

C Codes for 8051

Example codes for the classical Intel-8051 (mcu51) microcontroller core. Tested using sdcc open source compiler and stc12 device.

Codes for NMK322

Testing IR module and HC-SR04 ultrasonic sensor module.

test0.c

```
/*-----*/
-----*/
#include "uart.h"
#include "timer.h"
#define FPSIZE 2
#include "utils_float.h"
#define _LCD_4BIT_INTERFACE_
/** DB4-DB7 => P0 (UPPER NIBBLE) */
/** E => P0.2 : NEEDS -ve EDGE */
/** R/W => P0.1 : 0=WR 1=RD */
/** RS => P0.0 : 0=CMD 1=DAT */
#include "textlcd.h"
/*-----*/
-----*/
/**
 * Testing IR module and HC-SR04 ultrasonic sensor module
 * - display on both uart and lcd
 */
/*-----*/
-----*/
MY1SBIT(IRMOD,PIN10);
MY1SBIT(TRIG,PIN16);
MY1SBIT(ECHO,PIN17);
/*-----*/
-----*/
MY1SBIT(TEST_IR,PIN14);
MY1SBIT(TEST_HC,PIN15);
/*-----*/
-----*/
#define FLAG_IR 0x01
#define FLAG_HC 0x02
/*-----*/
-----*/
void main(void) {
    unsigned char wait;
```

```
unsigned int tval, loop, flag;
float fval, dist;
char buff[16];
uart_init();
uart_puts("\r\nTESTING NMK322 STUFFS\r\n");
lcd_init();
lcd_goto_line1();
lcd_puts("TESTKIT 4 NMK322");
timer_init();
flag = 0;
while (1) {
    if (TEST_IR==0) {
        if ((flag&FLAG_IR)==0) {
            lcd_goto_line1();
            lcd_puts("TEST 4 IR MODULE");
            uart_puts("\r\nTESTING IR MODULE\r\n");
            flag = FLAG_IR;
        }
        lcd_goto_line2();
        lcd_puts("                ");
        lcd_goto_line2();
        lcd_puts("Waiting... ");
        uart_puts("\r\nWaiting... ");
        while (IRMOD); // outputs logic low when obstacle detected
        lcd_puts("|*");
        uart_puts("|*");
        while (!IRMOD);
        lcd_puts("|");
        uart_puts("| \r\n");
        for (loop=65000; loop; loop--);
    }
    if (TEST_HC==0) {
        if ((flag&FLAG_HC)==0) {
            lcd_goto_line1();
            lcd_puts("TEST HC-SR04 MOD");
            uart_puts("\r\nTESTING HC-SR04 MODULE\r\n");
            flag = FLAG_HC;
        }
        lcd_goto_line2();
        lcd_puts("                ");
        lcd_goto_line2();
        timer_prep(0);
        TRIG = 1;
        for (wait=10; wait; wait--); // around 10us?
        TRIG = 0;
        while (!ECHO); timer_exec();
        while (ECHO); timer_stop();
        tval = ((unsigned int)TH0<<8)|TL0;
        fval = (float)tval * 1.085; // in us
        dist = fval / 58.0; // in cm
        lcd_puts("Dist:");
    }
}
```

```

        uart_puts("-- Distance=");
        float2str(buff,dist);
        lcd_puts(buff);
        lcd_puts("cm");
        uart_puts(buff);
        uart_puts(" cm\r\n");
        for (loop=65000;loop;loop--);
    }
}
}
/*-----*/
-----*/

```

Testing HC06 bluetooth module and TowerPro MG996R servo.

test1.c

```

/*-----*/
-----*/
#define BTNAME "nmk322bt"
#define BTPASS "0000"
#include "hc06.h"
#include "timer.h"
#include "utils.h"
/*-----*/
-----*/
/**
 * Testing HC06 bluetooth module and TowerPro MG996R servo
 * - note: servo pin (1|orange:PWM)(2|red:vcc)(3|brown:ground)
 */
/*-----*/
-----*/
MY1SBIT(SERVO,PIN10);
MY1SBIT(CHECK,PIN12);
MY1SBIT(G0000,PIN16);
MY1SBIT(G0180,PIN17);
/*-----*/
-----*/
void pwm_cycle(unsigned char wide) {
    unsigned char full;
    full = 200-wide;
    SERVO = 1;
    while (wide) {
        timer_wait(0xffa3); // 0.1ms
        wide--;
    }
    SERVO = 0;
    while (full) {

