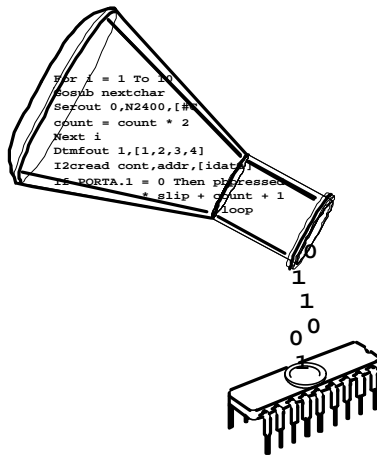


PicBasic Pro Compiler



microEngineering Labs, Inc.

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Introduction

1. Introduction

The PicBasic Pro Compiler (or PBP) is our next-generation programming language that makes it even quicker and easier for you to program Microchip Technology's powerful PICmicro microcontrollers. The English-like BASIC language is much easier to read and write than the quirky Microchip assembly language.

The PicBasic Pro Compiler is BASIC Stamp II like and has most of the libraries and functions of both the BASIC Stamp I and II. Being a true compiler, programs execute much faster and may be longer than their Stamp equivalents.

PBP is not quite as compatible with the BASIC Stamps as our original PicBasic Compiler is with the BS1. Decisions were made that we hope improve the language overall. One of these was to add a real **IF . . THEN . . ELSE . . ENDIF** instead of the **IF . . THEN (GOTO)** of the Stamps. These differences are spelled out later in this manual.

PBP defaults to create files that run on a PIC16F84-04/P clocked at 4MHz. Only a minimum of other parts are necessary: 2 22pf capacitors for the 4MHz crystal, a 4.7K pull-up resistor tied to the /MCLR pin and a suitable 5- volt power supply. Many PICmicros other than the 16F84, as well as oscillators of frequencies other than 4MHz, may be used with the PicBasic Pro Compiler.

1.1. The PICmicros

The PicBasic Pro Compiler produces code that may be programmed into a wide variety of PICmicro microcontrollers having from 8 to 84 pins and various on-chip features including A/D converters, hardware timers and serial ports.

There are many, many PICmicros, some pin-compatible with the >5x series, that may be used with the PicBasic Pro Compiler. Currently, the list includes the PIC12C67x, PIC14C000, PIC16C55x, 6xx, 7xx, 84, 9xx, PIC16F62x, 8x, 87x, PIC17Cxxx and the PIC18Cxxx series devices, with Microchip adding more at a rapid rate. For direct replacement of a PIC16C54, 56 or 58, the PIC16C554, 558, 620, 621 and 622 work well with the compiler and are very nearly the same price.* See the `READ.ME` file for the very latest PICmicro support list.

For general purpose PICmicro development using the PicBasic Pro Compiler, the PIC16F84, 16F876 and 16F877 are the current PICmicros of choice. These microcontrollers use flash technology to allow rapid erasing and reprogramming to speed program debugging. With the click of the mouse in the programming software, the flash PICmicro can be instantly erased and then reprogrammed again and again. Other PICmicros in the 12C67x, 14C000, 16C55x, 16C6xx, 16C7xx, 16C9xx, 17Cxxx and 18Cxxx series are either one-time programmable (OTP) or have a quartz window in the top (JW) to allow erasure by exposure to ultraviolet light for several minutes.

The PIC16F84 and 16F87x devices also contain between 64 and 256 bytes of non-volatile data memory that can be used to store program data and other parameters even when the power is turned off. This data area can be accessed simply by using the PicBasic Pro Compiler's **READ** and **WRITE** commands. (Program code is always permanently stored in the PICmicro's code space whether the power is on or off.)

By using a flash PICmicro for initial program testing, the debugging process may be sped along. Once the main routines of a program are operating satisfactorily, a PICmicro with more capabilities or expanded features of the compiler may be utilized.

While many PICmicro features will be discussed in this manual, for full PICmicro information it is necessary to obtain the appropriate PICmicro data sheets or the CD-ROM from Microchip Technology. Refer to Appendix B for contact information.

Introduction

*Selling price is dictated by Microchip Technology Inc. and its distributors.

1.2. About This Manual

This manual cannot be a full treatise on the BASIC language. It describes the PicBasic Pro instruction set and provides examples on how to use it. If you are not familiar with BASIC programming, you should acquire a book on the topic. Or just jump right in. BASIC is designed as an easy-to-use language and there are additional example programs on the disk and web site that can help get you started.

The next section of this manual covers installing the PicBasic Pro Compiler and writing your first program. Following is a section that describes different options for compiling programs.

Programming basics are covered next, followed by a reference section listing each PicBasic Pro command in detail. The reference section shows each command prototype, a description of the command and some examples. Curly brackets, {}, indicate optional parameters.

The remainder of the manual provides information for advanced programmers - all the inner workings of the compiler.

Getting Started

2. Getting Started

2.1. Software Installation

The PicBasic Pro files are compressed into a self-extracting file on the diskette. They must be uncompressed to your hard drive before use. To uncompress the files, create a subdirectory on your hard drive called `PBP` or another name of your choosing by typing:

```
md PBP
```

at the DOS prompt. Change to the directory:

```
cd PBP
```

Assuming the distribution diskette is in drive a:, uncompress the files into the PBP subdirectory:

```
a:\pbpxxx -d
```

where `xxx` is the version number of the compiler on the disk. Don't forget the `-d` option on the end of the command. This ensures that the proper subdirectories within PBP are created. Make sure that `FILES` and `BUFFERS` are set to at least 50 in your `CONFIG.SYS` file. Depending on how many `FILES` and `BUFFERS` are already in use by your system, allocating an even larger number may be necessary. See the `README.TXT` file on the diskette for more information on uncompressing the files. Also read the `READ.ME` file that is uncompressed to the PBP subdirectory on your hard drive for the latest PicBasic Pro Compiler information.

Files Information

`FILES` should be set to at least 75 in your `CONFIG.SYS` file. It is also a good idea to set `BUFFERS` to at least 75.

2.2. Your First Program

For operation of the PicBasic Pro Compiler you'll need a text editor or word processor for creation of your program source file, some sort of PICmicro programmer such as our EPIC Plus Pocket PICmicro Programmer, and the PicBasic Pro Compiler itself. Of course you also need a PC to run it all on.

The sequence of events goes something like this:

First create the BASIC source file for the program using your favorite text editor or word processor. If you don't have a favorite, DOS `EDIT` (included with MS-DOS) or Windows `NOTEPAD` (included with Windows and Windows95/98) may be substituted. The source file name should (but isn't required to) end with the extension `.BAS`.

The text file that is created must be pure ASCII text. It must not contain any special codes that might be inserted by word processors for their own purposes. You are usually given the option of saving the file as pure DOS or ASCII text by most word processors.

The following program provides a good first test of a PICmicro in the real world. You may type it in or you can simply copy it from the `SAMPLES` subdirectory included with the PicBasic Pro Compiler. The file is named `BLINK.BAS`. The BASIC source file should be created in or moved to the same directory where the `PBP.EXE` file is located.

' Example program to blink an LED connected to PORTB.0 about once a second

Getting Started

```
loop:    High PORTB.0    ' Turn on LED
        Pause 500      ' Delay for .5 seconds

        Low PORTB.0    ' Turn off LED
        Pause 500      ' Delay for .5 seconds

        Goto loop      ' Go back to loop and blink LED forever
End
```

Once you are satisfied that the program you have written will work flawlessly, you can execute the PicBasic Pro Compiler by entering `PBP` followed by the name of your text file at a DOS prompt. For example, if the text file you created is named `BLINK.BAS`, at the DOS command prompt enter:

```
PBP blink
```

The compiler will display an initialization (copyright) message and process your file. If it likes your file, it will create an assembler source code file (in this case named `BLINK.ASM`) and automatically invoke its assembler to complete the task. If all goes well, the final PICmicro code file will be created (in this case, `BLINK.HEX`). If you have made the compiler unhappy, it will issue a string of errors that will need to be corrected in your BASIC source file before you try compilation again.

To help ensure that your original file is flawless, it is best to start by writing and testing a short piece of your program, rather than writing an entire 100,000 line monolith all at once and then trying to debug it from end to end.

If you don't tell it otherwise, the PicBasic Pro Compiler defaults to creating code for the PIC16F84. To compile code for PICmicros other than the >F84, simply use the `-P` command line option described later in the manual to specify a different target processor. For example, if you intend to run the above program, `BLINK.BAS`, on a PIC16C74, compile it using the command:

```
PBP -p16c74 blink
```

Additional PM Information

PicBasic Pro now uses PM (PICmicro Macro Assembler) version 4.00 or later to work with the 16-bit core PICmicros. Do not use an earlier version of

PM with version 2.2 or later of PBP

2.3. Program That PICmicro

There are two steps left - putting your compiled program into the PICmicro microcontroller and testing it.

The PicBasic Pro Compiler generates standard 8-bit Merged Intel HEX (`.HEX`) files that may be used with any PICmicro programmer including our EPIC Plus Pocket PICmicro Programmer. PICmicros cannot be programmed with BASIC Stamp programming cables. The following is an example of how a PICmicro might be programmed using our EPIC Programmer with the DOS programming software. If Windows95/98/NT is available, using the Windows version of EPIC is recommended.

Make sure there are no PICmicros installed in the EPIC Programmer programming socket or any attached adapters.

Hook the EPIC Programmer to the PC parallel printer port using a DB25 male to DB25 female printer extension cable.

Getting Started

Plug the AC adapter into the wall and then into the EPIC Programmer (or attach 2 fresh 9-volt batteries to the programmer and connect the ABatt ON@ jumper).

The LED on the EPIC Programmer may be on or off at this point. Do not insert a PICmicro into the programming socket when the LED is on or before the programming software has been started.

Enter:

```
EPIC
```

at the DOS command prompt to start the programming software. The EPIC software should be run from a pure DOS session or from a full screen DOS session under Windows or OS/2. (Running under Windows is discouraged. Windows (all varieties) alters the system timing and plays with the port when you're not looking, which may cause programming errors.)

The EPIC software will take a look around to find where the EPIC Programmer is attached and get it ready to program a PICmicro. If the EPIC Programmer is not found, check all of the above connections and verify that there is not a PICmicro or any adapter connected to the programmer. Typing:

```
EPIC /?
```

at the DOS command prompt will display a list of available options for the EPIC software. Once the programming screen is displayed, use the mouse to click on Open file or press **Alt-O** on your keyboard. Use the mouse (or keyboard) to select `BLINK.HEX` or any other file you would like to program into the PICmicro from the dialog box.

The file will load and you should see a list of numbers in the window at the left. This is your program in PICmicro code. At the right of the screen there is a display of the configuration information that will be programmed into the PICmicro. Verify that it is correct before proceeding.

In general, the Oscillator should be set to XT for a 4MHz crystal and the Watchdog Timer should be set to ON for PicBasic Pro programs. Most importantly, **Code Protect** must be **OFF** when programming any windowed (JW) PICmicro. You may not be able to erase a windowed PICmicro that has been code protected.

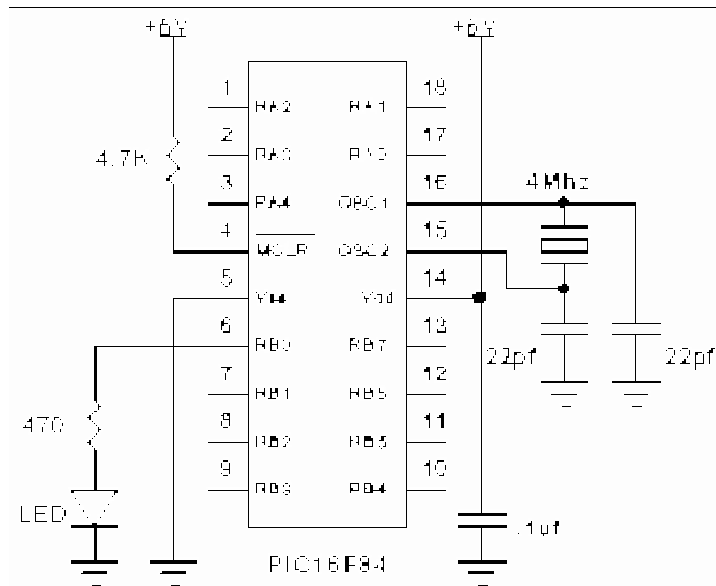
When it all looks marvelous, it is time to insert a PICmicro into the programming socket and click on Program or press **Alt-P** on the keyboard. The PICmicro will first be checked to make sure it is blank and then your code will be programmed into it. If the PICmicro is not blank and it is a flash device, you can simply choose to program over it without erasing first.

Once the programming is complete and the LED is off, it is time to test your program.

2.4. It's Alive

The sample schematic below gives you an idea of the few things that need to be connected to the PICmicro to make it work. Basically all you need is a pull-up resistor on the /MCLR line, a 4MHz crystal with 2 capacitors, and some kind of 5-volt power supply. We have added an LED and resistor to provide the output from the `BLINK` program.

Getting Started



Build and double check this simple circuit on a breadboard and plug in the PICmicro you just programmed. Our line of **PICProto** prototyping boards is perfect for this kind of thing. Connect a power supply. Your PICmicro come to life and start blinking the LED about once a second. If it does not blink, check all of the connections and make sure 5 volts is present at the appropriate pins on the PICmicro. From these simple beginnings, you can create your own world-conquering application.

2.5. I've Got Troubles

The most common problems with getting PICmicros running involve making sure the few external components are of the appropriate value and properly connected to the PICmicro. Following are some hints to help get things up and running.

Make sure the /MCLR pin is connected to 5 volts either through some kind of voltage protected reset circuit or simply with a 4.7K resistor. If you leave the pin unconnected, its level floats around and sometimes the PICmicro will work but usually it won't. The PICmicro has an on-chip power-on-reset circuit so in general just an external pull-up resistor is adequate. But in some cases the PICmicro may not power up properly and an external circuit may be necessary. See the Microchip PICmicro data books for more information.

Be sure you have a good crystal with the proper value capacitors connected to it. Capacitor values can be hard to read. If the values are off by too much, the oscillator won't start and run properly. A 4MHz crystal with two 22pf (picofarad) ceramic disk capacitors is a good start for most PICmicros. Once again, check out the Microchip data books for additional thoughts on the matter.

Make sure your power supply is up to the task. While the PICmicro itself consumes very little power, the power supply must be filtered fairly well. If the PICmicro is controlling devices that pull a lot of current from your power supply, as they turn on and off they can put enough of a glitch on the supply lines to cause the PICmicro to stop working properly. Even an LED display can create enough of an instantaneous drain to momentarily clobber a small power supply (like a 9-volt battery) and cause the PICmicro to lose its mind.

Start small. Write short programs to test features you are unsure of or might be having trouble with. Once these smaller programs are working properly, you can build on them.

Getting Started

Try doing things a different way. Sometimes what you are trying to do looks like it should work but doesn't, no matter how hard you pound on it. Usually there is more than one way to skin a program. Try approaching the problem from a different angle and maybe enlightenment will ensue.

2.5.1. PICmicro Specific Issues

Be sure to read the PICmicro data sheets. Some devices have features that can interfere with expected pin operations. The PIC16C62x parts (the 16C620, 621 and 622) are a good example of this. These PICmicros have analog comparators on PORTA. When these chips start up, PORTA is set to analog mode. This makes the pin functions on PORTA work in an unexpected manner. To change the pins to digital, simply add the line:

```
CMCON = 7
```

near the front of your program.

Any PICmicro with analog inputs, such as the PIC16C7xx, PIC16F87x and PIC12C67x series devices, will come up in analog mode. You must set them to digital if that is how you intend to use them:

```
ADCON1 = 7
```

Another example of potential disaster is that PORTA, pin 4 exhibits unusual behavior when used as an output. This is because the pin has an open drain output rather than the usual bipolar stage of the rest of the output pins. This means it can pull to ground when set to 0, but it will simply float when set to a 1, instead of going high. To make this pin act in the expected manner, add a pull-up resistor between the pin and 5 volts. The value of the resistor may be between 1K and 33K, depending on the drive necessary for the connected input. This pin acts as any other pin when used as an input.

Some PICmicros, such as the PIC16F873, 874, 876 and 877, allow low-voltage programming. This function takes over one of the PORTB pins and can cause the device to act erratically if this pin is not pulled low. It is best to make sure that low-voltage programming is not enabled at the time the PICmicro is programmed.

All of the PICmicro pins are set to inputs on power-up. If you need a pin to be an output, set it to an output before you use it, or use a PicBasic Pro command that does it for you. Once again, review the PICmicro data sheets to become familiar with the idiosyncrasies of a particular part.

The name of the port pins on the PIC12C67x and 12CE67x devices is GPIO. The name for the TRIS register is TRISIO.

```
GPIO.0 = 1
TRISIO = %101010
```

The PIC17Cxxx device TRIS registers are actually named DDR (data direction register). In place of using TRIS to set the input/output direction, use DDR:

```
DDRB = 0 ' Set PORTB to all output
```

There is no data direction register for PORTA.

Certain PICmicros have on-chip non-volatile data storage implemented like an I2C interfaced serial EEPROM. **READ** and **WRITE** will not work on devices with on-chip I2C interfaced serial EEPROM like the 12CE67x and 16CE62x parts. Use the **I2CREAD** and **I2CWRITE** instructions instead.

Some PICmicro devices, notably the PIC12C671, 672, 12CE673 and 674, have on-chip RC oscillators. These devices contain an oscillator calibration factor in the last location of code space. The on-chip oscillator may be fine-tuned by acquiring the data from this location and

Getting Started

moving it into the OSCCAL register. Two **DEFINEs** have been created to perform this task automatically each time the program starts:

```
DEFINE OSCCAL_1K 1      ' Set OSCCAL for 1K device
DEFINE OSCCAL_2K 1      ' Set OSCCAL for 2K device
```

Add one of these 2 **DEFINEs** near the beginning of the PicBasic Pro program to perform the setting of OSCCAL.

If a UV erasable device has been erased, the value cannot be read from memory. If one of these **DEFINEs** is used on an erased part, it will cause the program to loop endlessly. To set the OSCCAL register on an erased part, near the beginning of the program, add the line:

```
OSCCAL = $a0 ' Set OSCCAL register to $a0
```

The \$a0 is merely an example. The part would need to be read before it is erased to obtain the actual OSCCAL value for that particular device.

Please see the Microchip data sheets for more information on OSCCAL and any of the other PICmicro registers.

2.5.2. Code Crosses Page Boundary Messages

Many PICmicros contain code space memory that is segmented into 2K or 8K pages. As large files are compiled and then assembled, they may start to use more than the first page. As each page is used, PM, the assembler, will issue a message that the code is crossing a particular boundary. This is normal and no cause for alarm. PBP will make sure to take care of most of the issues for you.

The only thing that you must be aware of are the **BRANCH** instructions. If a **BRANCH** tries to access a label on the other side of a boundary, it will not work properly. **BRANCHL** should be used instead. It can address labels in any code page.

2.5.3. Out of Memory Errors

Compiling large PicBasic Pro source code files can tax the memory of the PC running the compiler. If an Out of Memory error is issued and the FILES and BUFFERS are set as recommended, an alternate version of PBP can be used. PBPW.EXE has been compiled to make use of all of the memory available to Windows 95, 98, NT and 2000. You must, of course, be running in a DOS shell from one of these 32-bit Windows environments or be within Microchip's MPLAB. To execute the Windows version from the DOS command line, simply substitute PBPW for PBP.

```
PBPW blink
```

2.6. Coding Style

Writing readable and maintainable programs is an art. There are a few simple techniques you can follow that may help you become an artist.

2.6.1. Comments

Use lots of comments. Even though it may be perfectly obvious to you what the code is doing as you write it, someone else looking at the program (or even yourself when you are someone else later in life) may not have any idea of what you were trying to achieve. While comments take up space in your BASIC source file, they do not take up any additional space in the PICmicro so use them freely.

Make the comments tell you something useful about what the program is doing. A comment like "Set Pin0 to 1" simply explains the syntax of the language but does nothing to tell you

Getting Started

why you have the need to do this. Something like "Turn on the Battery Low LED" might be a lot more useful.

A block of comments at the beginning of the program and before each section of code can describe what is about to happen in more detail than just the space remaining after each statement. But don't include a comment block instead of individual line comments - use both.

At the beginning of the program describe what the program is intended to do, who wrote it and when. It may also be useful to list revision information and dates. Specifying what each pin is connected to can be helpful in remembering what hardware this particular program is designed to run on. If it is intended to be run with a non-standard crystal or special compiler options, be sure to list those.

2.6.2. Pin and Variable Names

Make the name of a pin or variable something more coherent than `Pin0` or `B1`. In addition to the liberal use of comments, descriptive pin and variable names can greatly enhance readability. The following code fragment demonstrates:

```
BattLED var PORTB.0          ' Low battery LED
level    var    byte        ' Variable will contain the battery level

    If level < 10 Then      ' If batt level is low
        High BattLED      ' Turn on the LED
    Endif
```

2.6.3. Labels

Labels should also be more meaningful than `Alabel1:` or `Ahere:@`. Even a label like `Aloop:@` is more descriptive (though only slightly). Usually the line or routine you are jumping to does something unique. Try and give at least a hint of its function with the label, and then follow up with a comment.

