Sources/Librairies_Modules* » directory of the CD-rom.

These libraries for the management and access functions are located in the different sub-directories with the same summary denomination as the turret. « *GenIO* » e.g. for the Input Output module.

These directories contain the following files:

- « *Hemxx.h* », file having the sources and the define of the turret access function.
- « *Example_xx.c* », file containing an example of turret utilisation and explanation to use it in your project.

To use these functions in your project, place the "Hemxx.h" of the turret in your project directory and add « *#include Hemxx.h* » in your « *main.c* » projectfile.

8.2 Functions of the « I/O interface board » module

void HemGenIO_Init(**void**)

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemGenIO_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the GenIO turret.

char HemGenIO_Read_Version(**void**)

Goal : Read the firmware version (OS) of the GenIO turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (Firmware version number)

Example : NumVer = HemGenIO_Read_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged.

int1 HemGenIO_Read_Digital(**char** Input)

Goal : Read the state of a digital Input.

Parameter : 0 to 11 (digital input number)

Return : 0 or 1 (state of the digital input)

Example : EtatD2 = HemGenIO_Read_Digital(2); Return the state of the digital input n^o2.

Notice : This function will automatically configure the selected I/O as a Input.

void HemGenIO_Write_Digital(**char** Output , **int1** State)

Goal : Set the the state of a digital output of the turret.

Parameter1 : 0 to 11 (digital output number)

Parameter2 : 0 or 1 (State of the selected output)

Return : None

Example : HemGenIO_Write_Digital(9, 1); Set the digital ouput n^o9 to +5V.

Notice : This function will automatically configure the selected I/O as an Output

unsigned char HemGenIO_Read_Analog(**char** Input)

Goal : Read the value of an analog Input

Parameter : 0 to 4 (Analog input number)

Return : Unsigned int8 (0 = 0V and 255 = 5V)

Example : ValueA3 = HemGenIO_Read_Analog(3); Return the analog value of the input number 3. (i.e. if ValueA3 = 150, Voltage of A3 = $150 \times 5 / 255 = 2.94V$).

8.3 Functions of the « Ultrasonic detector» module

void HemUltraSon_Init(**void**)

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemUltraSon_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the USsensor turret

char HemUltraSon_Read_Version(**void**)

Goal : Read the firmware version (OS) of the USsensor turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (Firmware version number)

Example : NumVer = HemUltraSon_Read_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged.

unsigned char HemUltrason_Read_Brightness(**void**)

Goal : read the value of the brightness sensor

Parameter : None

Return : Unsigned int8.

Example : Lum = HemUltraSon_Read_Brightness(); Return the analog value of the brightness sensor.

void HemUltraSon_Start_Mesure(**void**)

Goal : Start a distance acquisition.

Parameter : None

Return : None

Example : HemUltraSon_Start_Mesure();

Notice : This function includes a delay of 65ms (emitting and receiving time of the Ultrasons).

unsigned int16 HemUltrason_Read_Value(**char** EchoNumber)

Goal : Read the distance value of the selected Echo (unit cm)

Parameter : 0 to 7 (Number of the Echo)

Return : Unsigned int16(0 to 65535)

Example : Dist1 = HemUltraSon_Read_Value(0); Return the centimetre distance of the first echo.

void HemUltraSon_Init_Range_Register(**unsigned char** Value)

Goal : Initialize the maximal range of the sensor.

Parameter : unsigned int16 (0 to 65535)

Return : None

Example : HemUltraSon_Init_Range_Register (24); maximal range distance limited to 1075 mm (see the calculation below)

Notice : The maximum range in mm is defined by:

$$D_{max} = (\text{Parameter} \times 43\text{mm}) + 43 \text{ mm} ;$$

$$1\ 075\text{mm} = (24 \times 43\text{mm}) + 43\text{mm} \text{ for the example.}$$

The echo beyond this value will return 0.

8.4 Functions of the « Linear camera » module

The sensor of the linear camera is composed of 3 detection areas which hold 34 pixels each with 256 grey levels.

The pixels value (grey levels 0 to 255) of each area is defined in different tables of 34 unsigned int8 values as follows:

```
unsigned char HemLinCam_Pixels_Zone1[34] ;
```

```
unsigned char HemLinCam_Pixels_Zone2[34] ;
```

```
unsigned char HemLinCam_Pixels_Zone3[34] ;
```

To use in your code to have access to the pixels value .

```
void HemLinCam_Init( void )
```

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemLinCam_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the LinCam turret.

```
char HemLinCam_Read_Version( void )
```

Goal : Read the firmware version (OS) of the LinCam turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (« Firmware » version number)

Example : NumVer = HemLinCam_Read_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged..

```
void HemLinCam_Set_Threshold( unsigned char Value )
```

Goal : Define the threshold value for the pixels reading.