```

```
        timer_wait(0xffa3); // 0.1ms
        full--;
    }
}
/*-----*/
-----*/
void servo_turn(unsigned char wide) {
    unsigned char tlen;
    tlen = 50; /* times 20ms? */
    while (tlen>0) {
        pwm_cycle(wide);
        tlen--;
    }
}
/*-----*/
-----*/
void main(void) {
    __xdata mylatcmd_t hc06;
    unsigned char curr;
    SERVO = 0; CHECK = 0; G0000 = 1; G0180 = 1;
    uart_init();
    timer_init();
    do {
        hc06_init(&hc06);
    } while (hc06_ok(&hc06)==0);
    hc06_setname(&hc06);
    hc06_setpin(&hc06);
    CHECK = 1;
    while (1) {
        if (uart_peek()) {
            if (hc06_wait(&hc06)==0) {
                if (hc06.buff[0]=='#') {
                    curr = (unsigned char) str2uint(&hc06.buff[1]);
                    if (curr>=5&&curr<=25) {
                        uart_puts("## Turning to (");
                        uart_puts(&hc06.buff[1]);
                        uart_puts(")\r\n");
                        servo_turn(curr);
                    } else {
                        uart_puts("*** Invalid angle (");
                        uart_puts(&hc06.buff[1]);
                        uart_puts(")\r\n");
                    }
                }
            } else {
                uart_puts(">> ");
                uart_puts(hc06.buff);
                uart_puts("\r\n");
            }
        }
    }
    if (G0000==0) {
```

```

        servo_turn(10); // 1ms pwm
        while (!G0000);
    }
    if (G0180==0) {
        servo_turn(20); // 2ms pwm
        while (!G0180);
    }
}
/*-----*/
-----*/

```

Code: relay

Testing basic relay.

relay.c

```

/*-----*/
-----*/
#include "timer.h"
#include "uart.h"
/*-----*/
-----*/
MY1SBIT(DRIVE,PIN20);
MY1SBIT(INPUT,PIN10);
/*-----*/
-----*/
void main(void) {
    unsigned char wait;
    timer_init();
    uart_init();
    uart_puts("\nTESTING RELAY\n");
    DRIVE = 1; /* active low */
    INPUT = 1;
    while(1) {
        if (INPUT==0) {
            uart_puts("-- Switch ON... ");
            DRIVE = 0;
            wait = 3*TIMER_LOOP_1S;
            do { timer_wait(TIMER_VAL50MS); } while (--wait);
            uart_puts("OFF.\n");
            DRIVE = 1;
            while (!INPUT);
        }
    }
}

```

```
/*-----  
-----*/
```

Code: gtuc51

Test code for the old GTUC51B001 development board.

gtuc51.c

```
/*-----  
-----*/  
/**  
 * Demo program for gtuc51 (with io board)  
**/  
/*-----  
-----*/  
#include "adc0831.h"  
#include "keypad_922.h"  
#include "textlcd.h"  
#include "utils_float.h"  
/*-----  
-----*/  
/**  
 * Switch & LED Interface for gtuc51 i/o board  
 * - multiplexed (dual/purpose)  
 * - require jumper link settings!  
**/  
/** SW0, SW1 => P3.3, P3.2 - LAYOUT ERROR */  
__sbit __at (0xB3) SW0;  
__sbit __at (0xB2) SW1;  
/** LED{0-3} => P3.4-P3.7 */  
__sbit __at (0xB4) LED0;  
__sbit __at (0xB5) LED1;  
__sbit __at (0xB6) LED2;  
__sbit __at (0xB7) LED3;  
/** LED{RX,TX} => P3.1, P3.0 - LAYOUT ERROR */  
__sbit __at (0xB1) LEDRX;  
__sbit __at (0xB0) LEDTX;  
/** alias LEDX=-2 and LEDY=-1 (LEFT OF LED0) */  
__sbit __at (0xB1) LEDX;  
__sbit __at (0xB0) LEDY;  
/*-----  
-----*/  
char display[LCD_MAX_CHAR];  
unsigned char lcdi, loop;  
float value;  
keybyte_t keyin;
```

```

adcbyte_t check;
__bit adc, adcgo, left, demo;
/*-----*/
-----*/
#define DEMO_I0 1
#define DEMO_ADC 0
/*-----*/
-----*/
#define LOOP_COUNT 20
/*-----*/
-----*/
/* interrupt service routine for timer0 */
void timer_blink(void) __interrupt TF0_VECTOR {
    TR0 = 0; loop--;
    P1 = ~P1;
    if (loop==0) {
        if (!left) {
            loop = LED0; LED0 = LED1; LED1 = LED2; LED2 = LED3;
            LED3 = LEDX; LEDX = LEDY; LEDY = loop;
        }
        else {
            loop = LED3; LED3 = LED2; LED2 = LED1; LED1 = LED0;
            LED0 = LEDY; LEDY = LEDX; LEDX = loop;
        }
        loop = LOOP_COUNT;
    }
    TH0 = 0x4B; TL0 = 0xFD; TR0 = 1; /** 50ms */
}
/*-----*/
-----*/
/* interrupt service routine for timer1 */
void timer_goadc(void) __interrupt TF1_VECTOR {
    TR1 = 0; TH1 = 0x4B; TL1 = 0xFD;
    if (loop>0) {
        TR1 = 1; /** 50ms */
        loop--;
    }
    else {
        loop = LOOP_COUNT;
        adcgo = adc;
    }
}
/*-----*/
-----*/
/* interrupt service routine for int1 */
void check_switch0(void) __interrupt IE1_VECTOR {
    left = 0;
    if (lcdi<LCD_MAX_CHAR) {
        lcd_data(0x30);
        lcdi++;
    }
}