2.6.4. GOTO

Try not to use too many `GOTOS`. While `GOTOS` may be a necessary evil, try to minimize their use as much as possible. Try to write your code in logical sections and not jump around too much. `GOSUBS` can be helpful in achieving this.

2.6.5. GOSUB

For code space reasons, it is usually better to place the program's subroutines at the beginning of the program than at the end. You will need to place a `GOTO` at the very beginning to skip around these subroutines.

2.7. Limited 12-bit Core Support

PicBasic Pro version 2.4 adds limited support for all the 12-bit core PICmicro microcontrollers. The reason the support is limited is that the resources on the 12-bit core devices are very limited. Some of these limits include only a two-level hardware stack and very small amounts of general purpose RAM memory. The code page size is also small at 512 bytes. There is also a limitation that calls and computed jumps can only be made to the first

Getting Started

half (256 words) of any code page. These limitations have made it necessary to eliminate some compiler commands and modify the operation of some others.

While many useful programs can be written for the 12-bit core PICmicros using the PicBasic Pro Compiler, some applications will not be suited for these devices. Choosing a 14- or 16-bit core device with more resources will, in many cases, be the best solution.

Commands that are not supported for the 12-bit core PICmicros:

<i>Command</i>	<i>Reason</i>
Adcin	No internal ADCs
Data	No on-chip EEPROM
Dtmfout	Not enough RAM or stack
Eeprom	No on-chip EEPROM
Freqout	Not enough RAM or stack
Hpwm	No hardware PWM
Hserin	No hardware serial port
Hserout	No hardware serial port
On Interrupt	No Interrupts
Read	No on-chip EEPROM
Readcode	No flash devices
Resume	No Interrupts
Serin2	Not enough RAM or stack
Serout2	Not enough RAM or stack
USBIn	No USB devices
USBInit	No USB devices
USBOut	No USB devices
Write	No on-chip EEPROM
Writecode	No flash devices
Xin	Not enough RAM or stack
Xout	Not enough RAM or stack

Trying to use these commands with 12-bit core devices will result in numerous errors. If you must use one of these commands, choose a 14- or 16-bit core device with more resources.

Getting Started

Commands that have had their operation modified are:

Button	The Define for debounce, BUTTON_PAUSE is limited to 65 milliseconds.
Debug, Debugin	The Serin2 and Serout2 modifiers are not supported for these commands because of memory and stack size limits.
I2CRead, I2CWrite	The I2C clock and data pins are fixed at compile time by Defines. They still must be specified in the I2CRead and I2CWrite statements, though this information is ignored by the compiler. Define I2C_SDA PORTA,0 Define I2C_SCL PORTA,1 Because of memory and stack constraints, the Define for I2C_SLOW does not do anything. Low-speed (100 kHz) I2C devices may be used up to 4MHz. Above 4MHz, high-speed (400kHz) devices should be used.
Lcdout	The Define for I2C_HOLD has no effect. The Serout2 modifiers are not supported for this command because of memory and stack size limits.
OWIn, OWOut	The Rep, Skip and Str modifiers are not supported for these commands because of memory and stack size limits.
Serout	The open drain modes are not available due to TRIS register constraints.
Shiftin, Shiftout	The Define for SHIFT_PAUSEUS is not available because of stack size limitations.

General Considerations

Because of the architecture of the 12-bit core PICmicro MCUs, programs compiled for them by PBP will, in general, be larger and slower than programs compiled for the other PICmicro families. In many cases, choosing a device from one of these other families will be more appropriate. However, many useful programs can be written and compiled for the 12-bit core devices.

The two main programming limitations that will most likely occur are running out of RAM memory for variables and running past the first 256 word limit for the library routines.

The compiler uses between 20 and 22 bytes of RAM for its internal variables, with additional RAM used for any necessary temporary variables. This RAM allocation includes a 4 level software stack so that the BASIC program can still nest Gosubs up to 4 levels deep. Some PICmicro devices only have 24 or 25 bytes of RAM so there is very little space for user variables on those devices. If the Unable to Fit Variable error message occurs during compilation, choose another PICmicro MCU with more general purpose RAM.

Getting Started

12-bit core PICmicro MCUs can call only into the first half (256 words) of a code page. Since the compiler's library routines are all accessed by calls, they must reside entirely in the first 256 words of the PICmicro code space. Many library routines, such as I2CRead, are fairly large. It may only take a few routines to overrun the first 256 words of code space. If it is necessary to use more library routines that will fit into the first half of the first code page, it will be necessary to move to a 14- or 16-bit core PICmicro MCU instead of the 12-bit core device.

Current PICmicro support:

Current PICmicro support

Limited support because of 12-bit core	12C508 (A), 12C509(A), 12CE518, 12CE519 16C505, 16C52, 16C54, 16C55, 16C56, 16C57, 16C58, 16HV540
Supported	12C671, 12C672, 12CE673, 12CE674 14C000 16C554, 16C558, 16C61, 16C62(AB), 16C620(A), 16C621(A), 16C622(A), 16C63(A), 16C64(A), 16C642, 16C65(AB), 16C66, 16C662, 16C67, 16C71, 16C710, 16C711, 16C712, 16C715, 16C716, 16C717, 16C72(A), 16C73(AB), 16F73, 16C74(AB), 16F74, 16C76, 16F76, 16C77, 16F77, 16C770, 16C771, 16C773, 16C774, 16C84, 16C923, 16C924, 16CE623, 16CE624, 16CE625, 16F627, 16F628, 16F83, 16F84(A), 16F870, 16F871, 16F872, 16F873, 16F874, 16F876, 16F877 17C42A, 17C43, 17C44, 17C752, 17C756(A), 17C762, 17C766 18C242, 18C442, 18C252, 18C452, 18C658, 18C858 PicStic1, PicStic2, PicStic3, PicStic4, PicStic1 2k, PicStic2 2k, PicStic3 2k, PicStic4 2k

Getting Started

2.8.. Temporary Variables

PBP creates temporary variables to store intermediate results of expressions. These temporaries are always words and are only created when necessary. They can cause unexpected RAM usage. To see what variables are used, see the .ASM file created by PBP.

Math operations are generally 16-bit integer operations. You can usually mix 8- and 16-bit operands with no ill effects. PBP will sort things out and usually give you the result you are looking for. However, certain situations can create problems.

As an example, consider the following two code fragments:

Listing 1:

```
addr var byte

addr = 10
I2CWrite 0,1,$a0,addr,[addr * 2]
```

Listing 2:

```
addr var byte
store var byte

addr = 10
store = addr * 2
I2CWrite 0,1,$a0,addr,[store]
```

These two listing seem as if they should yield the same result. But because of the 16-bit expression handling and word-sized temporary variables, they will do two different things.

The program in Listing 2 will write the byte store (which is address * 2 or 20) to I2C address 10.

The program in Listing 1 looks like it will do the same thing but in reality, it won't. Instead of writing a single byte 20 to I2C address 10, it will write a word 20 (two consecutive bytes, 0 then 20). This is because the result of the mathematical expression is a word.

Getting Started

This problem does not affect very many commands, but it is safer to create your own intermediate variables of the desired size as in Listing 2, rather than to let PBP make all the decisions for you.

2.9. Using PBP With MPLAB

With the latest releases of Microchip's MPLAB , the PicBasic and PicBasic Pro Compiler can now be used within the IDE.

First, download the latest release of MPLAB, if you don't have it, from Microchip's web site (www.microchip.com). Install MPLAB and make sure it is in your DOS path. This last step is important, even if you are using Windows. You must alter the path statement in the DOS AUTOEXEC.BAT file to include the path to the directory where MPLAB was installed. You must also reboot after this change to the path. Not making this addition to the path leads to unsuccessful builds as PicBasic Pro cannot find MPASM and its include files.

The PicBasic Pro Compiler should also have been installed into its own subdirectories by this point.

Setup

Start MPLAB and select Install Language Tool under the Project menu. Select microEngineering Labs, Inc. as the Language Suite. Select the appropriate Tool Name (PicBasic Pro Compiler). Use the browse button to select PBP.EXE or PBPW.EXE within the subdirectory where it was installed as the Executable. Select the Command-line radio button and click OK to finish up.

Installation of the compiler into MPLAB is now complete. You can now write, edit, simulate and program BASIC projects from within MPLAB.

Operation

To create a BASIC project within MPLAB, select New Project under the Project menu. Navigate to the subdirectory into which the PicBasic Pro Compiler was installed. The project and its associated files must exist in the compiler's subdirectory in order for all of the include files to be found. Enter a new

Getting Started

project name such as BLINK.PJT and click OK. The Edit Project window should pop up.

Select the desired processor type using the Change button next to Development Mode.

Select microEngineering Labs, Inc. as the Language Tool Suite.

Click on the name of the project under Project Files and then click the Node Properties button. The Node Properties window should pop up.

Select the desired Language Tool for the project (PicBasic Pro Compiler). The rest of the defaults should be OK so click OK to exit.

Click the Add Node button to add your BASIC source file to the project, or click OK and File|New to begin a new source file.

That's all (!!!) there is to it. You can now select Make or Build to compile your program.

MPASM Information

Additional Case Sensitivity Information

As the PicBasic Pro manual points out, the PicBasic Pro Compiler itself is not case sensitive. This means, for example, LOOP: would be the same label as loop: or even LoOp:.

The assemblers that are launched by PBP, on the other hand, are of varying degrees of case sensitivity. PM, the PICmicro Macro Assembler, is also case insensitive.

MPASM defaults to case sensitive. Normally this will have no noticeable effect on programs, unless in-line assembly code is used. PBP DEFINEs like OSC and the LCD definitions must be in all upper-case as shown in the examples in the manual. MPASM may be used with PBP in two ways. If the command line option "-ampasm" is used, MPASM will be launched following compilation to complete the process. MPASM will display its own screen with its progress.

Alternatively, the command line option "-amp" will launch MPASM in quiet mode and only display any errors. However, the launcher consumes additional memory that is therefore not available to MPASM.

For maximum memory availability to MPASM, the command line option "-ampasm" should be used.

Getting Started

In any case, MPASM is not included with PBP and must be obtained from
Microchip.

PicStic Information

Micromint PicStic users must tell PBP which PicStic is the target so that it can include the proper library. The command line option "-p" should be followed by the name of the PicStic:

```
pbp -pps1 filename  
pbp -pps2 filename  
pbp -pps3 filename  
pbp -pps4 filename
```

These files specify PIC16F84A as the device. A particular PicStic may contain either a PIC16C84, PIC16F84 or PIC16F84A.

```
pbp -pps1_2k filename  
pbp -pps2_2k filename  
pbp -pps3_2k filename  
pbp -pps4_2k filename
```

These PicStic 2k files specify PIC16F628 as the device.

The PicStic libraries only work with 14-bit core parts, not 12-bit core or 16-bit core 17Cxxx and 18Cxxx devices.

Command Line Options

3. Command Line Options

3.1. Usage

The PicBasic Pro Compiler can be invoked from the DOS command line using the following command format:

```
PBP Options Filename
```

Zero or more *Options* can be used to modify the manner in which PBP compiles the specified file. *Options* begin with either a minus (-) or a forward slash (/). The character following the minus or slash is a letter which selects the *Option*. Additional characters may follow if the *Option* requires more information. Each *Option* must be separated by a space and no spaces may occur within an *Option*.

Multiple *Options* may be used at the same time. For example the command line:

```
PBP -p16c71 -ampasm blink
```

will cause the file `BLINK.BAS` to be compiled using MPASM as the assembler and targeted for a PIC16C71 processor.

The first item not starting with a minus is assumed to be the *Filename*. If no extension is specified the default extension `.BAS` is used. If a path is specified, that directory is searched for the named file. Regardless of where the source file is found, files generated by PBP are placed in the current directory.

By default, PBP automatically launches the assembler (`PM.EXE`) if the compilation is performed without error. PBP expects to find `PM.EXE` in the same directory as `PBP.EXE`. If the compilation has errors or the `-s` option is used, the assembler is not launched. If PBP is invoked with no parameters or filename, a brief help screen is displayed.

3.2. Options

Table 1 Compiler command line options

<i>Option</i>	<i>Description</i>
A	Use a different Assembler
C	Insert source lines as Comments into assembler file
E	Output errors to a file
H(?)	Display Help screen
I	Use a different Include path
L	Use a different Library file
O	Pass Option to assembler
P	Specify target Processor
S	Skip execution of assembler when done
V	Verbose mode

Command Line Options

3.2.1. Option **-A**

PBP has the capability to use either PM, which is included with PBP, or Microchip's MPASM as its assembler. To specify MPASM (which must be acquired from Microchip), use **-ampasm** on the command line:

```
PBP -ampasm filename
```

If no assembler is specified on the command line, PM is used. See the section on assembly language programming for more information.

3.2.2. Option **-C**

The **-c** option causes PBP to insert the PicBasic Pro source file lines as comments into the assembly language source file. This can be useful as a debugging tool or learning tool as it shows the PicBasic Pro instruction followed by the assembly language instructions it generates.

```
PBP -c filename
```

3.2.3. Option **-E**

The **-E** option causes PBP to send all the errors to a file, filename.er.

```
PBP -e filename
```

3.2.4. Option **-H** or **-?**

The **-H** or **-?** option causes PBP to display a brief help screen. This help screen is also displayed if no option and filename is specified on the command line.

3.2.5. Option **-I**

The **-I** option lets you select the include path for files used by PicBasic Pro.

3.2.6. Option **-L**

The **-L** option lets you select the library used by PicBasic Pro. This option is generally unnecessary as the default library file is set in a configuration file for each microcontroller. For more information on PicBasic Pro libraries, see the advanced sections later in this manual.

```
PBP -lpbpps2 filename
```

This example tells PBP to compile `filename` using the PicStic2 library.

Command Line Options

3.2.7. Option -o

The -o option causes the letters following it to be passed to the assembler on its command line as options. Some pertinent PM options are listed in the following table:

Table 2 Option - O

<i>PM Option</i>	<i>Description</i>
OD	Generates Listing, Symbol Table, and Map File
OL	Generates Listing only

```
PBP -ol filename
```

This example tells PBP to generate a `filename.lst` file after a successful compilation. More than one -o option may be passed to the assembler at a time. The PICmicro Macro Assembler's manual on disk contains more information on the assembler and its options.

3.2.8. Option -P

If not told otherwise, PBP compiles programs for the PIC16F84. If the program requires a different processor as its target, its name must be specified on the command line use the -P option.

For example, if the desired target processor for the PBP program is a PIC16C74, the command line should look something like the following:

```
PBP -p16c74 filename
```

3.2.9. Option -s

Normally, when PBP successfully compiles a program, it automatically launches the assembler. This is done to convert the assembler output of PBP to an executable image. The -s option prevents this, leaving PBP's output in the generated .ASM file.

Since -s prevents the assembler from being invoked, options that are simply passed to the assembler using the -o option are effectively overridden.

```
PBP -s filename
```

3.2.10. Option -v

The -v option turns on PBP=s verbose mode which presents more information during program compilation.

```
PBP -v filename
```

Picbasic Pro Basics

4. PicBasic Pro Basics

4.1. Identifiers

An identifier is, quite simply, a name. Identifiers are used in PBP for line labels and variable names. An identifier is any sequence of letters, digits, and underscores, although it must not start with a digit. Identifiers are not case sensitive, thus label, LABEL, and Label are all treated as equivalent. And while labels might be any number of characters in length, PBP only recognizes the first 32.

4.2. Line Labels

In order to mark statements that the program might wish to reference with **GOTO** or **GOSUB** commands, PBP uses line labels. Unlike many older BASICs, PBP doesn't allow line numbers and doesn't require that each line be labeled. Rather, any PBP line may start with a line label, which is simply an identifier followed by a colon (:).

```
here:    Serout 0,N2400,["Hello, World!",13,10]
        Goto here
```

4.3. Variables

Variables are where temporary data is stored in a PicBasic Pro program. They are created using the **VAR** keyword. Variables may be bits, bytes or words. Space for each variable is automatically allocated in the microcontroller's RAM by PBP. The format for creating a variable is as follows:

```
Label    VAR    Size{.Modifiers}
```

Label is any identifier, excluding keywords, as described above. *Size* is **BIT**, **BYTE** or **WORD**. Optional *Modifiers* add additional control over how the variable is created. Some examples of creating variable are:

```
dog      var    byte
cat      var    bit
w0       var    word
```

There are no predefined user variables in PicBasic Pro. For compatibility sake, two files have been provided that create the standard variables used with the BASIC Stamps: `Abs1defs.bas@` and `Abs2defs.bas@`. To use one of these files, add the line:

```
Include "bs1defs.bas"
```

or

```
Include "bs2defs.bas"
```

near the top of the PicBasic program. These files contain numerous **VAR** statements that create all of the BASIC Stamp variables and pin definitions. However, instead of using these "canned" files, we recommend you create your own variables using names that are meaningful to you. The number of variables available depends on the amount of RAM on a particular device and the size of the variables and arrays. PBP reserves approximately 24 RAM locations for its own use. It may also create additional temporary variables for use in sorting out complex equations.

Picbasic Pro Basics

4.4. Aliases

VAR can also be used to create an alias (another name) for a variable. This is most useful for accessing the innards of a variable.

```
fido    var    dog           ' fido is another name for dog
b0      var    w0.byte0     ' b0 is the first byte of word w0
b1      var    w0.byte1     ' b1 is the second byte of word w0
flea    var    dog.0        ' flea is bit0 of dog
```

Table 3 Aliases for variables

<i>Modifier</i>	<i>Description</i>
BIT0 or 0	Create alias to bit 0 of byte or word
BIT1 or 1	Create alias to bit 1 of byte or word
BIT2 or 2	Create alias to bit 2 of byte or word
BIT3 or 3	Create alias to bit 3 of byte or word
BIT4 or 4	Create alias to bit 4 of byte or word
BIT5 or 5	Create alias to bit 5 of byte or word
BIT6 or 6	Create alias to bit 6 of byte or word
BIT7 or 7	Create alias to bit 7 of byte or word
BIT8 or 8	Create alias to bit 8 of word
BIT9 or 9	Create alias to bit 9 of word
BIT10 or 10	Create alias to bit 10 of word
BIT11 or 11	Create alias to bit 11 of word
BIT12 or 12	Create alias to bit 12 of word
BIT13 or 13	Create alias to bit 13 of word
BIT14 or 14	Create alias to bit 14 of word
BIT15 or 15	Create alias to bit 15 of word
BYTE0 or LOWBYTE	Create alias to low byte of word
BYTE1 or HIGHBYTE	Create alias to high byte of word

4.5. Arrays

Variable arrays can be created in a similar manner to variables.

```
Label VAR Size[Number of elements]
```

Label is any identifier, excluding keywords, as described above. *Size* is **BIT**, **BYTE** or **WORD**. *Number of elements* is how many array locations is desired. Some examples of creating arrays are:

```
sharks var byte[10]
fish var bit[8]
```


Picbasic Pro Basics

The first array location is element 0. In the `fish` array defined above, the elements are numbered `fish[0]` to `fish[7]` yielding 8 elements in total. Because of the way arrays are allocated in memory, there are size limits for each type:

Table 4 Array sizes

Size	Maximum Number of elements
BIT	256
BYTE	96*
WORD	48*

* Processor dependent. See the section on memory allocation for more information. Arrays must fit entirely within one RAM bank on most PICmicros. They may not span RAM banks on 14-bit or 17Cxxx devices. (Arrays may span banks on 18Cxxx devices. Byte- and word-sized arrays are only limited in length by the amount of memory.) The compiler will assure that arrays will fit in memory before successfully compiling.

4.6. Constants

Named constants may be created in a similar manner to variables. It can be more convenient to use a constant name instead of a constant number. If the number needs to be changed, it may be changed in only one place in the program; where the constant is defined. Variable data cannot be stored in a constant.

Label **CON** *Constant expression*

Some examples of constants are:

```
mice con 3
traps con mice * 1000
```

4.7. Symbols

SYMBOL provides yet another method for aliasing variables and constants. It is included for BS1 compatibility. **SYMBOL** cannot be used to create a variable. Use **VAR** to create a variable.

SYMBOL lion = cat ' cat was previously created using VAR

SYMBOL mouse = 1 ' Same as mouse con 1

4.8. Numeric Constants

PBP allows numeric constants to be defined in the three bases: decimal, binary and hexadecimal. Binary values are defined using the prefix '%' and hexadecimal values using the prefix '\$'. Decimal values are the default and require no prefix.

100 ' Decimal value 100

%100 ' Binary value for decimal 4

\$100 ' Hexadecimal value for decimal 256

For ease of programming, single characters are converted to their ASCII equivalents. Character constants must be quoted using double quotes and must contain only one character (otherwise, they are string constants).

"A" ' ASCII value for decimal 65

"d" ' ASCII value for decimal 100

Picbasic Pro Basics

Picbasic Pro Basics

4.9. String Constants

PBP doesn't provide string handling capabilities, but strings can be used with some commands. A string contains one or more characters and is delimited by double quotes. No escape sequences are supported for non-ASCII characters (although most PBP commands have this handling built-in).

```
Lcdout "Hello"      ' Output String (Short for "H","e","l","l","o")
```

Strings are usually treated as a list of individual character values.