Parameter : Unsigned int8 (0 to 255)

Return : None

Example : HemLinCam_Set_Threshold(100); Define the Threshold to 100

Notice : When the pixels threshold reading is made, the pixels with a grey level >= than 100 will have a value of 255 and the other (< 100) will reset to 0.

```
unsigned char HemLinCam_Read_Threshold( void )
```

Goal : read the setting threshold value.

Parameter : None

Return : Unsigned int8 (0 to 255)

Example : Seuil = HemLinCam_Read_Threshold();

```
void HemLinCam_Set_Exposition_Time( unsigned char Value )
```

Goal : Define the exposure time in ms.

Parameter : 1 to 10

Return : None

Example : HemLinCam_Set_Exposition_Time (2);

Notice : Warning with the too big value, the pixels will be saturate very fast.

unsigned char HemLinCam_Read_Exposition_Time(**void**)

Goal : read the exposure time.

Parameter : None

Return : Unsigned int8 (0 to 255)

Example : ExpoMs = HemLinCam_Read_Exposition_Time (); Return the exposure time in ms.

void HemLinCam_Read_Pixels(**void**)

Goal : Read the value of every pixels.

Parameter : None

Return : None

Example : HemLinCam_Read_Pixels() ;
// Reading of the pixel n°17 of the central area
If (HemLinCam_Pixels_Zone2[17] > 20)
{ ... }

Notice : After the reading, the values are stocked in the different value tables:

« HemLinCam_Pixels_Zone1 », « HemLinCam_Pixels_Zone2 » and « HemLinCam_Pixels_Zone3 ».

Each table has a size of 34 pixels, which correspond respectively to the left, central and right of the picture.

void HemLinCam_Read_Pixels_Tresholded(**void**)

Goal : Read the value of every pixel after the threshold

Parameter : None

Return : None

Example : HemLinCam_Read_Pixels_Tresholded () ;
// Reading of the thresholded pixel n°17 of the central area
If (HemLinCam_Pixels_Zone2[17] == 255)
{ ... }

Notice : After the reading, the values are stocked in the different value tables:

« HemLinCam_Pixels_Zone1 », « HemLinCam_Pixels_Zone2 » and « HemLinCam_Pixels_Zone3 ».

Each table has a size of 34 pixels, which correspond respectively to the left, central and right of the picture.

When the pixels threshold reading is made, the pixels with a grey level >= than the threshold will have a value of 255 and the other (< threshold) will reset to 0.

void HemLinCam_Set_Led_State(**int1** State)

Goal : Turn On or Off the Led

Parameter : ON (1) or OFF (0)

Return : None

Example : HemLinCam_Set_Led_State (ON); Turn On the camera LED.

8.5 Functions of the « Vocal synthesizer» module

void HemTextToSpeech_Init(**void**)

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemTextToSpeech_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the TextToSpeech turret

char HemTextToSpeech_Version(**void**)

Goal : Read the firmware version (OS) of the TextToSpeech turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (« Firmware » version number)

Example : NumVer = HemTextToSpeech_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged..

void HemTextToSpeech_Speed(**char** Value)

Goal : Define the speed teechting

Parameter : Unsigned int8 (0 to 255)

Return : None

Example : HemTextToSpeech_Speed(1);

Notice : Set a small value to speak the sentence slowly.

void HemTextToSpeech_Pitch(**char** Value)

Goal : Define the « pitch » value (hue of the pronunciation).

Parameter : Unsigned int8 (0 to 255).

Return : None

Example : HemTextToSpeech_Pitch(2);

Notice : Set a small value to speak the sentence high-pitched.

void HemTextToSpeech_Speak(**char** Phrase[], **char** Taille)

Goal : Play a loaded sentence.

Parameter 1 : Character table which contains the sentence to speak in text format.

Parameter 2 : Size of the sentence to speak, in a unsigned int8 value (0 to 255)

Return : None

Example : **char** Phrase[256];

 sprintf(Phrase, "Hello, my name is hemisson");

 HemTextToSpeech_Speak(Phrase, sizeof(Phrase));

Notice : The sentence « Hello, my name is hemisson » is speak in function of the speed and the pitch settings

void HemTextToSpeech_Speak_PreDef(**char** Num)

Goal : Speak a sentence which is saved in the turret.

Parameter : Number of the saved sentence to speak (0 to 32)

Return : None

Example : HemTextToSpeech_Speak_PreDef(20);

Notice : Speak the saved sentence number 20 which is loaded with the « SP03.exe » software (see EMP).