```

```
}
/*-----*/
-----*/
/* interrupt service routine for int0 */
void check_switch1(void) __interrupt IE0_VECTOR {
    left = 1;
    if (lcdi < LCD_MAX_CHAR) {
        lcd_data(0x31);
        lcdi++;
    }
}
/*-----*/
-----*/
/* main function */
void main(void) {
    /** initialize stuffs */
    demo = DEMO_IO; /* default... just in case */
    TMOD = 0x11; P1 = 0xFF; P3 = 0xFF;
    lcd_init();
    lcd_goto_line1();
    lcd_puts("8051 Select Demo");
    lcd_goto_line2();
    lcd_puts("[SW0]IO [SW1]ADC");
    /* wait for user key press */
    while (1) {
        if (!SW0) {
            demo = DEMO_IO; /* demo switch, led, keypad and P1 */
            while(!SW0); /* wait until the user press & let go */
            break;
        }
        else if (!SW1) {
            demo = DEMO_ADC; /* demo adc */
            while(!SW1);
            break;
        }
    }
    /* select! */
    if (demo == DEMO_IO) {
        lcd_goto_line1();
        lcd_puts("MY18051 I/O DEMO");
        lcd_goto_line2();
        lcd_puts("                ");
        lcd_goto_line2();
        /** set timer 0 overflow every 50ms - with interrupt handler */
        loop = LOOP_COUNT; lcdi = 0; left = 0;
        P1 = 0xAA; LED0 = 0; IT0 = 1; IT1 = 1;
        EA = 1; ET0 = 1; EX0 = 1; EX1 = 1;
        TH0 = 0x4B; TL0 = 0xFD; TR0 = 1;
        /** main loop */
        while (1) {
            keyin = key_wait_922();

```

```

        if (keyin<10&&lcdi<LCD_MAX_CHAR) { /** numeric key! */
            lcd_data(keyin+0x30);
            lcdi++;
        }
        else if(keyin==0x0F) { /** '#' key! */
            lcd_goto_line2();
            lcd_puts("HASHED!          ");
            lcd_goto_line2();
            lcdi = LCD_MAX_CHAR;
        }
        else if(keyin==0x0E) { /** '*' key! */
            lcd_goto_line2();
            lcd_puts("          ");
            lcd_goto_line2();
            lcdi = 0;
        }
    }
}
else {
    lcd_goto_line1();
    lcd_puts("MY18051 ADC DEM0");
    lcd_goto_line2();
    lcd_puts("SW0:ADC, SW1:CLR");
    /* initialize adc */
    adc_init();
    adc = 0; adcgo = 0; EA = 1;
    /** adc status indicator */
    LEDRX = adc; LEDTX = !adc;
    /** main loop */
    while (1) {
        if (!SW0) {
            while (!SW0); /** wait until the user lets go */
            adc = !adc;
            adcgo = adc;
            if (!adcgo) {
                ET1 = 0; TR1 = 0;
                lcd_puts("*");
            }
            LEDRX = adc; LEDTX = !adc;
        }
        else if(!SW1) {
            while (!SW1); /** wait until the user lets go */
            lcd_goto_line2();
            lcd_puts("SW0:ADC, SW1:CLR");
        }
        if (adcgo) {
            adcgo = 0;
            lcd_goto_line2();
            lcd_puts("          ");
            /** read adc */
            check = adc_get_data();

```

```
        value = ((float) check / 255.0) * VREF;
        lcd_goto_line2();
        lcd_puts("ADC: ");
        float2str(display,value);
        lcd_puts(display);
        lcd_puts(" (");
        int2str(display,check);
        lcd_puts(display);
        lcd_puts(")");
        /** set timer 1 overflow every 50ms - with interrupt
handler */
        ET1 = 1; TH1 = 0x4B; TL1 = 0xFD; TR1 = 1;
    }
}
}
}
}
/*-----*/
-----*/
```

From:

<http://azman.unimap.edu.my/dokuwiki/> - Azman @UniMAP

Permanent link:

<http://azman.unimap.edu.my/dokuwiki/doku.php?id=notes:code8051&rev=1693440815>Last update: **2023/08/31 08:13**