4.10. Ports and Other Registers

All of the PICmicro registers, including the ports, can be accessed just like any other byte-sized variable in PicBasic Pro. This means that they can be read from, written to or used in equations directly:

```
PORTA = %01010101      ' Write value to PORTA
anyvar = PORTB & $0f    ' Isolate lower 4 bits of PORTB and
                        place result in anyvar
```

4.11. Pins

Pins may be accessed in a number of different ways. The best way to specify a pin for an operation is to simply use its PORT name and bit number:

```
PORTB.1 = 1           ' Set PORTB, bit 1 to a 1
```

To make it easier to remember what a pin is used for, it should be assigned a name using the **VAR** command. In this manner, the name may then be used in any operation:

```
led      var      PORTA.0 ' Rename PORTA.0 as led
High led          ' Set led (PORTA.0) high
```

For compatibility with the BASIC Stamp, pins used in PicBasic Pro Compiler commands may also be referred to by number, 0 - 15. These pins are physically mapped onto different PICmicro hardware ports dependent on how many pins the microcontroller has.

Table 5 Pin mapping

No. PICmicro Pins	0 - 7	8 - 15
8-pin	GPIO*	GPIO*
18-pin	PORTB	PORTA*
28-pin (except 14C000)	PORTB	PORTC
28-pin (14C000)	PORTC	PORTD
40-pin	PORTB	PORTC

*GPIO and PORTA do not have 8 I/O pins.

If a port does not have 8 pins, such as PORTA, only the pin numbers that exist may be used, i.e. 8 - 12. Using pin numbers 13 - 15 will have no discernable effect.

This pin number, 0 - 15, has nothing to do with the physical pin number of a PICmicro.

Depending on the particular PICmicro, pin number 0 could be physical pin 6, 21 or 33, but in each case it maps to PORTB.0 (or GPIO.0 for 8-pin devices, or PORTC.0 for a PIC14C000). Pins may be referenced by number (0 - 15), name (e.g. `pin0`, if one of the `bsdefs.bas` files are included or you have defined them yourself), or full bit name (e.g. `PORTA.1`). Any pin or bit of the microcontroller can be accessed using the latter method.

Picbasic Pro Basics

The pin names (i.e. `Pin0`) are not automatically included in your program. In most cases, you would define pin names as you see fit using the `VAR` command:

```
led var PORTB.3
```

However, two definition files have been provided to enhance BASIC Stamp compatibility. The file `Abs1defs.bas@` or `Abs2defs.bas@` may be included in the PicBasic Pro program to provide pin and bit names that match the BASIC Stamp names.

```
Include "bs1defs.bas"
```

or

```
Include "bs2defs.bas"
```

`BS1DEFS.BAS` defines `Pins`, `B0-B13`, `W0-W6` and most of the other BS1 pin and variable names.

`BS2DEFS.BAS` defines `Ins`, `Outs`, `B0-B25`, `W0-W12` and most of the other BS2 pin and variable names.

When a PICmicro powers-up, all of the pins are set to input. To use a pin as an output, the pin or port must be set to an output or a command must be used that automatically sets a pin to an output.

To set a pin or port to an output (or input), set its TRIS register. Setting a TRIS bit to 0 makes its pin an output. Setting a TRIS bit to 1 makes its pin an input. For example:

```
TRISA = %00000000      \ Or TRISA = 0
```

sets all the PORTA pins to outputs.

```
TRISB = %11111111      \ Or TRISB = 255
```

sets all the PORTB pins to inputs.

```
TRISC = %11111111      \ Or TRISC = 255
```

Sets all the even pins on PORTC to outputs, and the odd pins to inputs. Individual bit directions may be set in the same manner.

```
TRISA.0 = 0
```

sets PORTA, pin 0 to an output. All of the other pin directions on PORTA are unchanged.

The BASIC Stamp variable names `Dir`, `Dirh`, `Dir1` and `Dir0-Dir15` are not defined and should not be used with the PicBasic Pro Compiler. TRIS should be used instead, but has the opposite state of `Dir`.

This **does not** work in PicBasic Pro:

```
Dir0 = 1      \ Doesn't set pin PORTB.0 to output
```

Do this instead:

```
TRISB.0 = 0   \ Set pin PORTB.0 to output
```

or simply use a command that automatically sets the pin direction.

4.12. Comments

A PBP comment starts with either the `REM` keyword or the single quote (`>`). All following characters on this line are ignored.

Unlike many BASICs, `REM` is a unique keyword and not an abbreviation for `REMark`. Thus, variables names may begin with `REM` (although `REM` itself is not valid).

Picbasic Pro Basics

4.13. Multi-statement Lines

In order to allow more compact programs and logical grouping of related commands, PBP supports the use of the colon (:) to separate statements placed on the same line. Thus, the following two examples are equivalent:

```
W2 = W0
W0 = W1
W1 = W2
```

is the same as:

```
W2 = W0 : W0 = W1 : W1 = W2
```

This does not, however, change the size of the generated code.

4.14. Line-extension Character

The maximum number of characters that may appear on one PBP line is 256. Longer statements may be extended to the next line using the line-extension character (underscore) at the end of each line to be continued.

```
Branch B0, [label10, label11, label12, _
label13, label14]
```

4.15. INCLUDE

Other BASIC source files may be added to a PBP program by using **INCLUDE**. You may have standardized subroutines, definitions or other files that you wish to keep separate. The Stamp and serial mode definition files are examples of this. These files may be included in programs where they are necessary, but kept out of programs where they are not needed.

The included file's source code lines are inserted into the program exactly where the **INCLUDE** is placed.

```
INCLUDE "modedefs.bas"
```

4.16. DEFINE

Some elements, like the clock oscillator frequency and the LCD pin locations, are predefined in PBP. **DEFINE** allows a PBP program to change these definitions, if desired.

DEFINE may be used to change the predefined oscillator value, the **DEBUG** pins and baud rate and the LCD pin locations, among other things. These definitions must be in all upper case. See the appropriate sections of the manual for specific information on these definitions.

A new Define has been added to set a maximum count for Pulsin and Rctime before it stops waiting for a pulse or the end of a pulse:

Picbasic Pro Basics

Table 6 Picbasic DEFINES

<i>Define</i>		<i>Description</i>
DEFINE BUTTON_PAUSE	10	'Button debounce delay in ms
DEFINE CHAR_PACING	1000	'Serout character pacing in us
DEFINE DEBUG_REG	PORTB	'Debug pin port
DEFINE DEBUG_BIT	0	'Debug pin bit
DEFINE DEBUG_BAUD	2400	'Debug baud rate
DEFINE DEBUG_MODE	1	'Debug baud rate
DEFINE DEBUG_PACING	1000	'Debug character pacing in us
DEFINE DEBUGIN_REG	PORTB	'Debugin pin port
DEFINE DEBUGIN_BIT	0	'Debugin pin bit
DEFINE DEBUGIN_MODE	1	'Debugin mode: 0 = True, 1 = Inverted
DEFINE HSER_BAUD	2400	'Hser baud rate
DEFINE HSER_CLROERR	1	If characters are not read soon enough from the hardware serial port, an overflow error will occur. In general, the BASIC program should detect this error and clear it by toggling CREN off and back on. A new Define has been added that tells the Hserin command to automatically detect this error and clear it. Keep in mind, characters are being missed when an overflow error occurs.
DEFINE HSER_SPBRG	25	'Hser spbrg init
	'Hser spbrg init	
DEFINE HSER_RCSTA	90h	'Hser receive status init
DEFINE HSER_TXSTA	20h	'Hser transmit status init
DEFINE HSER_EVEN	1	'Use only if even parity desired
DEFINE HSER_ODD	1	'Use only if odd parity desired
DEFINE I2C_HOLD	1	'Pause I2C transmission while clock held low
DEFINE I2C_INTERNAL	1	Use for internal EEPROM on 16CExxx and 2CExxx
DEFINE I2C_SCLOUT	1	'Set serial clock to bipolar instead of open-collector
DEFINE I2C_SLOW	1	'Use for >8MHz OSC with standard speed devices
DEFINE LCD_DREG	PORTA	'LCD data port
DEFINE LCD_DBIT	0	'LCD data starting bit 0 or 4
DEFINE LCD_RSREG	PORTA	'LCD register select port
DEFINE LCD_RSBIT	4	'LCD register select bit
DEFINE LCD_EREG	PORTB	'LCD enable port
DEFINE LCD_EBIT	3	'LCD enable bit
DEFINE LCD_RWREG	PORTE	'LCD read/write port
DEFINE LCD_RWBIT	2	'LCD read/write bit
DEFINE LCD_BITS	4	'LCD bus size 4 or 8
DEFINE LCD_LINES	2	'Number lines on LCD
DEFINE LCD_COMMANDUS	2000	'Command delay time in us
DEFINE LCD_DATAUS	50	'Data delay time in us
DEFINE LOADER_USED	1	tells the compiler that a boot loader, like the melabs Loader, is going to be used to put the program into the PICmicro. This Define moves the compiler's library code out of the first 4 locations.
DEFINE NO_CLRWDT	1	The compiler normally inserts clrwdt instructions throughout the program to keep the Watchdog Timer from timing out, if enabled. This Define tells the

Picbasic Pro Basics

DEFINE OSC	4	compiler not to insert these clrwdt instructions: 'Oscillator speed in MHz: 3(3.58) 4 8 10 12 16 20 25 32 33 40
DEFINE OSC	24	Adding support for the PIC16C745 and 765 low-speed USB devices meant raising the maximum oscillator speed to 24MHz
DEFINE OSCCAL_1K	1	'Set OSCCAL for PIC12C671/CE673,1K devices
DEFINE OSCCAL_2K	1	Set OSCCAL for 2K device
DEFINE PULSIN_MAX	1000	Set a maximum count for Pulsin and Rctime before it stops waiting for a pulse or the end of a pulse:
DEFINE OSCCAL_2K	1	'Set OSCCAL for PIC12C672/CE674
DEFINE SER2_BITS	8	'Set number of data bits for Serin2 and Serout2
DEFINE SHIFT_PAUSEUS	50	'Slow down the Shiftin and Shiftout clock
DEFINE USE_LFSR	1	'Use 18Cxxx LFSR instruction

4.17. Math Operators

Unlike the BASIC Stamp, the PicBasic Pro Compiler performs all math operations in full hierarchal order. This means that there is precedence to the operators. Multiplies and divides are performed before adds and subtracts, for example. To ensure the operations are carried out in the order you would like, use parenthesis to group the operations:

$$A = (B + C) * (D - E)$$

All math operations are unsigned and performed with 16-bit precision. The operators supported are:

Picbasic Pro Basics

Table 7 Maths operators

<i>Math Operators</i>	<i>Description</i>
+	Addition
-	Subtraction
*	Multiplication
**	Top 16 Bits of Multiplication
*/	Middle 16 Bits of Multiplication
/	Division
//	Remainder (Modulus)
<<	Shift Left
>>	Shift Right
ABS	Absolute Value
COS	Cosine
DCD	2n Decode
DIG	Digit
MAX	Maximum*
MIN	Minimum*
NCD	Encode
REV	Reverse Bits
SIN	Sine
SQR	Square Root
&	Bitwise AND
 	Bitwise OR
^	Bitwise Exclusive OR
~	Bitwise NOT
&/	Bitwise NOT AND
 /	Bitwise NOT OR
^/	Bitwise NOT Exclusive OR

*Implementation differs from BASIC Stamp.

4.17.1. Multiplication

PBP performs 16x16 multiplication. The '*' operator returns the lower 16 bits of the 32-bit result. This is the typical multiplication found in most programming languages. The '**' operator returns the upper 16 bits of the 32-bit result. These two operators can be used in conjunction to perform 16x16 multiplication that produces 32-bit results.

```
W1 = W0 * 1000 ' Multiply value in W0 by 1000 and place the result in W1
```

```
W2 = W0 ** 1000 ' Multiply W0 by 1000 and place the high order 16 bits (which may be 0) in W2
```

The '>*/=' operator returns the middle 16 bits of the 32-bit result.

```
W3 = W1 */ W0 ' Multiply W1 by W0 and place the middle 16 bits in W3
```


Picbasic Pro Basics

4.17.2. Division

PBP performs 16x16 division. The '/' operator returns the 16-bit result. The '// operator returns the remainder. This is sometimes referred to as the modulus of the number.

```
W1 = W0 / 1000 ` Divide value in W0 by 1000 and place the  
result in W1
```

```
W2 = W0 // 1000 ` Divide value in W0 by 1000 and place the  
remainder in W2
```

4.17.3. Shift

The '<<' and '>>' operators shift a value left or right, respectively, 0 to 15 times. The newly shifted-in bits are set to 0.

```
B0 = B0 << 3 ` Shifts B0 left 3 places (same as multiply by  
8)
```

```
W1 = W0 >> 1 ` Shifts W0 right 1 position and places result  
in W1 (same as divide by 2)
```

4.17.4. ABS

ABS returns the absolute value of a number. If a byte is greater than 127 (high bit set), **ABS** will return 256 - value. If a word is greater than 32767 (high bit set), **ABS** will return 65536 - value.

```
B1 = ABS B0
```

4.17.5. COS

COS returns the 8-bit cosine of a value. The result is in two's complement form (i.e. -127 to 127). It uses a quarter-wave lookup table to find the result. Cosine starts with a value in binary radians, 0 to 255, as opposed to the usual 0 to 359 degrees.

```
B1 = COS B0
```

4.17.6. DCD

DCD returns the decoded value of a bit number. It changes a bit number (0 - 15) into a binary number with only that bit set to 1. All other bits are set to 0.

```
B0 = DCD 2 ` Sets B0 to %00000100
```

4.17.7. DIG

DIG returns the value of a decimal digit. Simply tell it the digit number (0 - 4 with 0 being the rightmost digit) you would like the value of, and voila.

```
B0 = 123 ` Set B0 to 123
```

```
B1 = B0 DIG 1 ` Sets B1 to 2 (digit 1 of 123)
```

4.17.8. MAX and MIN

MAX and MIN returns the maximum and minimum, respectively, of two numbers. It is usually used to limit numbers to a value.

```
B1 = B0 MAX 100 ` Set B1 to the larger of B0 and 100 (B1 will  
be between 100 & 255)
```

```
B1 = B0 MIN 100 ` Set B1 to the smaller of B0 and 100 (B1  
can't be bigger than 100)
```

Picbasic Pro Basics

4.17.9. NCD

NCD returns the priority encoded bit number (1 - 16) of a value. It is used to find the highest bit set in a value. It returns 0 if no bit is set.

```
B0 = NCD %01001000 ' Sets B0 to 7
```

4.17.10. REV

REV reverses the order of the lowest bits in a value. The number of bits to be reversed is from 1 to 16.

```
B0 = %10101100 REV 4 ' Sets B0 to %10100011
```

4.17.11. SIN

SIN returns the 8-bit sine of a value. The result is in two's complement form (i.e. -127 to 127). It uses a quarter-wave lookup table to find the result. Sine starts with a value in binary radians, 0 to 255, as opposed to the usual 0 to 359 degrees.

```
B1 = SIN B0
```

4.17.12. SQR

SQR returns the square root of a value. Since PicBasic Pro only works with integers, the result will always be an 8-bit integer no larger than the actual result.

```
B0 = SQR W1 ' Sets B0 to square root of W1
```

4.17.13. Bitwise Operators

Bitwise operators act on each bit of a value in boolean fashion. They can be used to isolate bits or add bits into a value.

```
B0 = B0 & %00000001 ' Isolate bit 0 of B0  
B0 = B0 | %00000001 ' Set bit 0 of B0  
B0 = B0 ^ %00000001 ' Reverse state of bit 0 of B0
```

4.18. Comparison Operators

Comparison operators are used in **IF . . THEN** statements to compare one expression with another. The operators supported are:

Table 8 Comparison operators

Comparison Operator	Description
= or ==	Equal
<> or !=	Not Equal
<	Less Than
>	Greater Than
<=	Less Than or Equal
>=	Greater Than or Equal

```
If i > 10 Then loop
```

Picbasic Pro Basics

4.19. Logical Operators

Logical operators differ from bitwise operations. They yield a true/false result from their operation. Values of 0 are treated as false. Any other value is treated as true. They are mostly used in conjunction with the comparison operators in an **IF . . THEN** statement. The operators supported are:

Table 9 Logical operators

<i>Logical Operator</i>	<i>Description</i>
AND or &&	Logical AND
OR or	Logical OR
XOR or ^^	Logical Exclusive OR
NOT AND	Logical NAND
NOT OR	Logical NOR
NOT XOR	Logical NXOR

```
If (A == big) AND (B > mean) Then run
```

Be sure to use parenthesis to tell PBP the exact order you want the operations to be performed.

Picbasic Pro Statement Reference

5. PicBasic Pro Statement Reference

<i>Command</i>	<i>Description</i>
@	Insert one line of assembly language code.
ADCIN	Read on-chip analog to digital converter
ASM..ENDASM	Insert assembly language code section.
BRANCH	Computed GOTO (equiv. to ON..GOTO).
BRANCHL BRANCH	out of page (long BRANCH).
BUTTON	Debounce and auto-repeat input on specified pin.
CALL	Call assembly language subroutine
CLEAR	Zero all variables
CLEARWDT	Clear (tickle) Watchdog Timer
COUNT	Count number of pulses on a pin
DATA	Define initial contents of on-chip EEPROM
DEBUG	Asynchronous serial output to fixed pin and baud
DEBUGIN	Asynchronous serial input from fixed pin and baud
DISABLE	Disable ON DEBUG and ON INTERRUPT processing
DISABLE DEBUG	Disable ON DEBUG processing
DISABLE INTERRUPT	Disable ON INTERRUPT processing
DTMFOUT	Produce touch-tones on a pin
EEPROM	Define initial contents of on-chip EEPROM
ENABLE	Enable ON DEBUG and ON INTERRUPT processing
ENABLE DEBUG	Enable ON DEBUG processing
ENABLE INTERRUPT	Enable ON INTERRUPT processing
END	Stop execution and enter low power mode
FOR..NEXT	Repeatedly execute statements
FREQOUT	Produce up to 2 frequencies on a pin
GOSUB	Call BASIC subroutine at specified label
GOTO	Continue execution at specified label
HIGH	Make pin output high
HPWM	Output hardware pulse width modulated pulse train
HSERIN	Hardware asynchronous serial input
HSEROUT	Hardware asynchronous serial output
I2CREAD	Read from I2C device
I2CWRITE	Write to I2C device
IF..THEN..ELSE..ENDIF	Conditionally execute statements
INPUT	Make pin an input
LCDIN	Read from LCD RAM
LCDOUT	Display characters on LCD
{LET}	Assign result of an expression to a variable
LOOKDOWN	Search constant table for value
LOOKDOWN2	Search constant / variable table for value
LOOKUP	Fetch constant value from table
LOOKUP2	Fetch constant / variable value from table
LOW	Make pin output low
NAP	Power down processor for short period of time
ON DEBUG	Execute BASIC debug monitor
ON INTERRUPT	Execute BASIC subroutine on an interrupt
OWIN	One-wire input.

Picbasic Pro Statement Reference

OWOUT	One-wire output
OUTPUT	Make pin an output
PAUSE	Delay (1mSec resolution).
PAUSEUS	Delay (1uSec resolution).
PEEK	Read byte from register
POKE	Write byte to register
POT	Read potentiometer on specified pin
PULSIN	Measure pulse width on a pin
PULSOUT	Generate pulse to a pin
PWM	Output pulse width modulated pulse train to pin
RANDOM	Generate pseudo-random number
RCTIME	Measure pulse width on a pin
READ	Read byte from on-chip EEPROM
READCODE	Read word from code memory
RESUME	Continue execution after interrupt handling
RETURN	Continue at statement following last GOSUB.
REVERSE	Make output pin an input or an input pin an output
SELECT CASE	Compare a variable with different values
SERIN	Asynchronous serial input (BS1 style).
SERIN2	Asynchronous serial input (BS2 style).
SEROUT	Asynchronous serial output (BS1 style).
SEROUT2	Asynchronous serial output (BS2 style).
SHIFTIN	Synchronous serial input
SHIFTOUT	Synchronous serial output.
SLEEP	Power down processor for a period of time
SOUND	Generate tone or white-noise on specified pin
STOP	Stop program execution
SWAP	Exchange the values of two variables
TOGGLE	Make pin output and toggle state
USBIN	USB input.
USBINIT	Initialize USB
USBOUT	USB output
WHILE..WEND	Execute statements while condition is true
WRITE	Write byte to on-chip EEPROM
WRITECODE	Write word to code memory
XIN	X-10 input.
XOUT	X-10 output.

Picbasic Pro Statement Reference

5.1 @ Statement

When used at the beginning of a line, @ provides a shortcut for inserting one assembly language *Statement* into your PBP program. You can use this shortcut to freely mix assembly language code with PicBasic Pro statements.

```
i      var      byte
rollme var      byte
```

```
For i = 1 to 4
```

```
@      rlf      _rollme, F ; Rotate byte left once
```

```
Next i
```

The @ shortcut can also be used to include assembly language routines in another file. For example:

```
@ Include "fp.asm"
```

@ resets the register page to 0 before executing the assembly language instruction. The register page should not be altered using @.

See the section on assembly language programming for more information.