8.6 Functions of the « LCD screen» module

The LCD screen turret is made up a screen of 2 lines of 12 characters each and 3 push button. The text for each line is define by two characters table of 12 bytes:

```
char Line1[12] ;
```

```
char Line2[12] ;
```

The state of the push button is stocked in the following variable:

```
int1 SW1, SW2, SW3 ;
```

```
void HemLCD_Init( void )
```

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemLCD_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the LinCam turret

```
char HemLCD_Read_Version( void )
```

Goal : Read the firmware version (OS) of the LCD turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (« Firmware » version number)

Example : NumVer = HemLCD_Read_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged..

```
void HemLCD_Set_Backlight( unsigned char Value )
```

Goal : Define the back light intensity of the screen.

Parameter : Unsigned int8 (0 to 255 = 0 to 100%)

Return : None

Example : HemLCD_Set_Backlight(20); define the back light to 20 (= 8%)

```
void HemLCD_Set_Contrast( unsigned char Value )
```

Goal : Define the contrast level of the display.

Parameter : Unsigned int8 (0 to 255 = 0 to 100% of the maximal contrast)

Return : None

Example : HemLCD_Set_Contrast(200); define the contrast to 200 (= 80%)

Notice : below 150, the characters display are no more visible with a too small back light. The contrast value must adapt according to the back light.

```
void HemLCD_Clear_Screen( void )
```

Goal : Clear the screen

Parameter : None

Return : None

Example : HemLCD_Clear_Screen(); clear all the word display on the screen.

void HemLCD_Clear_Line1(**void**)

Goal : Clear the line 1

Parameter : None

Return : None

Example : HemLCD_Clear_Line1();

void HemLCD_Clear_Line2(**void**)

Goal : Clear the line 2

Parameter : None

Return : None

Example : HemLCD_Clear_Line2();

void HemLCD_Read_Interruptors(**void**)

Goal : Read the value of the 3 push-button.

Parameter : None

Return : None

Example : HemLCD_Read_Interruptors ();

Notice : The state of the 3 push-buttons are put in the variables SW1, SW2 and SW3.

void HemLCD_Line1_Left(**char*** Data)

Goal : Display the line 1 aligned on the left.

Parameter : Table of character, use the table of the Line1

Return : None

Example : strcpy(Line1, "MENU"); define the content of the Line1 table.

HemLCD_Line1_Left(Line1); Display the « MENU » text aligned on the left of the Line 1.

Notice : You must use the predefined characters table of Line1 and Line2.

void HemLCD_Line1_Centered(**char*** Data)

Goal : Display the Line1 centered

Parameter : Table of character, use the table of the Line1

Return : None

Example : strcpy(Line1, "MENU"); define the content of the Line1 table.

HemLCD_Line1_Centered(Line1); Display the « MENU » text centered of the Line 1.

Notice : You must use the predefined characters table of Line1 and Line2.

void HemLCD_Line1_Right(**char*** Data)

Goal : Display the line 1 aligned on the right

Parameter : Table of character, use the table of the Line1

Return : None

Example : strcpy(Line1, "MENU"); define the content of the Line1 table.

HemLCD_Line1_Right(Line1); Display the « MENU » text aligned on the right of the Line 1.

Notice : You must use the predefined characters table of Line1 and Line2.

void HemLCD_Line2_Left(**char*** Data)

Goal : Display the line 2 aligned on the left.

Parameter : Table of character, use the table of the Line2

Return : None

Example : strcpy(Line2, "MENU"); define the content of the Line2 table.

HemLCD_Line2_Left(Line2); Display the « MENU » text aligned on the left of the Line 2.

Notice : You must use the predefined characters table of Line1 and Line2.

void HemLCD_Line2_Centered(**char*** Data)

Goal : Display the Line2 centered

Parameter : Table of character, use the table of the Line2

Return : None

Example : strcpy(Line2, "MENU"); define the content of the Line2 table.

HemLCD_Line2_Centered(Line2); Display the « MENU » text centered of the Line 2.

Notice : You must use the predefined characters table of Line1 and Line2.

void HemLCD_Line2_Right(**char*** Data)

Goal : Display the line 2 aligned on the right

Parameter : Table of character, use the table of the Line2

Return : None

Example : strcpy(Line2, "MENU"); define the content of the Line2 table.

HemLCD_Line2_Right(Line2); Display the « MENU » text aligned on the right of the Line 2.

Notice : You must use the predefined characters table of Line1 and Line2.

8.7 Functions of the « Gripper» module

void HemGripper_Init(**void**)

Goal : Initialize the turret

Parameter : None

Return : None

Example : HemGripper_Init();

Notice : It's the first function to call at the beginning of your Code to initialize the Gripper turret

char HemGripper_Read_Version(**void**)

Goal : Read the firmware version (OS) of the Gripper turret connected on the I²C Bus

Parameter : None

Return : Unsigned int8 (« Firmware » version number)

Example : NumVer = HemGripper_Read_Version();

Notice : This function can be used to verify the presence of the turret. If 0xFF is returned then no turret is plugged..

