

8051 Codes

Example codes (in C) for the classical Intel-8051 (mcu51) microcontroller core. Using my1code51 library. 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 , TowerPro MG996R servo & Text LCD.

[nmk322_test1.c](#)

```

/*-----*/
-----*/
/**
 * Testing HC06 bluetooth module , TowerPro MG996R servo & Text LCD
 * - note: servo pin (1|orange:PWM)(2|red:vcc)(3|brown:ground)
 */
/*-----*/
-----*/
#define BTNAME "nmk322bt"
#define BTPASS "0000"
#include "hc06.h"
#include "uart.h"
#include "timer.h"
#include "utils.h"
/*-----*/
-----*/
/** interface as defined in nmk322 lab module */
#define _LCD_8BIT_INTERFACE_
#define _LCD_PINS_DEFINED_
MY1SFR(LCD_DATA,0xA0);
MY1SBIT(LCD_BUSY,0xA7);
MY1SBIT(LCD_DNC,0x87);
MY1SBIT(LCD_RNW,0x86);
MY1SBIT(LCD_ENB,0x85);
/*-----*/
-----*/
#include "textlcd.h"
/*-----*/
-----*/
#define SERVO_PIN P1_0
#include "servo.h"

```

```

/*-----*/
-----*/
MY1SBIT(G0000,PIN15);
MY1SBIT(G01MS,PIN16);
MY1SBIT(G02MS,PIN17);
/*-----*/
-----*/
#define BUFFSIZE 128
/*-----*/
-----*/
__xdata char buff[BUFFSIZE];
/*-----*/
-----*/
void main(void) {
    unsigned char curr, test;
    G0000 = 1; G01MS = 1; G02MS = 1;
    timer_init();
    servo_init();
    lcd_init();
    lcd_goto_line1();
    lcd_puts("NMK322 SV/LCD/BT");
    uart_init();
    uart_puts("NMK322 SV/LCD/BT\r\n\r\n");
    hc06_init();
    curr = 3;
    do {
        uart_puts("-- Sending AT... ");
        hc06_find();
        if (hc06_wait_ok()==HC06_OK) {
            uart_puts("OK.\r\n");
            uart_puts("\r\nSet default name & pin\r\n");
            uart_puts("-- Set Name (");
            uart_puts(BTNAME);
            uart_puts("): ");
            hc06_setname(buff,BUFFSIZE);
            uart_puts(buff);
            uart_puts("\r\n");
            timer_delay1s(test,1);
            /* set pass */
            uart_puts("-- Set Pin (");
            uart_puts(BTPASS);
            uart_puts("): ");
            hc06_setpin(buff,BUFFSIZE);
            uart_puts(buff);
            uart_puts("\r\n");
            timer_delay1s(test,1);
            break;
        }
        uart_puts("timeout.\n");
        timer_delay1s(test,1);
    } while (--curr);
}

```

```

while (1) {
  if (hc06_peek()) {
    if (hc06_wait(buff,BUFFSIZE)>1) {
      if (buff[0]=='#') {
        curr = (unsigned char) str2uint(&buff[1]);
        if (curr>=5&&curr<=25) {
          uart_puts("## Turning to (");
          uart_puts(&buff[1]);
          uart_puts(")\r\n");
          servo_turn(curr);
        } else {
          uart_puts("** Invalid angle (");
          uart_puts(&buff[1]);
          uart_puts(")\r\n");
        }
      }
    } else {
      uart_puts(">> ");
      uart_puts(buff);
      uart_puts("\r\n");
    }
  }
}

if (G0000==0) {
  lcd_goto_line2();
  lcd_puts("ServoTurn CENTER");
  servo_turn(15);
  while (!G0000);
  lcd_goto_line2();
  lcd_puts("                ");
}

if (G01MS==0) {
  lcd_goto_line2();
  lcd_puts("ServoTurn PWM1ms");
  servo_turn(10); // 1ms pwm
  while (!G01MS);
  lcd_goto_line2();
  lcd_puts("                ");
}

if (G02MS==0) {
  lcd_goto_line2();
  lcd_puts("ServoTurn PWM2ms");
  servo_turn(20); // 2ms pwm
  while (!G02MS);
  lcd_goto_line2();
  lcd_puts("                ");
}
}

}

/*-----*/
-----*/

```

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 DEMO");
    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;
        }
    }
}
```

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

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