Picbasic Pro Statement Reference

5.2. ADCIN

`ADCIN Channel,Var`

Read the on-chip analog to digital converter *Channel* and store the result in *Var*. While the ADC registers can be accessed directly, `ADCIN` makes the process a little easier. Before `ADCIN` can be used, the appropriate TRIS register must be set to make the desired pins inputs. ADCON1 also needs to be set to assign the desired pins to analog inputs and in some cases to set the result format and clock source. See the Microchip data sheets for more information on these registers and how to set them for the specific device. Several `DEFINES` may also be used:

```
DEFINE ADC_BITS 8          ' Set number of bits in result
DEFINE ADC_CLOCK 3        ' Set clock source (rc = 3)
DEFINE ADC_SAMPLEUS 50    ' Set sampling time in microseconds

TRISA = 255                ' Set PORTA to all input
ADCON1 = 2                 ' PORTA is analog
ADCIN 0, B0                ' Read channel 0 to B0
```

ANALOG-TO-DIGITAL CONVERTER (A/D) MODULE

12C67x devices – A/D

The Analog-To-Digital (A/D) converter module has four analog inputs. The A/D allows conversion of an analog input signal to a corresponding 8-bit digital number (refer to Application Note AN546 for use of A/D Converter). The output of the sample and hold is the input into the converter, which generates the result via successive approximation.

The analog reference voltage is software selectable to either the device's positive supply voltage (VDD) or the voltage level on the GP1/AN1/VREF pin. The A/D converter has a unique feature of being able to operate while the device is in SLEEP mode. The A/D module has three registers.

These registers are:

- A/D Result Register (ADRES)
- A/D Control Register 0 (ADCON0)
- A/D Control Register 1 (ADCON1)

The ADCON0 Register controls the operation of the A/D module. The ADCON1 Register configures the functions of the port pins. The port pins can be configured as analog inputs (GP1 can also be a voltage reference) or as digital I/O.

ADCON0 Register – A/D module control

ADCS	ADCS0	reserved	CHS1	CHS0	GO/DONE	reserved	ADON
R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0
bit7							bit0

R =Readable bit

W =Writable bit

U =Unimplemented bit, read as '0'

- n = Value at POR reset

bit 7-6: **ADCS<1:0>**: A/D Conversion Clock Select bits

00 = Fosc/2

Picbasic Pro Statement Reference

01 = Fosc/8
 10 = Fosc/32
 11 = FRC (clock derived from an RC oscillation)

bit 5: **Reserved**

bit 4-3: **CHS<1:0>**: Analog Channel Select bits

00 = channel 0, (GP0/AN0)
 01 = channel 1, (GP1/AN1)
 10 = channel 2, (GP2/AN2)
 11 = channel 3, (GP4/AN3)

bit 2: **GO/DONE**: A/D Conversion Status bit

If ADON = 1

1 = A/D conversion in progress (setting this bit starts the A/D conversion)
 0 = A/D conversion not in progress (this bit is automatically cleared by hardware when the A/D conversion is complete)

bit 1: **Reserved**

bit 0: **ADON**: A/D on bit

1 = A/D converter module is operating
 0 = A/D converter module is shut off and consumes no operating current

Note 1: If the port pins are configured as analog inputs (reset condition), reading the port (MOVWF GPIO,W) results in reading '0's.

2: Changing ADCON1 Register can cause the GPIF and INTF flags to be set in the INTCON Register. These interrupts should be disabled prior to modifying ADCON1.

ADCON1 REGISTER - Port pin function configuration

U-0	U-0	U-0	U-0	U-0	R/W-0	R/W-0	R/W-0
—	—	—	—	—	PCFG2	PCFG1	PCFG0

Bit 7 Bit 0

R =Readable bit

W =Writable bit

U =Unimplemented bit, read as '0'

- n =Value at POR reset

bit 7-2: **Unimplemented**: Read as '0'

bit 1-0: **PCFG<2:0>**: A/D Port Configuration Control bits

ADCON1 REGISTER - Port pin function configuration

PCFG<2:0>	GP4	GP2	GP1	GP0	VREF
000(1)	A	A	A	A	VDD
001	A	A	VREF	A	GP1
010	D	A	A	A	VDD
011	D	A	VREF	A	GP1
100	D	D	A	A	VDD
101	D	D	VREF	A	GP1
110	D	D	D	A	VDD
111	D	D	D	D	VDD

A = Analog input

D = Digital I/O

Note 1: Value on reset.

2: Any instruction that reads a pin configured as an analog input will read a '0'.

The ADRES Register contains the result of the A/D conversion. When the A/D conversion is complete, the result is loaded into the ADRES register, the GO/DONE bit (ADCON0<2>) is cleared, and A/D interrupt flag bit ADIF (PIE1<6>) is set.

Picbasic Pro Statement Reference

After the A/D module has been configured as desired, the selected channel must be acquired before the conversion is started. The analog input channels must have their corresponding TRIS bits selected as an input.

. After this acquisition time has elapsed, the A/D conversion can be started. The following steps should be followed for doing an A/D conversion:

1. Configure the A/D module:
 - Configure analog pins / voltage reference / and digital I/O (ADCON1 and TRIS)
 - Select A/D input channel (ADCON0)
 - Select A/D conversion clock (ADCON0)
 - Turn on A/D module (ADCON0)
 2. Configure A/D interrupt (if desired):
 - Clear ADIF bit
 - Set ADIE bit
 - Set GIE bit
 3. Wait the required acquisition time.
 4. Start conversion:
 - Set GO/DONE bit (ADCON0)
 5. Wait for A/D conversion to complete, by either:
 - Polling for the GO/DONE bit to be clearedOR
 - Waiting for the A/D interrupt
 6. Read A/D Result Register (ADRES), clear bit ADIF if required.
 7. For the next conversion, go to step 1, step 2 or step 3 as required.
- The A/D conversion time per bit is defined as T_{AD} . A minimum wait of $2T_{AD}$ is required before next acquisition starts.

16F87x devices – A/D

From the 16F87x datasheet

For 16F87x devices the Analog-to-Digital (A/D) Converter module has five inputs for the 28-pin devices and eight for the other devices.

The analog input charges a sample and hold capacitor. The output of the sample and hold capacitor is the input into the converter. The converter then generates a digital result of this analog level via successive approximation.

The A/D conversion of the analog input signal results in a corresponding 10-bit digital number. The A/D module has high and low voltage reference input that is software selectable to some combination of VDD, VSS, RA2 or RA3.

The A/D converter has a unique feature of being able to operate while the device is in SLEEP mode. To operate in sleep, the A/D clock must be derived from the A/D's internal RC oscillator.

The A/D module has four registers. These registers are:

- A/D Result High Register (ADRESH)
- A/D Result Low Register (ADRESL)
- A/D Control Register0 (ADCON0)
- A/D Control Register1 (ADCON1)

The ADCON0 register, shown below controls the operation of the A/D module.

The ADCON1 register configures the functions of the port pins.

The port pins can be configured as analog inputs (RA3 can also be the voltage reference) or as digital I/O.

Picbasic Pro Statement Reference

Additional information on using the A/D module can be found in the PICmicro™ Mid-Range MCU Family Reference Manual (DS33023).

ADCON0 REGISTER - A/D module control							
ADCS1	ADCS0	CHS2	CHS1	CHS0	GO/DONE	—	ADON
R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	R/W-0	0 U	R/W-0

R = Readable bit
W = Writable bit

U = Unimplemented bit, read as '0'
- n = Value at POR reset

bit7 bit0

bit 7-6: **ADCS1:ADCS0: A/D Conversion Clock Select bits**

- 00 = FOSC/2
- 01 = FOSC/8
- 10 = FOSC/32
- 11 = FRC (clock derived from an RC oscillation)

bit 5-3: **CHS2:CHS0: Analog Channel Select bits**

- 000 = channel 0, (RA0/AN0)
- 001 = channel 1, (RA1/AN1)
- 010 = channel 2, (RA2/AN2)
- 011 = channel 3, (RA3/AN3)
- 100 = channel 4, (RA5/AN4)
- 101 = channel 5, (RE0/AN5)(1)
- 110 = channel 6, (RE1/AN6)(1)
- 111 = channel 7, (RE2/AN7)(1)

bit 2: **GO/DONE: A/D Conversion Status bit**

If ADON = 1

- 1 = A/D conversion in progress (setting this bit starts the A/D conversion)
- 0 = A/D conversion not in progress (This bit is automatically cleared by hardware when the A/D conversion is complete)

bit 1: **Unimplemented:** Read as '0'

bit 0: **ADON: A/D On bit**

- 1 = A/D converter module is operating
- 0 = A/D converter module is shutoff and consumes no operating current

Note 1: These channels are not available on the 28-pin devices.

ADCON1 REGISTER - Port pin function configuration							
U-0	U-0	R/W-0	U-0	R/W-0	R/W-0	R/W-0	R/W-0
ADFM	—	—	—	PCFG3	PCFG2	PCFG1	PCFG0
bit7							bit0

R = Readable bit, W = Writable bit,
U = Unimplemented bit, read as '0'
n = Value at POR reset

Picbasic Pro Statement Reference

bit 7: ADFM: A/D Result format select

1 = Right Justified. 6 most significant bits of ADRESH are read as '0'.

0 = Left Justified. 6 least significant bits of ADRESL are read as '0'.

bit 6-4: Unimplemented: Read as '0'

bit 3-0: PCFG3:PCFG0: A/D Port Configuration Control bits

Port configuration bits, 0-3

PCFG3 PCFG0	AN7 RE2 (1)	AN6 RE1 (1)	AN5 RE0 (1)	AN4 RA5	AN3 RA3	AN2 RA2	AN1 RA1	AN0 RA0	VREF+	VREF-	CHAN /Refs (2)
0000	A	A	A	A	A	A	A	A	VDD	VSS	8/0
0001	A	A	A	A	Vref+	A	A	A	RA3	VSS	7/1
0010	D	D	D	A	A	A	A	A	VDD	VSS	5/0
0011	D	D	D	A	Vref+	A	A	A	RA3	VSS	4/1
0100	D	D	D	D	A	D	A	A	VDD	VSS	3/0
0101	D	D	D	D	Vref+	D	A	A	RA3	VSS	2/1
011x	D	D	D	D	D	D	D	D	VDD	VSS	0/0
1000	A	A	A	A	Vref+	Vref-	A	A	RA3	RA2	6/2
1001	D	D	A	A	A	A	A	A	VDD	VSS	6/0
1010	D	D	A	A	Vref+	A	A	A	RA3	VSS	5/1
1011	D	D	A	A	Vref+	Vref--	A	A	RA3	RA2	4/2
1100	D	D	D	A	Vref+	Vref--	A	A	RA3	RA2	3/2
1101	D	D	D	D	Vref+	Vref--	A	A	RA3	RA2	2/2
1110	D	D	D	D	D	D	D	A	VDD	VSS	1/0
1111	D	D	D	D	Vref+	Vref--	D	A	RA3	RA2	1/2

A = Analog input

D = Digital I/O

Note 1: These channels are not available on the 28-pin devices.

2: This column indicates the number of analog channels available as A/D inputs and the number of analog channels used as voltage reference inputs.

Picbasic Pro Statement Reference

5.3. ASM..ENDASM

ASM

ENDASM

The **ASM** and **ENDASM** instructions tells PBP that the code between these two lines is in assembly language and should not be interpreted as PicBasic Pro statements. You can use these two instructions to freely mix assembly language code with PicBasic Pro statements. The maximum size for an assembler text section is 8K. This is the maximum size for the actual source, including comments, not the generated code. If the text block is larger than this, break it into multiple **ASM** . **ENDASM** sections or simply include it in a separate file. **ASM** resets the register page to 0. You must ensure that the register page is reset to 0 before **ENDASM** if the assembly language code has altered it.

See the section on assembly language programming for more information.

ASM

```
bsf PORTA, 0      ; Set bit 0 on PORTA
bcf PORTB, 0      ; Clear bit 0 on PORTB
```

ENDASM

Picbasic Pro Statement Reference

5.4. BRANCH

BRANCH *Index*, [*Label*{, *Label*...}]

BRANCH causes the program to jump to a different location based on a variable index. This is similar to On..Goto in other BASICs.

Index selects one of a list of labels. Execution resumes at the indexed label. For example, if *Index* is zero, the program jumps to the first label specified in the list, if *Index* is one, the program jumps to the second label, and so on. If *Index* is greater than or equal to the number of labels, no action is taken and execution continues with the statement following the **BRANCH**. Up to 255 (256 for 18Cxxx) *Labels* may be used in a **BRANCH**.

Label must be in the same code page as the **BRANCH** instruction. If you cannot be sure they will be in the same code page, use **BRANCHL** below.

BRANCH B4,[dog,cat,fish]

‘ Same as:

‘ If B4=0 Then dog (goto dog)

‘ If B4=1 Then cat (goto cat)

‘ If B4=2 Then fish (goto fish)

Picbasic Pro Statement Reference

5.5. BRANCHL

BRANCHL *Index*, [*Label*{, *Label*...}]

BRANCHL (**BRANCH** long) works very similarly to **BRANCH** in that it causes the program to jump to a different location based on a variable index. The main differences are that it can jump to a *Label* that is in a different code page than the **BRANCHL** instruction and that it generates code that is about twice the size as code generated by the **BRANCH** instruction. If you are sure the labels are in the same page as the **BRANCH** instruction or if the microcontroller does not have more than one code page (2K or less of ROM), using **BRANCH** instead of **BRANCHL** will minimize memory usage.

Index selects one of a list of labels. Execution resumes at the indexed label. For example, if *Index* is zero, the program jumps to the first label specified in the list, if *Index* is one, the program jumps to the second label, and so on. If *Index* is greater than or equal to the number of labels, no action is taken and execution continues with the statement following the **BRANCHL**. Up to 127 (256 for 18Cxxx) *Labels* may be used in a **BRANCHL**.

BRANCHL B4,[dog,cat,fish]

‘ Same as:

‘ If B4=0 Then dog (goto dog)

‘ If B4=1 Then cat (goto cat)

‘ If B4=2 Then fish (goto fish)

Picbasic Pro Statement Reference

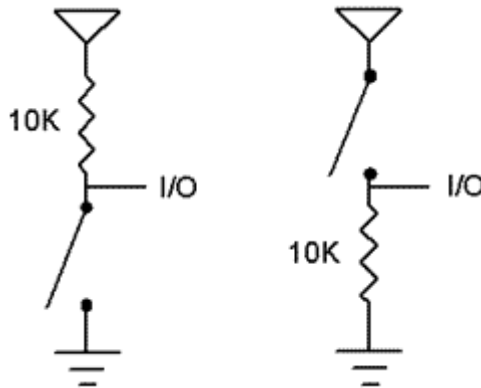
5.6. BUTTON

BUTTON *Pin,Down,Delay,Rate,BVar,Action,Label*

Read *Pin* and optionally performs debounce and auto-repeat. *Pin* is automatically made an input. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

Table 10 Button command parameters

<i>Parm</i>	<i>Description</i>
Down	State of pin when button is pressed (0..1).
Delay	Cycle count before auto-repeat starts (0..255). If 0, no debounce or auto-repeat is performed. If 255, debounce, but no auto-repeat, is performed.
Rate	Auto-repeat rate (0..255).
BVar	Byte-sized variable used internally for delay/repeat countdown. It must be initialized to 0 prior to use and not used elsewhere in the program.
Action	State of button to act on (0 if not pressed, 1 if pressed).
Label	Execution resumes at this label if Action is true.



' Goto notpressed if button not pressed on Pin2

BUTTON *PORTB.2,0,100,10,B2,0,notpressed*

BUTTON needs to be used within a loop for auto-repeat to work properly.

BUTTON accomplishes debounce by delaying program execution for a period of milliseconds to wait for the contacts to settle down. The default debounce delay is 10ms. To change the debounce to another value, use **DEFINE**:

```
> Set button debounce delay to 50ms
```

```
DEFINE BUTTON_PAUSE 50
```

Be sure that **BUTTON_PAUSE** is all in upper case.

In general, it is easier to simply read the state of the pin in an **IF** . . **THEN** than to use the **BUTTON** command as follows:

```
If PORTB.2 = 1 Then notpressed
```

Picbasic Pro Statement Reference

Button Example

' BUTTON Command

' Demonstate BUTTON command. Prints working variable (in this case B0) to

' show how auto-repeat works. Prints "PRESS" when button is pressed or

' repeated.

```
Include "modedefs.bas"      ' Include serial modes

SO  con  0                  ' Define serial output pin
B   con  5                  ' Define Button input pin

B0  var  byte
B0 = 0                      ' Zero Button Working Buffer
loop: Button B,1,10,5,B0,0,notp ' Check Button (Skip if Not Pressed)
      Serout SO,N2400,["Press",13,10] ' Indicate Button Pressed
notp: Serout SO,N2400,[#B0,13,10]  ' Show Working Variable
      Pause 100                  ' Visual Pause
      Goto loop                  ' Forever
```


Picbasic Pro Statement Reference

5.7. CALL

CALL *Label*

Execute the assembly language subroutine named *Label*.

GOSUB is normally used to execute a PicBasic Pro subroutine. The main difference between **GOSUB** and **CALL** is that with **CALL**, *Label*'s existence is not checked until assembly time. Using **CALL**, a *Label* in an assembly language section can be accessed that is otherwise inaccessible to PBP.

See the section on assembly language programming for more information on **CALL**.

CALL *pass* ' Execute assembly language subroutine named *_pass*

Picbasic Pro Statement Reference

5.8. CLEAR

CLEAR

Set all RAM registers to zero.

CLEAR zeroes all the RAM registers in each bank. This will set all variables, including the internal system variables to zero. This is not automatically done when a PBP program starts as it is on a BASIC Stamp. In general, the variables should be set in the program to an appropriate initial state rather than using **CLEAR**.

CLEAR ' Clear all variables to 0

Picbasic Pro Statement Reference

5.9. CLEARWDT

CLEARWDT

Clear (tickle) the Watchdog Timer.

The Watchdog Timer is used in conjunction with the **SLEEP** and **NAP** instructions to wake the PICmicro after a certain period of time. Assembler instructions (clrwdt) to keep the Watchdog Timer from timing out under normal circumstances and resetting the PICmicro are automatically inserted at appropriate places throughout the program.

CLEARWDT allows the placement of additional clrwdt instructions in the program.

CLEARWDT ' Clear Watchdog Timer

The compiler normally inserts clrwdt instructions throughout the program to keep the Watchdog Timer from timing out, if enabled. A new Define tells the compiler not to insert these clrwdt instructions:

SEE also Define NO_CLRWDT 1

Picbasic Pro Statement Reference

5.10.COUNT

COUNT *Pin,Period,Var*

Count the number of pulses that occur on *Pin* during the *Period* and stores the result in *Var*. *Pin* is automatically made an input. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

The resolution of *Period* is in milliseconds. It tracks the oscillator frequency based on the **DEFINED** OSC.

COUNT checks the state of *Pin* in a tight loop and counts the low to high transitions. With a 4MHz oscillator it checks the pin state every 20us. With a 20MHz oscillator it checks the pin state every 4us. From this, it can be determined that the highest frequency of pulses that can be counted is 25KHz with a 4MHz oscillator and 125KHz with a 20MHz oscillator if the frequency has a 50% duty cycle (the high time is the same as the low time).

' Count # of pulses on Pin1 in 100 milliseconds

COUNT PORTB.1, 100, W1

' Determine frequency on a pin

COUNT PORTA.2, 1000, W1

' Count for 1 second

Serout PORTB.0, N2400, [W1]

Picbasic Pro Statement Reference

5.11. DATA

```
DATA {@Location,} Constant{, Constant...}
```

Store constants in on-chip non-volatile EEPROM when the device is first programmed. If the optional *Location* value is omitted, the first **DATA** statement starts storing at address 0 and subsequent statements store at the following locations. If the *Location* value is specified, it denotes the starting location where these values are stored. An optional label can be assigned to the starting EEPROM address for later reference by the program.

Constant can be a numeric constant or a string constant. Only the least significant byte of numeric values are stored unless the **WORD** modifier is used. Strings are stored as consecutive bytes of ASCII values. No length or terminator is automatically added.

DATA only works with microcontrollers with on-chip EEPROM such as the PIC16F84 and PIC16C84. It will not work on devices with on-chip I2C interfaced serial EEPROM like the 12CE67x and 16CE62x parts. Since EEPROM is non-volatile memory, the data will remain intact even if the power is turned off.

The data is stored in the EEPROM space only once at the time the microcontroller is programmed, not each time the program is run. **WRITE** can be used to set the values of the on-chip EEPROM at runtime.

' Store 10, 20 and 30 starting at location 5

```
DATA @5,10,20,30
```

' Assign a label to a word at the next location

```
dlabel DATA word $1234 ' Stores $34, $12
```

' Skip 4 locations and store 10 0s

```
DATA (4), 0(10)
```

Picbasic Pro Statement Reference

5.12. DEBUG

DEBUG *Item*{,*Item*...}

Send one or more *Items* to a predefined pin at a predefined baud rate in standard asynchronous format using 8 data bits, no parity and 1 stop bit (8N1). The pin is automatically made an output.

If a pound sign (#) precedes an *Item*, the ASCII representation for each digit is sent serially. **DEBUG** also supports the same data modifiers as **SEROUT2**. Refer to the section on **SEROUT2** for this information.