Unsigned int16 HemGripper_Read_Arm_Position(**void**)

Goal : Read the position of the Arm (0-7000)

Parameter : None

Return : Unsigned int16

Example : Position = HemGripper_Read_Arm_Position();

Unsigned int16 HemGripper_Read_Gripper_Position(**void**)

Goal : Read the position of the Gripper (0-5100)

Parameter : None

Return : Unsigned int16

Example : Position = HemGripper_Read_Gripper_Position();

Unsigned int16 HemGripper_Read_Arm_Consign(**void**)

Goal : Read the position consign of the Arm (0-7000)

Parameter : None

Return : Unsigned int16

Example : Consign = HemGripper_Read_Arm_Consign();

Unsigned int16 HemGripper_Read_Gripper_Consign(**void**)

Goal : Read the position consign of the Gripper (0-5100)

Parameter : None

Return : Unsigned int16

Example : Consign = HemGripper_Read_Gripper_Consign();

Unsigned char HemGripper_Read_Arm_Speed(**void**)

Goal : Read the speed of the Arm used for the consign movements (0-255)

Parameter : None

Return : Unsigned char

Example : Speed = HemGripper_Read_Arm_Speed();

Unsigned char HemGripper_Read_Gripper_Speed(void)

Goal : Read the speed of the Gripper used for the consign movements (0-255)

Parameter : None

Return : Unsigned char

Example : Speed = HemGripper_Read_Gripper_Speed();

Unsigned char HemGripper_Read_Arm_Disable(void)

Goal : Read the flag which indicate if the Arm must be turn off or not when a stable position is reach

Parameter : None

Return : Unsigned char

Example : Flag = HemGripper_Read_Arm_Disable();

Unsigned char HemGripper_Read_Gripper_Disable(void)

Goal : Read the flag which indicate if the Gripper must be turn off or not when the open position is reach

Parameter : None

Return : Unsigned char

Example : Flag = HemGripper_Read_Gripper_Disable();

Unsigned int16 HemGripper_Read_Battery_Voltage(void)

Goal : Read the Voltage level of the battery

Parameter : None

Return : Unsigned int16

Example : Voltage = HemGripper_Read_Battery_Voltage();

Unsigned char HemGripper_Read_Battery_Capacity(void)

Goal : Read the value of the available remaining capacity of the Battery

Parameter : None

Return : Unsigned char

Example : Capacity = HemGripper_Read_Battery_Capacity();

void HemGripper_Set_Arm_Position(unsigned int16 value)

Goal : Set the Arm position to reach without speed control

Parameter : unsigned int16

Return : None

Example : HemGripper_Set_Arm_Position(1500);

void HemGripper_Set_Gripper_Position(unsigned int16 value)

Goal : Set the Gripper position to reach without speed control

Parameter : unsigned int16

Return : None

Example : HemGripper_Set_Gripper_Position(1500);

void HemGripper_Set_Arm_Consign(**unsigned int16** value)

Goal : Set the Arm position to reach using the speed defined with the Hemisson_Set_Arm_Speed() function.

Parameter : unsigned int16

Return : None

Example : HemGripper_Set_Arm_Consign(500);

void HemGripper_Set_Gripper_Consign(**unsigned int16** value)

Goal : Set the Gripper position to reach using the speed defined with the Hemisson_Set_Gripper_Speed() function.

Parameter : unsigned int16

Return : None

Example : HemGripper_Set_Gripper_Gripper(1500);

void HemGripper_Set_Arm_Speed(**unsigned char** value)

Goal : Configure the speed to use for a Arm movement with speed control

Parameter : unsigned char

Return : None

Example : HemGripper_Set_Arm_Speed(100);

void HemGripper_Set_Gripper_Speed(**unsigned char** value)

Goal : Configure the speed to use for a Gripper movement with speed control

Parameter : unsigned char

Return : None

Example : HemGripper_Set_Gripper_Speed(50);

void HemGripper_Arm_Disable(**unsigned char** value)

Goal : Configure the flag to define if the Arm must turn off its motor when a stable Position is reach.

Parameter : unsigned char

Return : None

Example : HemGripper_Arm_Disable(0);

void HemGripper_Gripper_Disable(**unsigned char** value)

Goal : Configure the flag to define if the Gripper must turn off its motor when a stable Position is reach.

Parameter : unsigned char

Return : None

Example : HemGripper_Gripper_Disable(1);

APPENDIX

All the described functions in this manual are summarised in the « HemissonCFunctionsGlossary.rtf » file in a RTF format available in the « *HemissonOS/HemissonOS_Sources* » directory of the Cd-rom « Professor Installation » which you have copy in your PC.

You can easily choose the needed functions and copy them to your code (See the C compilation tutorial in the « Programming tools » section of the CD-Rom.

Use the EMP given with your Hemisson, a tutorial will help you to realize your first C language Software.



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