Table 11 Debug command modifiers

<i>Modifier</i>	<i>Operation</i>
{I} {S}BIN{1..16}	Send binary digits
{I} {S}DEC{1..5}	Send decimal digits
{I} {S}HEX{1..4}	Send hexadecimal digits
REP c\n	Send character c repeated n times
STR ArrayVar{n}	Send string of n characters

DEBUG is one of several built-in asynchronous serial functions. It is the smallest of the software generated serial routines. It can be used to send debugging information (variables, program position markers, etc.) to a terminal program like Hyperterm. It can also be used anytime serial output is desired on a fixed pin at a fixed baud rate.

The serial pin and baud rate are specified using **DEFINEs**:

```
' Set Debug pin port
DEFINE DEBUG_REG      PORTB

' Set Debug pin bit
DEFINE DEBUG_BIT      0

' Set Debug baud rate
DEFINE DEBUG_BAUD     2400

' Set Debug mode: 0 = true, 1 = inverted
DEFINE DEBUG_MODE     1
```

DEBUG assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to any different oscillator value.

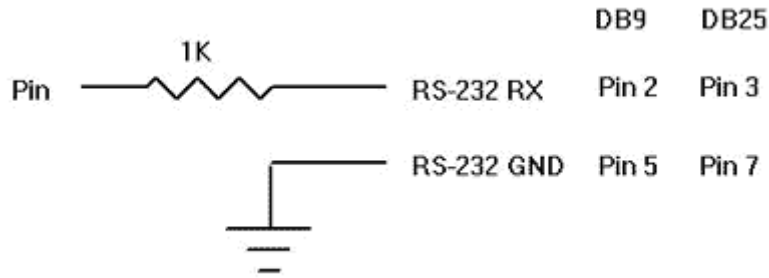
In some cases, the transmission rates of **DEBUG** instructions may present characters too quickly to the receiving device. A **DEFINE** adds character pacing to the serial output transmissions. This allows additional time between the characters as they are transmitted. The character pacing **DEFINE** allows a delay of 1 to 65,535 microseconds (.001 to 65.535 milliseconds) between each character transmitted.

For example, to pause 1 millisecond between the transmission of each character:

```
DEFINE DEBUG_PACING 1000
```

While single-chip RS-232 level converters are common and inexpensive, thanks to current RS-232 implementation and the excellent I/O specifications of the PICmicro, most applications don't require level converters. Rather, inverted TTL (**DEBUG_MODE** = 1) can be used. A current limiting resistor is suggested (RS-232 is suppose to be short-tolerant).

Picbasic Pro Statement Reference



' Send the text "B0=" followed by the decimal value of B0 and a linefeed out serially
DEBUG "B0=", dec B0, 10

Additional DEBUG Instructions

Also new are the instructions **On Debug Goto**, **Disable Debug** and **Enable Debug**.

These instructions allow a monitor program to be written that can take control of the program in between each PicBasic Pro instruction.

The method by which this happens is similar to the method used by On Interrupt Goto. Once On Debug Goto is encountered, a call to the specified debug label is inserted before each PicBasic Pro instruction in the program.

Disable Debug prevents the insertion of this call while Enable Debug resumes the insertion of the call.

A monitor routine may be written that is activated before each instruction.

This routine can send data to an LCD or to a serial comm program. Any program information may be displayed or even altered in this manner. A small monitor program example is posted on the melabs web site.

A definition is required to provide a word-sized variable to store the address the program was at before the monitor routine was called by On Debug Goto:

```
DEBUG_ADDRESS var word bank0 system
```

An additional definition may be used to return the level of the current program stack:

```
DEBUG_STACK var byte bank0 system
```

This level should not be greater than 4 in a PicBasic Pro program. The supplied variable will be incremented at each Gosub and decremented at

Picbasic Pro Statement Reference

each Return.

The actual stack contents may be saved by creating an array variable with a specific name to which the addresses will be saved:

```
DEBUG_STACK_ADDR var word[4] bank0 system
```

When PicBasic Pro sees this variable defined, It will store the return address of each Gosub it encounters into this array. DEBUG_STACK, above, must also be defined to use the stack address array.

Picbasic Pro Statement Reference

5.13. DEBUGIN

DEBUGIN {*Timeout*, *Label*, } [*Item*{, *Item*...}]

Receive one or more *Items* from a predefined pin at a predefined baud rate in standard asynchronous format using 8 data bits, no parity and 1 stop bit (8N1). The pin is automatically made an input.

An optional *Timeout* and *Label* may be included to allow the program to continue if a character is not received within a certain amount of time. *Timeout* is specified in units of 1 millisecond.

Debugin is the converse of **Debug**. It will read serial input from a fixed pin at a fixed baud rate (the same baud rate as **Debug**). Several new **Defines** may be used in conjunction with **Debugin**:

```
Define DEBUGIN_REG PORTB      ' Debugin pin port
Define DEBUGIN_BIT 0         ' Debugin pin bit
Define DEBUGIN_MODE 1       ' Debugin mode: 0 = true, 1 = inverted
```

DEBUGIN supports the same data modifiers as **SERIN2**. Refer to the section on **SERIN2** for this information.

Table 12 **DEBUGIN** command modifiers

<i>Modifier</i>	<i>Operation</i>
BIN{1..16}	Receive binary digits
DEC{1..5}	Receive decimal digits
HEX{1..4}	Receive hexadecimal digits
SKIP n	Skip n received characters
STR ArrayVar\n{c}	Receive string of n characters optionally ended in character c
WAIT ()	Wait for sequence of characters
WAITSTR ArrayVar{n}	Wait for character string

Any of the **Hserin2** modifiers, with the exception of parity, may be used with **Debugin**:

```
Debugin {Timeout, Label,}[Item{...}]
Debugin [B0, dec W1]
```

DEBUGIN is one of several built-in asynchronous serial functions. It is the smallest of the software generated serial routines. It can be used to receive debugging information from a terminal program like **Hyperterm**. It can also be used anytime serial input is desired on a fixed pin at a fixed baud rate.

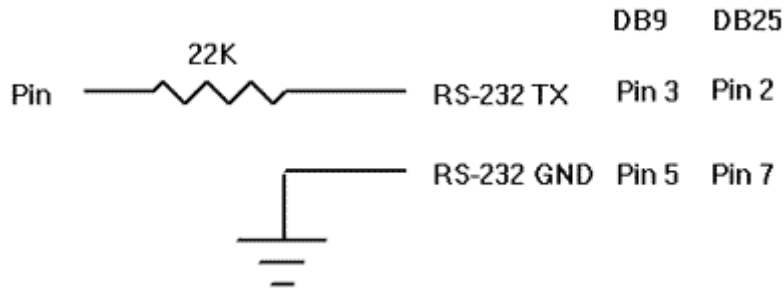
The serial pin and baud rate are specified using **DEFINES**

If any of the **DEFINES** are not included in a program, the **DEBUGIN** port, pin or mode is set to the same values as they are for **DEBUG**. The **DEBUGIN** baud rate is always the same as **DEBUG=s**. It cannot be **DEFINED** differently.

Picbasic Pro Statement Reference

DEBUGIN assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to any different oscillator value.

While single-chip RS-232 level converters are common and inexpensive, thanks to current RS-232 implementation and the excellent I/O specifications of the PICmicro, most applications don't require level converters. Rather, inverted TTL (**DEBUGIN_MODE** = 1) can be used. A current limiting resistor is suggested (RS-232 is suppose to be short-tolerant).



' Wait until the character "A" is received serially and put next character into B0

```
DEBUGIN [wait ("A"),B0]
```

' Skip 2 chars and grab a 4 digit decimal number

```
DEBUGIN [skip 2,dec4 B0]
```

Also added are Disable Interrupt and Enable Interrupt. These instructions disable and enable the placement of interrupt check calls in the program as Disable and Enable previously did. Disable and Enable have be altered to stop and start the insertion of both On Interrupt Goto and On Debug Goto calls.

Picbasic Pro Statement Reference

5.14. DISABLE

5.14.1 DISABLE

DISABLE

DISABLE both debug and interrupt processing following this instruction. Interrupts can still occur but the BASIC interrupt handler in the PicBasic Pro program and the debug monitor will not be executed until an **ENABLE** is encountered.

DISABLE and **ENABLE** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON DEBUG** and **ON INTERRUPT** for more information.

```
DISABLE ' Disable interrupts in handler
myint: led = 1      ' Turn on LED when interrupted
Resume ' Return to main program
Enable ' Enable interrupts after handler
```

5.14.2 DISABLE DEBUG

DISABLE DEBUG

DISABLE DEBUG processing following this instruction. The debug monitor will not be called between instructions until an **ENABLE** or **ENABLE DEBUG** is encountered.

DISABLE DEBUG and **ENABLE DEBUG** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON DEBUG** for more information.

```
DISABLE DEBUG > Disable debug monitor calls
```

5.14.3 DISABLE INTERRUPT

DISABLE INTERRUPT

DISABLE INTERRUPT processing following this instruction. Interrupts can still occur but the BASIC interrupt handler in the PicBasic Pro program will not be executed until an **ENABLE** or **ENABLE INTERRUPT** is encountered.

DISABLE INTERRUPT and **ENABLE INTERRUPT** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON INTERRUPT** for more information.

```
DISABLE INTERRUPT ' Disable interrupts in handler
myint: led = 1      ' Turn on LED when interrupted
Resume ' Return to main program
Enable Interrupt ' Enable interrupts after handler
```

Picbasic Pro Statement Reference

5.15. Div32 Function

PBPs multiply (*) function operates as a 16-bit x 16-bit multiply yielding a 32-bit result. However, since the compiler only supports a maximum variable size of 16 bits, access to the result had to happen in 2 steps: $c = b * a$ returns the lower 16 bits of the multiply while $d = b ** a$ returns the upper 16 bits. There was no way to access the 32-bit result as a unit.

In many cases it is desirable to be able to divide the entire 32-bit result of the multiply by a 16-bit number for averaging or scaling. A new function has been added for this purpose: Div32. Div32 is actually limited to dividing a 31-bit unsigned integer (max 2147483647) by a 15-bit unsigned integer (max 32767). This should suffice in most circumstances.

As the compiler only allows a maximum variable size of 16 bits, Div32 relies that a multiply was just performed and that the internal compiler variables still contain the 32-bit result of the multiply. No other operation may occur between the multiply and the Div32 or the internal variables may be altered, destroying the 32-bit multiplication result.

This means, among other things, that On Interrupt must be Disabled from before the multiply until after the Div32. If On Interrupt is not used, there is no need to add Disable to the program. Interrupts in assembler should have no effect on the internal variables so they may be used without regard to Div32.

The following code fragment shows the operation of Div32:

```
a  var  word
b  var  word
c  var  word
dummy var  word

    b = 500
    c = 1000

    Disable      ' Necessary if On Interrupt used

    dummy = b * c ' Could also use ** or */
    a = Div32 100

    Enable      ' Necessary if On Interrupt used
```

This program assigns b the value 500 and c the value 1000. When multiplied together, the result would be 500000. This number exceeds the 16-bit word size of a variable (65535). So the dummy variable contains only the lower 16 bits of the result. In any case, it is not used by the Div32 function. Div32 uses variables internal to the compiler as the operands.

In this example, Div32 divides the 32-bit result of the multiplication $b * c$ by 100 and stores the result of this division, 5000, in the word-sized variable a.

Picbasic Pro Statement Reference

DIV32 Example

```
' PicBasic Pro program to demonstrate the Div32 command.
' Div32 must be used immediately after a multiply statement
' in order to retain the state of the internal registers of
' the device.

' Define Debug pin

DEFINE DEBUG_REGPORTC
DEFINE DEBUG_BIT 6
DEFINE DEBUG_BAUD    9600
DEFINE DEBUG_MODE    1

' Define variables for testing the command
WRESULT          VAR WORD ' Used to store results to a word
EXPECTED         VAR WORD ' Used to display the expected result
BRESULT          VAR BYTE ' Used to store results to a byte
bogus            VAR BYTE ' Used to store intermediate results of the multiply

BB0              VAR BYTE ' Data in byte form
BB1              VAR BYTE ' Data in byte form
WW0              VAR WORD ' Data in word form
WW1              VAR WORD ' Data in word form

' Set values for testing
BB0=25
BB1=250
WW0=255
WW1=10052

Debug 10,13                ' Send new line

bogus = WW0 * WW1          ' Multiply to load internal registers with 32-bit value
WRESULT = Div32 BB1        ' Divide 32-bit value by byte and store in word
EXPECTED = 10253           ' Expected result for this calculation
GoSub resultword          ' Send the result with Debug

bogus = WW0 * WW1          ' Multiply to load internal registers with 32-bit value
WRESULT = Div32 WW0        ' Divide 32-bit value by word and store in word
EXPECTED = 10052           ' Expected result for this calculation
GoSub resultword          ' Send the result with Debug

bogus = WW0 * WW1          ' Multiply to load internal registers with 32-bit value
WRESULT = Div32 1000       ' Divide 32-bit value by constant and store in word
EXPECTED = 2563            ' Expected result for this calculation
GoSub resultword          ' Send the result with Debug

bogus = BB0 * BB1          ' Multiply to load internal registers with 32-bit value
BRESULT = Div32 BB0        ' Divide 32-bit value by byte and store in byte
EXPECTED = 250             ' Expected result for this calculation
GoSub resultbyte          ' Send the result with Debug
```

Picbasic Pro Statement Reference

```
bogus = BB0 * BB1          ' Multiply to load internal registers with 32-bit value
BRESULT = Div32 WW0       ' Divide 32-bit value by word and store in byte
EXPECTED = 24             ' Expected result for this calculation
GoSub resultbyte         ' Send the result with Debug
```

```
bogus = BB0 * BB1          ' Multiply to load internal registers with 32-bit value
BRESULT = Div32 100       ' Divide 32-bit value by constant and store in byte
EXPECTED = 62             ' Expected result for this calculation
GoSub resultbyte         ' Send the result with Debug
```

```
Debug 10,13                ' Send new line
```

```
End                        ' Stop
```

```
resultbyte:                ' Send byte value
```

```
    Debug "Byte Result = ",#BRESULT," ",#EXPECTED," Expected",10,13
    Pause 500
    Return
```

```
resultword:                ' Send word value
```

```
    Debug "Word Result = ",#WRESULT," ",#EXPECTED," Expected",10,13
    Pause 500
    Return
```

Picbasic Pro Statement Reference

5.16. DTMFOUT

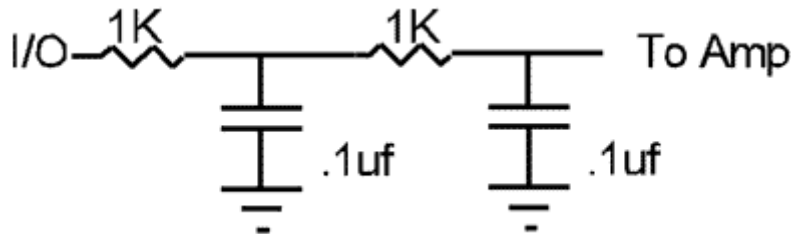
DTMFOUT *Pin*, {*Onms*, *Offms*, } [*Tone*{, *Tone*...}]

Produce DTMF touch *Tone* sequence on *Pin*. *Pin* is automatically made an output. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

Onms is the number of milliseconds to sound each tone and *Offms* is the number of milliseconds to pause between each tone. If they are not specified, *Onms* defaults to 200ms and *Offms* defaults to 50ms.

Tones are numbered 0-15. *Tones* 0-9 are the same as on a telephone keypad. *Tone* 10 is the * key, *Tone* 11 is the # key and *Tones* 12-15 correspond to the extended keys **A-D**.

DTMFOUT uses **FREQOUT** to generate the dual tones. **FREQOUT** generates tones using a form of pulse width modulation. The raw data coming out of the pin looks pretty scary. Some kind of filter is usually necessary to smooth the signal to a sine wave get rid of some of the harmonics that are generated:



DTMFOUT works best with a 20MHz oscillator. It can also work with a 10MHz oscillator and even at 4MHz, although it will start to get very hard to filter and be of fairly low amplitude. Any other frequency will cause **DTMFOUT** to generate a frequency that is a ratio of the actual oscillator used and 20MHz which will not be very useful for sending touch tones.

```
' Send DTMF tones for 212 on Pin1
DTMFOUT PORTB.1,[2,1,2]
```

Picbasic Pro Statement Reference

5.17. EEPROM

```
EEPROM {Location,}[Constant{,Constant...}]
```

Store constants in on-chip EEPROM. If the optional *Location* value is omitted, the first **EEPROM** statement starts storing at address 0 and subsequent statements store at the following locations. If the *Location* value is specified, it denotes the starting location where these values are stored.

Constant can be a numeric constant or a string constant. Only the least significant byte of numeric values are stored. Strings are stored as consecutive bytes of ASCII values. No length or terminator is automatically added.

EEPROM only works with microcontrollers with on-chip EEPROM such as the PIC16F84 and PIC16C84. It will not work on devices with on-chip I2C interfaced serial EEPROM like the 12CE67x and 16CE62x parts. Since EEPROM is non-volatile memory, the data will remain intact even if the power is turned off.

The data is stored in the EEPROM space only once at the time the microcontroller is programmed, not each time the program is run. **WRITE** can be used to set the values of the on-chip EEPROM at runtime.

```
' Store 10, 20 and 30 starting at location 5
```

```
EEPROM 5,[10,20,30]
```


Picbasic Pro Statement Reference

5.18. ENABLE

5.18.1. ENABLE

ENABLE

ENABLE debug and interrupt processing that was previously **DISABLEd** following this instruction.

DISABLE and **ENABLE** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON DEBUG** and **ON INTERRUPT** for more information.

	Disable	' Disable interrupts in handler
myint:	led = 1	' Turn on LED when interrupted
	Resume	' Return to main program
	ENABLE	' Enable interrupts after handler

5.18.2. ENABLE DEBUG

ENABLE DEBUG

ENABLE DEBUG processing that was previously **DISABLEd** following this instruction.

DISABLE DEBUG and **ENABLE DEBUG** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON DEBUG** for more information.

	DISABLE DEBUG	' Disable calls to the debug monitor
--	---------------	--------------------------------------

5.18.3. ENABLE INTERRUPT

ENABLE INTERRUPT

ENABLE INTERRUPT processing that was previously **DISABLEd** following this instruction.

DISABLE INTERRUPT and **ENABLE INTERRUPT** are more like pseudo-ops in that they give the compiler directions, rather than actually generate code. See **ON INTERRUPT** for more information.

	Disable Interrupt	' Disable interrupts in handler
myint:	led = 1	' Turn on LED when interrupted
	Resume	' Return to main program
	ENABLE INTERRUPT	' Enable interrupts after handler

Picbasic Pro Statement Reference

5.19. END

END

Stop program execution and enter low power mode. All of the I/O pins remain in their current state. **END** works by executing a Sleep instruction continuously in a loop.

An **END** or **STOP** or **GOTO** should be placed at the end of every program to keep it from falling off the end of memory and starting over.

END

Picbasic Pro Statement Reference

5.20. FOR..NEXT

```
FOR Count = Start TO End {STEP {-} Inc}  
  
    {Body}  
  
NEXT {Count}
```

The **FOR . .NEXT** loop allows programs to execute a number of statements (the *Body*) some number of times using a variable as a counter. Due to its complexity and versatility, **FOR . .NEXT** is best described step by step:

- 1) The value of *Start* is assigned to the index variable, *Count*. *Count* can be a variable of any type.
- 2) The *Body* is executed. The *Body* is optional and can be omitted (perhaps for a delay loop).
- 3) The value of *Inc* is added to (or subtracted from if "-" is specified) *Count*. If no **STEP** clause is defined, *Count* is incremented by one.
- 4) If *Count* has not passed *End* or overflowed the variable type, execution returns to Step 2. If the loop needs to *Count* to more than 255, a word-sized variable must be used.

```
FOR i = 1 TO 10          ' Count from 1 to 10  
  Serout 0,N2400,[#i," "] ' Send each number to Pin0 serially  
NEXT i                  ' Go back to and do next count  
Serout 0,N2400,[10] ' Send a linefeed  
FOR B2 = 20 TO 10 STEP -2 ' Count from 20 to 10 by 2  
  Serout 0,N2400,[#B2," "] ' Send each number to Pin0 serially  
NEXT B2                 ' Go back to and do next count  
Serout 0,N2400,[10] ' Send a linefeed
```

Picbasic Pro Statement Reference

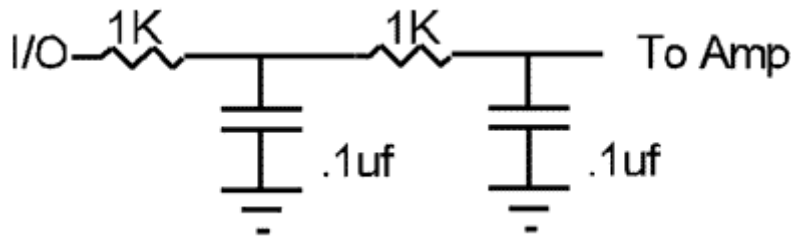
5.21. FREQOUT

FREQOUT *Pin, Onms, Frequency1{, Frequency2}*

Produce the *Frequency(s)* on *Pin* for *Onms* milliseconds. *Pin* is automatically made an output. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

One or two different frequencies from 0 to 32767 hertz may be produced at a time.

FREQOUT generates tones using a form of pulse width modulation. The raw data coming out of the pin looks pretty scary. Some kind of filter is usually necessary to smooth the signal to a sine wave get rid of some of the harmonics that are generated:



FREQOUT works best with a 20MHz oscillator. It can also work with a 10MHz oscillator and even at 4MHz, although it will start to get very hard to filter and be of fairly low amplitude. Any other frequency will cause **FREQOUT** to generate a frequency that is a ratio of the actual oscillator used and 20MHz.

' Send 1KHz tone on Pin1 for 2 seconds

FREQOUT PORTB.1,2000,1000

Picbasic Pro Statement Reference

5.22. GOSUB

`GOSUB Label`

Jump to the subroutine at *Label* saving its return address on the stack. Unlike `GOTO`, when a **RETURN** statement is reached, execution resumes with the statement following the last executed `GOSUB` statement.

An unlimited number of subroutines may be used in a program. Subroutines may also be nested. In other words, it is possible for a subroutine to call another subroutine. Such subroutine nesting should be restricted to no more than four levels deep.

```
        GOSUB beep      ' Execute subroutine named beep
...
beep:   High 0          ' Turn on LED connected to Pin0
        Sound 1,[80,10] ' Beep speaker connected to Pin1
        Low 0          ' Turn off LED connected to Pin0
        Return        ' Go back to main routine that called us
```

Picbasic Pro Statement Reference

5.23. GOTO *GOTO Label*

Program execution continues with the statements at *Label*.

GOTO send ‘ Jump to statement labeled send

...

send: Serout 0,N2400,["Hi"] ‘ Send "Hi" out Pin0 serially

Picbasic Pro Statement Reference

5.24. HIGH

HIGH *Pin*

Make the specified *Pin* high. *Pin* is automatically made an output. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

HIGH 0 ‘ Make Pin0 an output and set it high (~5 volts)

HIGH PORTA.0 ‘ Make PORTA, pin 0 an output and set it high (~5 volts)

led var PORTB.0 ‘ Define LED pin

HIGH led ‘ Make LED pin an output and set it high (~5 volts)

Alternatively, if the pin is already an output, a much quicker and shorter way (from a generated code standpoint) to set it high would be:

PORTB.0 = 1 ‘ Set PORTB pin 0 high

Picbasic Pro Statement Reference

5.25. HPWM

Hardware PWM command sets up the PWM hardware available on some PICmicro MCUs. It can run continuously in the background while the program is doing other things.

Hpwm Channel, DutyCycle, Frequency

Channel specifies which hardware PWM channel to use. Some devices have 1, 2 or 3 PWM channels. On devices with 2 channels, the Frequency must be the same on both channels.

DutyCycle specifies the on/off (high/low) ratio of the signal. It ranges from 0 to 255, where 0 is off (low all the time) and 255 is on (high) all the time. A value of 127 gives a 50% duty cycle (square wave).

Frequency is the desired frequency of the PWM signal. Not all frequencies are available at all oscillator settings. The lowest frequency at 4MHz is 245Hz. The highest frequency at any oscillator speed is 32767Hz.

See the Microchip data sheet for the device for more information on the PWM hardware.

```
HPWM 1,127,1000 ' Send a 50% duty cycle PWM signal at 1kHz
```

```
HPWM 1,64,200 ' Send a 25% duty cycle PWM signal at 2kHz
```

The HPWM instruction has a few Defines to go along with it. The first specifies which pin is the CCP pin for devices that have alternate places for the pin, such as the 18C452:

```
Define CCP1_REG PORTC
Define CCP1_BIT 2
Define CCP2_REG PORTC
Define CCP2_BIT 1
```

The following specify which timer, 1 or 2, to use with PWM2 and PWM3 for the 17C7xx devices. The default is timer 1 if no Define is specified.

```
Define HPWM2_TMR 1
Define HPWM3_TMR 1
```


Picbasic Pro Statement Reference

5.26. HSERIN

```
HSERIN {ParityLabel,}{Timeout,Label,}[Item{,...}]
```

Receive one or more *Items* from the hardware serial port on devices that support asynchronous serial communications in hardware.

HSERIN is one of several built-in asynchronous serial functions. It can only be used with devices that have a hardware USART. See the device data sheet for information on the serial input pin and other parameters. The serial parameters and baud rate are specified using **DEFINES**:

```
' Set receive register to receiver enabled
```

```
DEFINE HSER_RCSTA      90h
```

```
' Set transmit register to transmitter enabled
```

```
DEFINE HSER_TXSTA      20h
```

```
' Set baud rate
```

```
DEFINE HSER_BAUD       2400
```

```
' Set SPBRG directly (normally set by HSER_BAUD)
```

```
DEFINE HSER_SPBRG      25
```

```
'Automatically detect overflow error
```

```
Define HSER_CLROERR 1
```

If characters are not read soon enough from the hardware serial port, an overflow error will occur. In general, the BASIC program should detect this error and clear it by toggling CREN off and back on. A new Define has been added that tells the Hserin command to automatically detect this error and clear it. Keep in mind, characters are being missed when an overflow error occurs.

HSERIN assumes a 4MHz oscillator when calculating the baud rate. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to the new oscillator value.

An optional *Timeout* and *Label* may be included to allow the program to continue if a character is not received within a certain amount of time. *Timeout* is specified in 1 millisecond units.

The serial data format defaults to 8N1, 8 data bits, no parity bit and 1 stop bit. 7E1 (7 data bits, even parity, 1 stop bit) or 7O1 (7 data bits, odd parity, 1 stop bit) can be enabled using one of the following **DEFINES**:

```
' Use only if even parity desired
```

```
DEFINE HSER_EVEN       1
```

Picbasic Pro Statement Reference

' Use only if odd parity desired

```
DEFINE HSER_ODD      1
```

The parity setting, along with all of the other **HSER DEFINES**, affect both **HSERIN** and **HSEROUT**.

An optional *ParityLabel* may be included in the statement. The program will continue at this location if a character with a parity error is received. It should only be used if parity is enabled using one of the preceding **DEFINES**.

Since the serial reception is done in hardware, it is not possible to set the levels to an inverted state to eliminate an RS-232 driver. Therefore a suitable driver should be used with **HSERIN**. **HSERIN** supports the same data modifiers that **SERIN2** does. Refer to the section on **SERIN2** for this information.

Table 13 HSERIN command modifiers

Modifier	Operation
BIN{1..16}	Receive binary digits
DEC{1..5}	Receive decimal digits
HEX{1..4}	Receive hexadecimal digits
SKIP n	Skip n received characters
STR ArrayVar\n{c}	Receive string of n characters optionally ended in character c
WAIT ()	Wait for sequence of characters
WAITSTR ArrayVar{n}	Wait for character string

On 17Cxxx devices with 2 serial ports, **HSERIN** will only access the first port. The second port should be set up and read by accessing the registers directly.

```
HSERIN [B0, dec W1]
```

Hserin and Hserout USART restrictions

Hserin and Hserout work with the first USART only. On devices that have two USARTs, use the register names to directly access the second USART.

Picbasic Pro Statement Reference

5.27. HSEROUT

HSEROUT [*Item*{,*Item*...}]

Send one or more *Items* to the hardware serial port on devices that support asynchronous serial communications in hardware.

HSEROUT is one of several built-in asynchronous serial functions. It can only be used with devices that have a hardware USART. See the device data sheet for information on the serial output pin and other parameters. The serial parameters and baud rate are specified using **DEFINES**:

DEFINES:

' Set receive register to receiver enabled

DEFINE HSER_RCSTA 90h

' Set transmit register to transmitter enabled

DEFINE HSER_TXSTA 20h

' Set baud rate

DEFINE HSER_BAUD 2400

' Set SPBRG directly (normally set by HSER_BAUD)

DEFINE HSER_SPBRG 25

HSEROUT assumes a 4MHz oscillator when calculating the baud rate. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to the new oscillator value.

The serial data format defaults to 8N1, 8 data bits, no parity bit and 1 stop bit. 7E1 (7 data bits, even parity, 1 stop bit) or 7O1 (7 data bits, odd parity, 1 stop bit) can be enabled using one of the following **DEFINES**:

' Use only if even parity desired

DEFINE HSER_EVEN 1

' Use only if odd parity desired

DEFINE HSER_ODD 1

The parity setting, along with all of the other **HSER** **DEFINES**, affect both **HSERIN** and **HSEROUT**.

Since the serial transmission is done in hardware, it is not possible to set the levels to an inverted state to eliminate an RS-232 driver. Therefore a suitable driver should be used with **HSEROUT**.

HSEROUT supports the same data modifiers that **SEROUT2** does. Refer to the section on **SEROUT2** for this information.

Table 14 HSEROUT command modifiers

<i>Modifier</i>	<i>Operation</i>
{B}{S}BIN{1..16}	Send binary digits
{B}{S}DEC{1..5}	Send decimal digits
{B}{S}HEX{1..4}	Send hexadecimal digits
REP c\n	Send character c repeated n times
STR ArrayVar{\n}	Send string of n characters

Picbasic Pro Statement Reference

On 17Cxxx devices with 2 serial ports, **HSEROUT** will only access the first port. The second port should be set up and read by accessing the registers directly.

' Send the decimal value of B0 followed by a linefeed out the hardware USART

HSEROUT [dec B0,10]

Hserin and Hserout USART restrictions

Hserin and Hserout work with the first USART only. On devices that have two USARTs, use the register names to directly access the second USART.

Picbasic Pro Statement Reference

5.28.I2CREAD

I2CREAD *dataPin*, *ClockPin*, *Control*, {*Address*, } [*Var*{, *Var*. . . }]{, *Label*}

Send *Control* and optional *Address* bytes out the *ClockPin* and *DataPin* and store the byte(s) received into *Var*. *ClockPin* and *DataPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

I2CREAD and **I2CWRITE** can be used to read and write data to a serial EEPROM with a 2-wire I²C interface such as the Microchip 24LC01B and similar devices. This allows data to be stored in external non-volatile memory so that it can be maintained even after the power is turned off. These commands operate in the I²C master mode and may also be used to talk to other devices with an I²C interface like temperature sensors and A/D converters.

The upper 7 bits of the *Control* byte contain the control code along with chip select or additional address information, depending on the particular device. The low order bit is an internal flag indicating whether it is a read or write command and should be kept clear.

This format for the *Control* byte is different than the format used by the original PicBasic Compiler. Be sure to use this format with PBP I²C operations.

For example, when communicating with a 24LC01B, the control code is %1010 and the chip selects are unused so the *Control* byte would be %10100000 or \$A0. Formats of *Control* bytes for some of the different parts follows:

Table 15 I2Cread EEPROM data

Device	Capacity	Control	Address size
24LC01B	128 bytes	%1010xxx0	1 byte
24LC02B	256 bytes	%1010xxx0	1 byte
24LC04B	512 bytes	%1010xxb0	1 byte
24LC08B	1K bytes	%1010xbb0	1 byte
24LC16B	2K bytes	%1010bbb0	1 byte
24LC32B	4K bytes	%1010ddd0	2 bytes
24LC65	8K bytes	%1010ddd0	2 bytes

bbb = block select (high order address) bits

ddd = device select bits

xxx = don't care

The *Address* size sent (byte or word) is determined by the size of the variable that is used. If a byte-sized variable is used for the *Address*, an 8-bit address is sent. If a word-sized variable is used, a 16-bit address is sent. Be sure to use the proper sized variable for the device you wish to communicate with. Constants should not be used for the address as the size can vary dependent on the size of the constant.

If a word-sized *Var* is specified, 2 bytes are read and stored into the *Var* high byte first, followed by the low byte. This order is different than the way variables are normally stored, low byte first.

A modifier, **STR**, may be included before the variable name. This can load an entire array (string) at once. If **STR** is specified, the following variable must be the name of a word or byte array, followed by a backslash (\) and a count:

```
a var byte[8]
```

Picbasic Pro Statement Reference

```
I2CREAD PORTC.4,PORTC.3,$a0,0,[STR a\8]
```

If a word-sized array is specified, the 2 bytes that comprise each element are read low byte first. This is the opposite of how simple words are read and is consistent with the way the compiler normally stores word-sized variables.

If the optional *Label* is included, this label will be jumped to if an acknowledge is not received from the I²C device.

The I²C instructions can be used to access the on-chip serial EEPROM on the 12CExxx and 16CExxx devices. Simply specify the pin names for the appropriate internal lines as part of the I²C command and place the following **DEFINE** at the top of the program:

```
DEFINE I2C_INTERNAL 1
```

For the 12CE67x devices, the data line is GPIO.6 and the clock line is GPIO.7. For the 16CE62x devices, the data line is EEINTF.1 and the clock line is EEINTF.2. See the Microchip data sheets for these devices for more information.

The timing of the I²C instructions is set so that standard speed devices (100KHz) will be accessible at clock speeds up to 8MHz. Fast mode devices (400KHz) may be used up to 20MHz. If it is desired to access a standard speed device at above 8MHz, the following **DEFINE** should be added to the program:

```
DEFINE I2C_SLOW 1
```

Transfer on the I2C bus can be paused by the receiving device by its holding the clock line low. To enable this the following **DEFINE** should be added to the program:

```
DEFINE I2C_HOLD 1
```

```
addr    var    byte
cont    con    %10100000
addr = 17      ' Set address to 17
' Read data at address 17 into B2
I2CREAD PORTA.0,PORTA.1,cont,addr,[B2]
```

See the Microchip ANon-Volatile Memory Products Data Book@ for more information on these and other devices that may be used with the **I2CREAD** and **I2CWRITE** commands.

The I²C clock and data lines should be pulled up to Vcc with a 4.7K resistor per the following schematic as they are both run in a bi-directional open-collector manner.

To make the I2C clock line bipolar instead of open-collector the following **DEFINE** may be added to the program:

```
DEFINE I2C_SCLOUT 1
```

```
addr    var    byte
cont    con    %10100000
addr = 17      ' Set address to 17
' Read data at address 17 into B2
I2CREAD PORTA.0,PORTA.1,cont,addr,[B2]
```

See the Microchip ANon-Volatile Memory Products Data Book@ for more information on these and other devices that may be used with the **I2CREAD** and **I2CWRITE** commands.

Picbasic Pro Statement Reference

5.29. I2CWRITE

```
I2CWRITE DataPin,ClockPin,Control, {Address,}  
[Value{,Value...}] {,Label}
```

I2CWRITE sends *Control* and optional *Address* out the I²C *ClockPin* and *DataPin* followed by *Value*. *ClockPin* and *DataPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

The *Address* size sent (byte or word) is determined by the size of the variable that is used. If a byte-sized variable is used for the *Address*, an 8-bit address is sent. If a word-sized variable is used, a 16-bit address is sent. Be sure to use the proper sized variable for the device you wish to communicate with. Constants should not be used for the address as the size can vary dependent on the size of the constant.

When writing to a serial EEPROM it is necessary to wait 10ms (device dependent) for the write to complete before attempting communication with the device again. If a subsequent **I2CREAD** or **I2CWRITE** is attempted before the write is complete, the access will be ignored.

While a single **I2CWRITE** statement may be used to write multiple bytes at once, doing so may violate the above write timing requirement for serial EEPROMs. Some serial EEPROMs let you write multiple bytes into a single page before necessitating the wait. Check the data sheet for the specific device you are using for these details. The multiple byte write feature may also be useful with I²C devices other than serial EEPROMs that don't have to wait between writes.

If a word-sized *Value* is specified, 2 bytes are sent, high byte first, followed by the low byte. This order is different than the way variables are normally stored, low byte first.

A modifier, **STR**, may be included before the variable name. This can be used to write an entire array (string) at once and take advantage of a serial EEPROM's page mode. The data must fit into a single EEPROM page. The page size is dependent on the particular EEPROM device. If **STR** is specified, the following variable must be the name of a word or byte array, followed by a backslash (\) and a count:

```
a var byte[8]  
  
I2CWRITE PORTC.4,PORTC.3,$a0,0,[STR a\8]
```

If a word-sized array is specified, the 2 bytes that comprise each element are written low byte first. This is the opposite of how simple words are written and is consistent with the way the compiler normally stores word-sized variables.

If the optional *Label* is included, this label will be jumped to if an acknowledge is not received from the I²C device.

The I²C instructions can be used to access the on-chip serial EEPROM on the 12CExxx and 16CExxx devices. Simply specify the pin names for the appropriate internal lines as part of the I²C command and place the following **DEFINE** at the top of the program:

```
DEFINE I2C_INTERNAL 1
```

For the 12CE67x devices, the data line is GPIO.6 and the clock line is GPIO.7. For the 16CE62x devices, the data line is EEINTF.1 and the clock line is EEINTF.2. See the Microchip data sheets for these devices for more information.

The timing of the I²C instructions is set so that standard speed devices (100KHz) will be accessible at clock speeds up to 8MHz. Fast mode devices (400KHz) may be used up to 20MHz. If it is desired to access a standard speed device at above 8MHz, the following **DEFINE** should be added to the program:

```
DEFINE I2C_SLOW 1
```

Picbasic Pro Statement Reference

Transfer on the I2C bus can be paused by the receiving device by its holding the clock line low. To enable this the following **DEFINE** should be added to the program:

```
DEFINE I2C_HOLD 1
```

To make the I2C clock line bipolar instead of open-collector the following **DEFINE** may be added to the program:

```
DEFINE I2C_SCLOUT 1
```

See the **I2CREAD** command above for the rest of the story.

```
addr    var        byte
cont    con        %10100000
```

```
addr = 17          ' Set address to 17
' Send the byte 6 to address 17
I2CWRITE PORTA.0,PORTA.1,cont,addr,[6]
Pause 10          ' Wait 10ms for write to complete
addr = 1          ' Set address to 1
' Send the byte in B2 to address 1
I2CWRITE PORTA.0,PORTA.1,cont,addr,[B2]
Pause 10          ' Wait 10ms for write to complete
```


Picbasic Pro Statement Reference

5.30. IF..THEN

```
IF Comp {AND/OR Comp...} THEN Label
```

```
IF Comp {AND/OR Comp...} THEN
```

```
    Statement...
```

```
ELSE
```

```
    Statement...
```

```
ENDIF
```

Performs one or more comparisons. Each *Comp* term can relate a variable to a constant or other variable and includes one of the comparison operators listed previously.

IF . . THEN evaluates the comparison terms for true or false. If it evaluates to true, the operation after the **Then** is executed. If it evaluates to false, the operation after the **Then** is not executed. Comparisons that evaluate to 0 are considered false. Any other value is considered true. All comparisons are unsigned since PBP only supports unsigned types.

Be sure to use parenthesis to specify the order the operations should be tested in. Otherwise, operator precedence will determine it for you and the result may not be as expected.

IF . . THEN can operate in 2 manners. In one form, the **THEN** in an **IF . . THEN** is essentially a **GOTO**. If the condition is true, the program will **GOTO** the label after the **THEN**. If the condition evaluates to false, the program will continue at the next line after the **IF . . THEN**. Another statement may not be placed after the **THEN**, it must be a label.

```
    If Pin0 = 0 Then pushd          ' If button connected to Pin0 is pushed (0), jump to  
label pushd
```

```
    If B0 >= 40 Then old          ' If the value in variable B0 is greater than or equal to 40, jump  
to old
```

```
    If PORTB.0 Then itson        ' If PORTB, pin 0 is high (1), jump to itson
```

```
    If (B0 = 10) AND (B1 = 20) Then loop
```

In the second form, **IF . . THEN** can conditionally execute a group of *Statements* following the **THEN**. The *Statements* must be followed by an **ELSE** or **ENDIF** to complete the structure.

```
    If B0 <> 10 Then
```

```
        B0 = B0 + 1
```

```
        B1 = B1 - 1
```

```
    Endif
```

```
    If B0 = 20 Then
```

```
        led = 1
```

```
    Else
```

```
        led = 0
```

```
    Endif
```

Picbasic Pro Statement Reference

5.31. INPUT

INPUT *Pin*

Makes the specified *Pin* an input. *Pin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

```
INPUT 0          ' Make Pin0 an input
```

```
INPUT PORTA.0    ' Make PORTA, pin 0 an input
```

Alternatively, the pin may be set to an input in a much quicker and shorter way (from a generated code standpoint):

```
TRISB.0 = 1          ' Set PORTB, pin 0 to an input
```

All of the pins on a port may be set to inputs by setting the whole TRIS register at once:

```
TRISB = %11111111    ' Set all of PORTB to inputs
```

Picbasic Pro Statement Reference

5.32. LCDIN

```
LCDIN {Address,}[Var{,Var...}]
```

Read LCD RAM at *Address* and store data to *Var*.

LCDs have RAM onboard that is used for character memory. Most LCDs have more RAM available that is necessary for the displayable area. This RAM can be written using the **LCDOUT** instruction. The **LCDIN** instruction allows this RAM to be read.

CG (character generator) RAM runs from address \$40 to \$7f. Display data RAM starts at address \$80. See the data sheet for the specific LCD for these addresses and functions. It is necessary to connect the LCD read/write line to a PICmicro pin so that it may be controlled to select either a read (**LCDIN**) or write (**LCDOUT**) operation. Two **DEFINES** control the pin address:

```
DEFINE LCD_RWREG PORTE          ' LCD read/write pin port
```

```
DEFINE LCD_RWBIT 2             ' LCD read/write pin bit
```

Picbasic Pro Statement Reference

5.33. LCDOUT

LCDOUT *Item*{,*Item*...}

Display *Items* on an intelligent Liquid Crystal Display. PBP supports LCD modules with a Hitachi 44780 controller or equivalent. These LCDs usually have a 14- or 16-pin single- or dual-row header at one edge.

If a pound sign (#) precedes an *Item*, the ASCII representation for each digit is sent to the LCD. **LCDOUT** can also use any of the modifiers used with **SEROUT2**. See the section on **SEROUT2** for this information.

Table 16 LCDout command modifier

Modifier	Operation
{I}{S}BIN{1..16}	Send binary digits
{I}{S}DEC{1..5}	Send decimal digits
{I}{S}HEX{1..4}	Send hexadecimal digits
REP c\n	Send character c repeated n times
STR ArrayVar{n}	Send string of n characters

A program should wait for at least half a second before sending the first command to an LCD. It can take quite a while for an LCD to start up.

Commands are sent to the LCD by sending a \$FE followed by the command. Some useful commands are listed in the following table:

Table 17 LCD display format commands

Command	Operation
\$FE, 1	Clear display
\$FE, 2	Return home (beginning of first line)
\$FE, \$0C	Cursor off
\$FE, \$0E	Underline cursor on
\$FE, \$0F	Blinking cursor on
\$FE, \$10	Move cursor left one position
\$FE, \$14	Move cursor right one position
\$FE, \$C0	Move cursor to beginning of second line
\$FE, \$94	Move cursor to beginning of third line
\$FE, \$D4	Move cursor to beginning of fourth line

Note that there is a command to move the cursor to the beginning of the second line of a 2-line display. For most LCDs, the displayed characters and lines are not consecutive in display memory - there can be a break in between locations. For most 16x2 displays, the first line starts at \$0 and the second line starts at \$40. The command:

LCDOUT \$FE, \$C0

Picbasic Pro Statement Reference

sets the display to start writing characters at the beginning of the second line. 16x1 displays are usually formatted as 8x2 displays with a break between the memory locations for the first and second 8 characters. 4-line displays also have a mixed up memory map. See the data sheet for the particular LCD device for the character memory locations and additional commands..

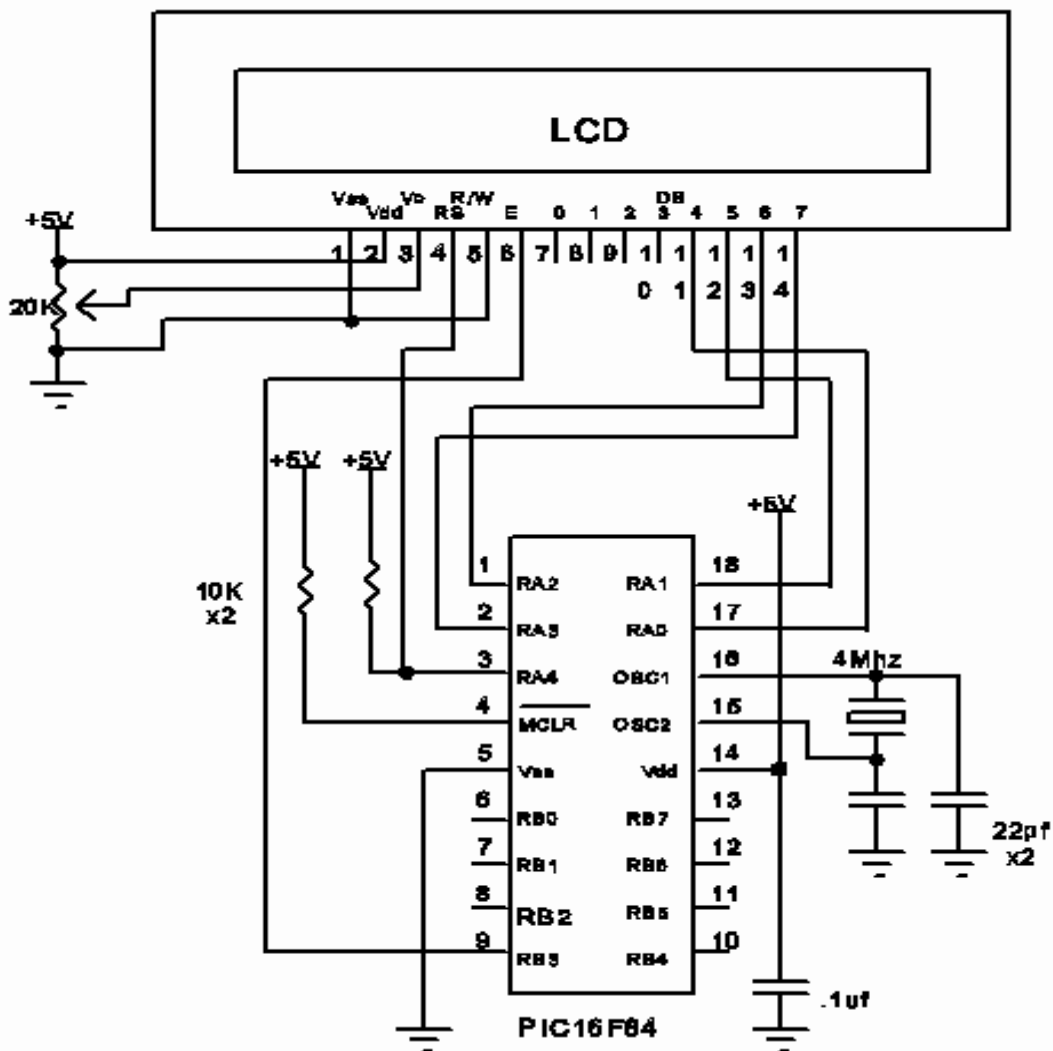
```
LCDOUT $FE, 1, "Hello"      ' Clear display and show "Hello"
```

```
LCDOUT B0, #B1
```

The LCD may be connected to the PICmicro using either a 4-bit bus or an 8-bit bus. If an 8-bit bus is used, all 8 bits must be on one port. If a 4-bit bus is used, it must be connected to either the bottom 4 or top 4 bits of one port. Enable and Register Select may be connected to any port pin. R/W should be tied to ground as the LCDOUT command is write only.

PBP assumes the LCD is connected to specific pins unless told otherwise. It assumes the LCD will be used with a 4-bit bus with data lines DB4 - DB7 connected to PICmicro PORTA.0 - PORTA.3, Register Select to PORTA.4 and Enable to PORTB.3.

It is also preset to initialize the LCD to a 2 line display.



Picbasic Pro Statement Reference

To change this setup, place one or more of the following **DEFINES**, all in upper-case, at the top of your PicBasic Pro program:

```
DEFINE LCD_DREG      PORTB  'Set LCD Data port
DEFINE LCD_DBIT      4      ' Set starting Data bit (0 or 4) if 4-bit bus
DEFINE LCD_RSREG     PORTB  ' Set LCD Register Select port
DEFINE LCD_RSBIT     1      ' Set LCD Register Select bit
DEFINE LCD_EREGL     PORTB  ' Set LCD Enable port
DEFINE LCD_EBIT      0      ' Set LCD Enable bit
DEFINE LCD_BITS      4      ' Set LCD bus size (4 or 8 bits)
DEFINE LCD_LINES     2      ' Set number of lines on LCD
DEFINE LCD_COMMANDUS 2000   ' Set command delay time in us

DEFINE LCD_DATAUS    50     ' Set data delay time in us
```

This setup will tell PBP a 2-line LCD is connected in 4-bit mode with the data bus on the top 4 bits of PORTB, Register Select on PORTB.1, and Enable on PORTB.0.

The schematic shows one way to connect an LCD to a PICmicro, using the defaults

The default Defines for the LCD are:

```
Define LCD_DREG PORTB  ' LCD data pin port
Define LCD_DBIT 0      ' LCD data pin bit
Define LCD_RSREG PORTB ' LCD register select pin port
Define LCD_RSBIT 4     ' LCD register select pin bit
Define LCD_EREGL PORTB ' LCD enable pin port
Define LCD_EBIT 5     ' LCD enable pin bit
Define LCD_BITS 4     ' LCD number of data bits
Define LCD_LINES 2    ' LCD number of lines
```

Picbasic Pro Statement Reference

5.34. {LET}

`{LET} Var = Value`

Assign a *Value* to a *Variable*. The *Value* may be a constant, another variable or the result of an expression. Refer to the previous section on operators for more information. The keyword **LET** itself is optional.

`LET B0 = B1 * B2 + B3`

`B0 = Sqr W1`

Picbasic Pro Statement Reference

5.35. LOOKDOWN

`LOOKDOWN Search, [Constant{, Constant...}], Var`

The **LOOKDOWN** statement searches a list of 8-bit *Constant* values for the presence of the *Search* value. If found, the index of the matching constant is stored in *Var*. Thus, if the value is found first in the list, *Var* is set to zero. If second in the list, *Var* is set to one. And so on. If not found, no action is taken and *Var* remains unchanged.

The constant list can be a mixture of numeric and string constants. Each character in a string is treated as a separate constant with the character's ASCII value. Array variables with a variable index may not be used in **LOOKDOWN** although array variables with a constant index are allowed. Up to 255 (256 for 18Cxxx) constants are allowed in the list.

`Serin 1,N2400,B0` ' Get hexadecimal character from Pin1
serially

`LOOKDOWN B0,["0123456789ABCDEF"],B1` ' Convert hexadecimal
character in B0 to decimal value B1

`Serout 0,N2400,[#B1]` ' Send decimal value to Pin0
serially

Picbasic Pro Statement Reference

5.36. LOOKDOWN2

LOOKDOWN2 *Search*, {*Test*} [*Value*{, *Value*...}], *Var*

The **LOOKDOWN2** statement searches a list of *Values* for the presence of the *Search* value. If found, the index of the matching constant is stored in *Var*. Thus, if the value is found first in the list, *Var* is set to zero. If second in the list, *Var* is set to one. And so on. If not found, no action is taken and *Var* remains unchanged.

The optional parameter *Test* can be used to perform a test for other than equal to (A=@) while searching the list. For example, the list could be searched for the first *Value* greater than the *Search* parameter by using A>@ as the *Test* parameter. If *Test* is left out, A=@ is assumed.

The *Value* list can be a mixture of 16-bit numeric and string constants and variables. Each character in a string is treated as a separate constant equal to the character's ASCII value. Expressions may not be used in the *Value* list, although they may be used as the *Search* value.

Array variables with a variable index may not be used in **LOOKDOWN2** although array variables with a constant index are allowed. Up to 85 (256 for 18Cxxx) values are allowed in the list. **LOOKDOWN2** generates code that is about 3 times larger than **LOOKDOWN**. If the search list is made up only of 8-bit constants and strings, use **LOOKDOWN**.

```
LOOKDOWN2 W0, [512, W1, 1024], B0
```

```
LOOKDOWN2 W0, <[10, 100, 1000], B0
```


Picbasic Pro Statement Reference

5.38. LOOKUP2

LOOKUP2 *Index*, [*Value*{, *Value*...}], *Var*

The **LOOKUP2** statement can be used to retrieve entries from a table of *Values*. If *Index* is zero, *Var* is set to the first *Value*. If *Index* is one, *Var* is set to the second *Value*. And so on. If *Index* is greater than or equal to the number of entries in the list, no action is taken and *Var* remains unchanged.

The *Value* list can be a mixture of 16-bit numeric and string constants and variables. Each character in a string is treated as a separate constant equal to the character's ASCII value. Expressions may not be used in the *Value* list, although they may be used as the *Index* value.

Array variables with a variable index may not be used in **LOOKUP2** although array variables with a constant index are allowed. Up to 85 (256 for 18Cxxx) values are allowed in the list. **LOOKUP2** generates code that is about 3 times larger than **LOOKUP**. If the *Value* list is made up of only 8-bit constants and strings, use **LOOKUP**.

LOOKUP2 B0, [256, 512, 1024], W1

Picbasic Pro Statement Reference

5.39. LOW

LOW *Pin*

Make the specified *Pin* low. *Pin* is automatically made an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

LOW 0 ' Make Pin0 an output and set it low (0 volts)

LOW PORTA.0 ' Make PORTA, pin 0 an output and set it low (0 volts)

led var PORTB.0 ' Define LED pin

LOW led ' Make LED pin an output and set it low (0 volts)

Alternatively, if the pin is already an output, a much quicker and shorter way (from a generated code standpoint) to set it low would be:

PORTB.0 = 0 ' Set PORTB, pin 0 low

Picbasic Pro Statement Reference

5.40. NAP

NAP Period

Places the microcontroller into low power mode for short periods of time. During this **NAP**, power consumption is reduced to minimum. The listed periods are only approximate because the timing is derived from the Watchdog Timer which is R/C driven and can vary greatly from chip to chip and over temperature. Since **NAP** uses the Watchdog Timer, its timing is independent of the oscillator frequency.

Table 18 Nap period table

Period	Delay (Approx.)
0	18 milliseconds
1	36 milliseconds
2	72 milliseconds
3	144 milliseconds
4	288 milliseconds
5	576 milliseconds
6	1.152 seconds
7	2.304 seconds

NAP 7 ' Low power pause for about 2.3 seconds

Picbasic Pro Statement Reference

5.41. ON DEBUG

`ON DEBUG GOTO Label`

ON DEBUG allows a debug monitor program to be executed between each PicBasic Pro instruction

The method by which this happens is similar to the method used by **ON INTERRUPT GOTO**. Once **ON DEBUG GOTO** is encountered, a call to the specified debug label is inserted before each PicBasic Pro instruction in the program. **DISABLE DEBUG** prevents the insertion of this call while **ENABLE DEBUG** resumes the insertion of the call.

A monitor routine may be written that is activated before each instruction. This routine can send data to an LCD or to a serial comm program. Any program information may be displayed or even altered in this manner. A small monitor program example is posted on our web site. A word-sized system variable that resides in `BANK0` is required to provide place to store the address the program was at before the monitor routine was called by **ON DEBUG GOTO**:

```
DEBUG_ADDRESS VAR WORD BANK0 SYSTEM
```

An Additional byte-sized variable may be used to return the level of the current program stack:

```
DEBUG_STACK VAR BYTE BANK0 SYSTEM
```

This level should never be greater than 4 in a PicBasic Pro program. The supplied variable will be incremented at each **GOSUB** and decremented at each **RETURN**. This variable should be set to 0 at the beginning of the program.

Adding this variable to a program does add overhead in that the value of the variable must be incremented and decremented at each **GOSUB** and **RETURN**.

Picbasic Pro Statement Reference

5.42. ON INTERRUPT

`ON INTERRUPT GOTO Label`

ON INTERRUPT allows the handling of microcontroller interrupts by a PicBasic Pro subroutine.

There are 2 ways to handle interrupts using the PicBasic Pro Compiler. The first is to write an assembly language interrupt routine. This is the way to handle interrupts with the shortest latency and lowest overhead. This method is discussed under advanced topics in a later section.

The second method is to write a PicBasic Pro interrupt handler. This looks just like a PicBasic Pro subroutine but ends with a **RESUME**.

When an interrupt occurs, it is flagged. As soon as the current PicBasic Pro statement's execution is complete, the program jumps to the BASIC interrupt handler at *Label*. Once the interrupt handler is complete, a **RESUME** statement sends the program back to where it was when the interrupt occurred, picking up where it left off.

DISABLE and **ENABLE** allow different sections of a PicBasic Pro program to execute without the possibility of being interrupted. The most notable place to use **DISABLE** is right before the actual interrupt handler. Or the interrupt handler may be placed before the **ON INTERRUPT** statement as the interrupt flag is not checked before the first **ON INTERRUPT** in a program. Latency is the time it takes from the time of the actual interrupt to the time the interrupt handler is entered. Since PicBasic Pro statements are not re-entrant (i.e. you cannot execute another PicBasic Pro statement while one is being executed), there can be considerable latency before the interrupt routine is entered.

PBP will not enter the BASIC interrupt handler until it has finished executing the current statement. If the statement is a **PAUSE** or **SERIN**, it could be quite a while before the interrupt is acknowledged. The program must be designed with this latency in mind. If it is unacceptable and the interrupts must be handled more quickly, an assembly language interrupt routine must be used.

Overhead is another issue. **ON INTERRUPT** will add an instruction after every statement to check whether or not an interrupt has occurred. **DISABLE** turns off the addition of this instruction. **ENABLE** turns it back on again. Usually the additional instruction will not be much of a problem, but long programs in small microcontrollers could suffer.

More than one **ON INTERRUPT** may be used in a program.

```
ON INTERRUPT GOTO myint ' Interrupt handler is myint
INTCON = %10010000      ' Enable RB0 interrupt
...

DISABLE                ' Disable interrupts in handler
myint: led = 1          ' Turn on LED when interrupted
RESUME                 ' Return to main program
ENABLE                 ' Enable interrupts after handler
```

To turn off interrupts permanently (or until needed again) once **ON INTERRUPT** has been used, set INTCON to \$80:

```
INTCON = $80
```

Picbasic Pro Statement Reference

ONInt Example

```
' On Interrupt - Interrupts in BASIC  
' Turn LED on. Interrupt on PORTB.0 (INTE) turns LED off.  
' Program waits .5 seconds and turns LED back on.
```

```
led var PORTB.7
```

```
OPTION_REG = $7f ' Enable PORTB pullups
```

```
On Interrupt Goto myint ' Define interrupt handler  
INTCON = $90 ' Enable INTE interrupt
```

```
loop: High led ' Turn LED on  
Goto loop ' Do it forever
```

```
' Interrupt handler  
Disable ' No interrupts past this point  
myint: Low led ' If we get here, turn LED off  
Pause 500 ' Wait .5 seconds  
INTCON.1 = 0 ' Clear interrupt flag  
Resume ' Return to main program  
Enable
```


Picbasic Pro Statement Reference

5.43.OUTPUT

OUTPUT *Pin*

Make the specified *Pin* an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

OUTPUT 0 ‘ Make Pin0 an output

OUTPUT PORTA.0 ‘ Make PORTA, pin 0 an output

Alternatively, the pin may be set to an output in a much quicker and shorter way (from a generated code standpoint):

TRISB.0 = 0 ‘ Set PORTB, pin 0 to an output

All of the pins on a port may be set to outputs by setting the whole TRIS register at once:

TRISB = %00000000 ‘ Set all of PORTB to outputs

Picbasic Pro Statement Reference

5.44. OWIn

One-Wire Command added to simplify access to Dallas Semiconductor one-wire devices:

OWIn Pin, Mode, [Item{, Item...}]

OWIn optionally sends a reset pulse to the one-wire device and then reads one or more bits or bytes of data from it, optionally ending with another reset pulse.

Pin is a constant or variable that specifies which I/O pin the one-wire device is connected to.

Mode specifies whether a reset is sent before and/or after the operation and the size of the data items, either bit or byte.

<i>Mode bit number</i>	<i>Effect</i>
0	1 = send reset pulse before data
1	1 = send reset pulse after data
2	0 = byte-sized data, 1 = bit-sized data

Some Mode examples would be: Mode of 0 means no reset and byte-sized data, Mode of 1 means reset before data and byte-sized data, Mode of 4 means no reset and bit-sized data.

Item is one or more variables or modifiers separated by commas. The allowable modifiers are Str for reading data into a byte array variable and Skip for skipping a number of input values.

OWIn PORTC.0, 0, [temperature\2, Skip 4, count_remain, count_per_c]

This statement would receive bytes from a one-wire device on PORTC pin 0 with no reset pulse being sent. It would receive 2 bytes and put them into the byte array temperature, skip the next 4 bytes and then read the final 2 bytes into separate variables.

Note: Use a 2k5 pull up resistor on the data pin.
See *OWOUT* for example code

Picbasic Pro Statement Reference

5.45. OWOut

One-Wire Command added to simplify access to Dallas Semiconductor one-wire devices:

OWOut Pin, Mode, [Item{, Item...}]

OWOut optionally sends a reset pulse to the one-wire device and then writes one or more bits or bytes of data to it, optionally ending with another reset pulse.

Pin is a constant or variable that specifies which I/O pin the one-wire device is connected to.

Mode specifies whether a reset is sent before and/or after the operation and the size of the data items, either bit or byte.

<i>Mode bit number</i>	<i>Effect</i>
0	1 = send reset pulse before data
1	1 = send reset pulse after data
2	0 = byte-sized data, 1 = bit-sized data

Some Mode examples would be: Mode of 0 means no reset and byte-sized data, Mode of 1 means reset before data and byte-sized data, Mode of 4 means no reset and bit-sized data.

Item is one or more constants, variables or modifiers separated by commas. The allowable modifiers are Str for sending data from a byte array variable and Rep for sending a number of repeated values.

OWOut PORTC.0, 1, [\$cc, \$be]

This statement would send a reset pulse to a one-wire device on PORTC pin 0 followed by the bytes \$cc and \$be.

Note: Use a 2k5 pull up resistor on the data pin.

Picbasic Pro Statement Reference

OW Example program

```
' One-wire temperature for LAB-X1 and DS1820

temperature Var Word           ' Temperature storage
count_remain Var Byte         ' Count remaining
count_per_c Var Byte         ' Count per degree C

DQ Var PORTC.0                ' One-wire data pin

' Define LCD registers and bits
Define LCD_DREG PORTD
Define LCD_DBIT 4
Define LCD_RSREG PORTE
Define LCD_RSBIT 0
Define LCD_EREG PORTE
Define LCD_EBIT 1

ADCON1 = 7                    ' Set PORTA and PORTE to digital
Low PORTE.2                   ' LCD R/W line low (W)

mainloop: OWOut DQ, 1, [SCC, $44] ' Start temperature conversion

waitloop: OWIn DQ, 4, [count_remain] ' Check for still busy converting
           If count_remain = 0 Then waitloop
           OWOut DQ, 1, [SCC, $BE] ' Read the temperature
           OWIn DQ, 0, [temperature.LOWBYTE, temperature.HIGHBYTE, Skip 4, count_remain,
count_per_c]

           ' Calculate temperature in degrees C to 2 decimal places
           ' (not valid for negative temperature)
           temperature = (((temperature >> 1) * 100) - 25) + (((count_per_c - count_remain) * 100) /
count_per_c)
           Lcdout $fe, 1, DEC (temperature / 100), ".", DEC2 temperature, " C"

           ' Calculate temperature in degrees F to 2 decimal places
           ' (not valid for negative temperature)
           temperature = (temperature * / 461) + 3200
           Lcdout $fe, $c0, DEC (temperature / 100), ".", DEC2 temperature, " F"

Pause 1000                    ' Display about once a second

Goto mainloop                 ' Do it forever
```

Picbasic Pro Statement Reference

5.46.PAUSE

PAUSE *Period*

Pause the program for *Period* milliseconds. *Period* is 16-bits, so delays can be up to 65,535 milliseconds (a little over a minute). Unlike the other delay functions (**NAP** and **SLEEP**), **PAUSE** doesn't put the microcontroller into low power mode. Thus, **PAUSE** consumes more power but is also much more accurate. It has the same accuracy as the system clock. **PAUSE** assumes an oscillator frequency of 4MHz. If an oscillator other than 4MHz is used, PBP must be told using a **DEFINE** `OSC OSC` command. See the section on speed for more information.

```
PAUSE 1000      \ Delay for 1 second
```

Picbasic Pro Statement Reference

5.47. PAUSEUS

`PAUSEUS` *Period*

Pause the program for *Period* microseconds. *Period* is 16-bits, so delays can be up to 65,535 microseconds. Unlike the other delay functions (**NAP** and **SLEEP**), **PAUSEUS** doesn't put the microcontroller into low power mode. Thus, **PAUSEUS** consumes more power but is also much more accurate. It has the same accuracy as the system clock.

Because **PAUSEUS** takes a minimum number of cycles to operate, depending on the frequency of the oscillator, delays of less than a minimum number of microseconds are not possible using **PAUSEUS**. To obtain shorter delays, use an assembly language routine in an **ASM** . **ENDASM** construct.

Table 19 Pauseus period

OSC	Minimum delay
3 (3.58)	20us
4	24us
8	12us
10	8us
12	7us
16	5us
20	3us
25*	2us
32*	2us
33*	2us
40**	2us

* PIC17Cxxx and PIC18Cxxx only.

** PIC18Cxxx only.

PAUSEUS assumes an oscillator frequency of 4MHz. If an oscillator other than 4MHz is used, PBP must be told using a **DEFINE** **OSC** command. See the section on speed for more information.

```
PAUSEUS 1000    ' Delay for 1 millisecond
```

Picbasic Pro Statement Reference

5.48. PEEK

PEEK *Address, Var*

Read the microcontroller register at the specified *Address* and stores the result in *Var*. Special PICmicro features such as A/D converters and additional I/O ports may be read using **PEEK**.

However, all of the PICmicro registers can be and should be accessed without using **PEEK** and **POKE**. All of the PICmicro registers are considered 8-bit variables by PicBasic Pro and may be used as you would any other byte-sized variable. They can be read directly or used directly in equations.

To emphasize: **PEEK and POKE should never be used in a PicBasic Pro program.**

B0 = PORTA

' Get current PORTA pin states to B0

Peek and Poke Command Changes

Peek and Poke have been changed to work more like Peek and Poke in the standard PicBasic compiler. For example, Peek PORTB, B0 will now store the value of the PORTB pins to B0. It is still recommended that Peek and Poke not be used. It is much better to simply say B0 = PORTB, for example.

Picbasic Pro Statement Reference

5.49. POKE

POKE Address, Value

Write *Value* to the microcontroller register at the specified *Address*. Special PICmicro features such as A/D converters and additional I/O ports may be written using **POKE**. However, all of the PICmicro registers can be and should be accessed without using **PEEK** and **POKE**. All of the PICmicro registers are considered 8-bit variables by PicBasic Pro and may be used as you would any other byte-sized variable. They can be written directly or used directly in equations.

To emphasize: **PEEK and POKE should never be used in a PicBasic Pro program.**

```
TRISA = 0      ' Set PORTA to all outputs
PORTA.0 = 1    ' Set PORTA bit 0 high
```

Peek and Poke Command Changes

Peek and Poke have been changed to work more like Peek and Poke in the standard PicBasic compiler. For example, Peek PORTB, B0 will now store the value of the PORTB pins to B0. It is still recommended that Peek and Poke not be used. It is much better to simply say B0 = PORTB, for example.

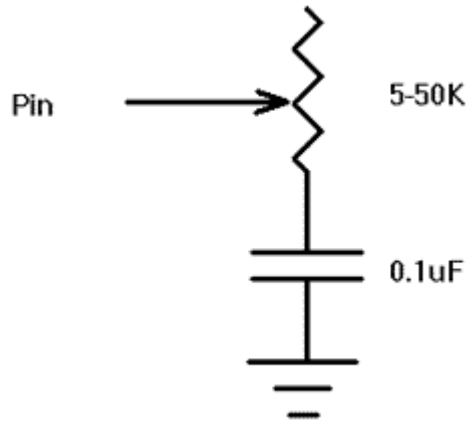
Picbasic Pro Statement Reference

5.50. POT

`POT Pin,Scale,Var`

Reads a potentiometer (or some other resistive device) on *Pin*. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0). The resistance is measured by timing the discharge of a capacitor through the resistor (typically 5K to 50K). *Scale* is used to adjust for varying RC constants. For larger RC constants, *Scale* should be set low (a minimum value of one). For smaller RC constants, *Scale* should be set to its maximum value (255). If *Scale* is set correctly, *Var* should be zero near minimum resistance and 255 near maximum resistance.

Unfortunately, *Scale* must be determined experimentally. To do so, set the device under measure to maximum resistance and read it with *Scale* set to 255. Under these conditions, *Var* will produce an appropriate value for *Scale*. (NOTE: This is the same type of process performed by the **Alt-P** option of the BS1 environment).



```
POT 3,255,B0
```

```
Serout 0,N2400,[#B0]
```

' Read potentiometer on Pin3 to determine scale

' Send pot value serially out Pin0

Picbasic Pro Statement Reference

5.51. PULSIN

PULSIN *Pin, State, Var*

Measures pulse width on *Pin*. If *State* is zero, the width of a low pulse is measured. If *State* is one, the width of a high pulse is measured. The measured width is placed in *Var*. If the pulse edge never happens or the width of the pulse is too great to measure, *Var* is set to zero. If an 8-bit variable is used, only the LSB of the 16-bit measurement is used. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The resolution of **PULSIN** is dependent upon the oscillator frequency. If a 4MHz oscillator is used, the pulse width is returned in 10us increments. If a 20MHz oscillator is used, the pulse width will have a 2us resolution. Defining an **OSC** value has no effect on **PULSIN**. The resolution always changes with the actual oscillator speed.

' Measure high pulse on Pin4 stored in W3

PULSIN PORTB.4,1,W3

Picbasic Pro Statement Reference

5.52. PULSOUT

PULSOUT *Pin, Period*

Generates a pulse on *Pin* of specified *Period*. The pulse is generated by toggling the pin twice, thus the initial state of the pin determines the polarity of the pulse. *Pin* is automatically made an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The resolution of **PULSOUT** is dependent upon the oscillator frequency. If a 4MHz oscillator is used, the *Period* of the generated pulse will be in 10us increments. If a 20MHz oscillator is used, *Period* will have a 2us resolution. Defining an **OSC** value has no effect on **PULSOUT**. The resolution always changes with the actual oscillator speed.

' Send a pulse 1mSec long (at 4MHz) to Pin5

PULSOUT PORTB.5,100

Picbasic Pro Statement Reference

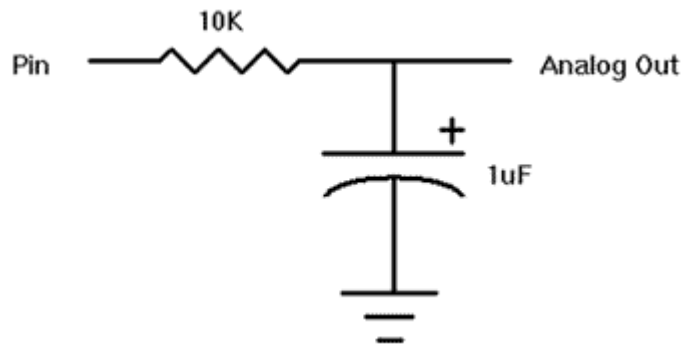
5.53. PWM

PWM *Pin, Duty, Cycle*

Outputs a pulse width modulated pulse train on *Pin*. Each cycle of PWM consists of 256 steps. The *Duty* cycle for each PWM cycle ranges from 0 (0%) to 255 (100%). This PWM cycle is repeated *Cycle* times. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The *Cycle* time of **PWM** is dependent upon the oscillator frequency. If a 4MHz oscillator is used, each *Cycle* would be about 5ms long. If a 20MHz oscillator is used, each *Cycle* would be about 1ms in length. Defining an *OSC* value has no effect on **PWM**. The *Cycle* time always changes with the actual oscillator speed.

Pin is made an output just prior to pulse generation and reverts to an input after generation stops. The **PWM** output on a pin looks like so much garbage, not a beautiful series of square waves. A filter of some sort is necessary to turn the signal into something useful. An RC circuit can be used as a simple D/A converter:



PWM PORTB.7,127,100 ' Send a 50% duty cycle PWM signal out Pin7 for
100 cycles

Picbasic Pro Statement Reference

5.54. RANDOM

RANDOM *Var*

Perform one iteration of pseudo-randomization on *Var*. *Var* should be a 16-bit variable. Array variables with a variable index may not be used in **RANDOM** although array variables with a constant index are allowed. *Var* is used both as the seed and to store the result. The pseudo-random algorithm used has a walking length of 65535 (only zero is not produced).

RANDOM W4 ' Get a random number to W4

Picbasic Pro Statement Reference

5.55. RCTIME

RCTIME *Pin, State, Var*

RCTIME measures the time a *Pin* stays in a particular *State*. It is basically half a **PULSIN**. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

RCTIME may be used to read a potentiometer (or some other resistive device). Resistance can be measured by discharging and timing the charge (or vice versa) of a capacitor through the resistor (typically 5K to 50K).

The resolution of **RCTIME** is dependent upon the oscillator frequency. If a 4MHz oscillator is used, the time in state is returned in 10us increments. If a 20MHz oscillator is used, the time in state will have a 2us resolution. Defining an **OSC** value has no effect on **RCTIME**. The resolution always changes with the actual oscillator speed.

If the pin never changes state, 0 is returned.

Low PORTB.3 ' Discharge cap to start

Pause 10 ' Discharge for 10ms

RCTIME PORTB.3,0,W0 ' Read potentiometer on Pin3

Picbasic Pro Statement Reference

5.56. READ

READ *Address,Var*

Read the on-chip EEPROM at the specified *Address* and stores the result in *Var*. This instruction may only be used with a PICmicro that has an on-chip EEPROM data area such as the PIC16F84, PIC16C84 and the PIC16F87x series.

READ will not work on devices with on-chip I2C interfaced serial EEPROM like the 12CE67x and 16CE62x parts. Use the **I2CREAD** instruction instead.

READ 5,B2 ' Put the value at EEPROM location 5 into B2

Picbasic Pro Statement Reference

5.57. READCODE

READCODE *Address,Var*

Read the word-sized code at location *Address* into *Var*.

The PIC16F87x devices allow code to be read and written at run-time. While writing self-modifying code can be a dangerous technique, it does allow non-volatile data storage above 64 - 256 bytes. One must be very careful not to write over active program memory. The listing file may be examined to determine program addresses.

READCODE 100,W ' Put the code word at location 100 into W

Picbasic Pro Statement Reference

5.58. RESUME

RESUME {*Label*}

Pick up where program left off after handling an interrupt. **RESUME** is similar to **RETURN** but is used at the end of a PicBasic Pro interrupt handler.

If the optional *Label* is used, program execution will continue at the *Label* instead of where it was when it was interrupted. In this case, any other return addresses on the stack will no longer be accessible.

See **ON INTERRUPT** for more information.

clockint:	seconds = seconds + 1	' Count time
	RESUME	' Return to program after interrupt
error:	High errorled	' Turn on error LED
	RESUME restart	' Resume somewhere else

Picbasic Pro Statement Reference

5.59. RETURN

RETURN

Return from subroutine. **RETURN** resumes execution at the statement following the **GOSUB** which called the subroutine.

```
Gosub sub1      ' Go to subroutine labeled sub1
...
sub1:  Serout 0,N2400,["Lunch"]  ' Send "Lunch" out Pin0 serially
      RETURN      ' Return to main program after Gosub
```

Picbasic Pro Statement Reference

5.60. REVERSE

REVERSE *Pin*

If *Pin* is an input, it is made an output. If *Pin* is an output, it is made an input. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

Output 4 ' Make Pin4 an output

REVERSE 4 ' Change Pin4 to an input

Picbasic Pro Statement Reference

5.61. SELECT CASE

Case statements have been added that, in some cases, are easier to use than multiple If..Thens. These statements are used to compare a variable with different values or ranges of values, and take action based on the value.

```
Select Case var
  Case expr1 {, expr...}
    statements
  Case expr2 {, expr...}
    statements
  {Case Else
    statements}
End Select
```

The variable used in all of the comparisons is specified in the Select Case statement. Each Case is followed by the statements to be executed if the Case is true. If none of the Cases are true, the statements under the optional Case Else statement are executed. An End Select closes the Select Case.

Picbasic Pro Statement Reference

Select Case Example

'PicBasic Pro program to demonstrate the Select Case...Case...End Select structure.
'Each loop results in the same output using slightly different conditions.

' Define Debug pin

```
DEFINE DEBUG_REG PORTC
DEFINE DEBUG_BIT 6
DEFINE DEBUG_BAUD 9600
DEFINE DEBUG_MODE 1
```

```
B10 VAR BYTE ' Used to count and specify the case
```

```
loop1: ' First example
  Pause 250
  B10 = B10 + 1 ' Increment B10
  Select Case B10 ' Begin Select Case - use B10
    Case 1 ' Execute if B10=1
      Debug "loop1 case 1",10,13 ' Send string and new line
    Case 2 ' Execute if B10=2
      Debug "loop1 case 2",10,13
    Case 4 ' Execute if B10=4
      Debug "loop1 case 4",10,13
    Case is >5 ' Execute if B10 > 5
      Clear ' Set B10 to 0
      Debug 10,13 ' Send new line
      GoTo loop2 ' Finished - jump to second
      \ example
    Case is >2 ' Execute if B10>2 (but not >5 or =4)
      Debug "loop1 case 3,5",10,13

  End Select ' Resume here after case is executed

  GoTo loop1 ' Continue first example
```

```
loop2: ' Second Example
  Pause 250
  B10 = B10 + 1 ' Increment B10
  Select Case B10 ' Begin Select Case - use B10
    Case 1 ' Execute if B10=1
      Debug "loop2 case 1",10,13
    Case 2 ' Execute if B10=2
      Debug "loop2 case 2",10,13
    Case 4 ' Execute if B10=4
      Debug "loop2 case 4",10,13
    Case is <6 ' Execute if B10<6 (but not = 1,2, or 4)
      Debug "loop2 case 3,5",10,13
    Case Else ' Execute if no other conditions met (B10>5)
      Clear ' Set B10 to 0
      Debug 10,13 ' Send new line
      GoTo loop1 ' Finished - jump back to first example
  End Select ' Resume here after case is executed
  GoTo loop2 ' Continue second example
```

Picbasic Pro Statement Reference

5.62. SERIN

```
SERIN Pin,Mode,{Timeout,Label},{[Qual...],}{Item...}
```

Receive one or more *Items* on *Pin* in standard asynchronous format using 8 data bits, no parity and one stop bit (8N1). **SERIN** is similar to the BS1 Serin command with the addition of a *Timeout*. *Pin* is automatically made an input. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0). The *Mode* names (e.g. T2400) are defined in the file MODEDEFS.BAS. To use them, add the line:

```
Include "modedefs.bas"
```

to the top of the PicBasic Pro program. BS1DEFS.BAS and BS2DEFS.BAS already includes MODEDEFS.BAS. Do not include it again if one of these files is already included. The *Mode* numbers may be used without including this file.

Table 20 Serin mode definitions

<i>Mode</i>	<i>Mode No.</i>	<i>Baud Rate</i>	<i>State</i>
T2400	0	2400	
T1200	1	1200	
T9600	2	9600	
T300	3	300	True
N2400	4	2400	
N1200	5	1200	
N9600	6	9600	
N300	7	300	Inverted

An optional *Timeout* and *Label* may be included to allow the program to continue if a character is not received within a certain amount of time. *Timeout* is specified in units of 1 millisecond.

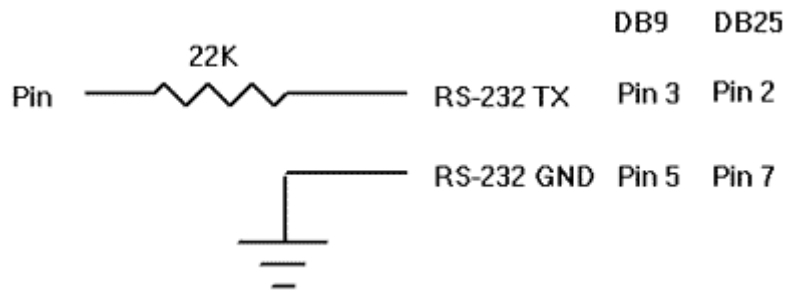
The list of data items to be received may be preceded by one or more qualifiers enclosed within brackets. **SERIN** must receive these bytes in exact order before receiving the data items. If any byte received does not match the next byte in the qualifier sequence, the qualification process starts over (i.e. the next received byte is compared to the first item in the qualifier list). A *Qualifier* can be a constant, variable or a string constant. Each character of a string is treated as an individual qualifier.

Once the qualifiers are satisfied, **SERIN** begins storing data in the variables associated with each *Item*. If the variable name is used alone, the value of the received ASCII character is stored in the variable. If variable is preceded by a pound sign (#), **SERIN** converts a decimal value in ASCII and stores the result in that variable. All non-digits received prior to the first digit of the decimal value are ignored and discarded. The non-digit character which terminates the decimal value is also discarded.

SERIN assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the OSC setting to the new oscillator value.

While single-chip RS-232 level converters are common and inexpensive, the excellent I/O specifications of the PICmicro allow most applications to run without level converters. Rather, inverted input (N300..N9600) can be used in conjunction with a current limiting resistor.

Picbasic Pro Statement Reference



SERIN 1,N2400,["A"],B0 ' Wait until the character "A" is received serially

on Pin1 and put next character into

B0

Picbasic Pro Statement Reference

5.63. SERIN2

```
SERIN2 DataPin{\FlowPin},Mode,{ParityLabel,}  
{Timeout,Label,}[Item...]
```

Receive one or more *Items* on *Pin* in standard asynchronous format. **SERIN2** is similar to the BS2 Serin command. *DataPin* is automatically made an input. The optional *FlowPin* is automatically made an output. *DataPin* and *FlowPin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The optional flow control pin, *FlowPin*, may be included to help keep data from overrunning the receiver. If it is used, *FlowPin* is automatically set to the enabled state to allow transmission of each character. This enabled state is determined by the polarity of the data specified by *Mode*.

Mode is used to specify the baud rate and operating parameters of the serial transfer. The low order 13 bits select the baud rate. Bit 13 selects parity or no parity. Bit 14 selects inverted or true level. Bit 15 is not used.

The baud rate bits specify the bit time in microseconds - 20. To find the value for a given baud rate, use the equation:

$$(1000000 / \text{baud}) - 20$$

Some standard baud rates are listed in the following table.

Table 21 Serin2 baud rates

Baud Rate	Bits 0 - 12
300	3313
600	1646
1200	813
2400	396
4800	188
9600	84
19200	32

Bit 13 selects even parity (bit 13 = 1) or no parity (bit 13 = 0). Normally, the serial transmissions are 8N1 (8 data bits, no parity and 1 stop bit). If parity is selected, the data is received as 7E1 (7 data bits, even parity and 1 stop bit).

Bit 14 selects the level of the data and flow control pins. If bit 14 = 0, the data is received in true form for use with RS-232 drivers. If bit 14 = 1, the data is received inverted. This mode can be used to avoid installing RS-232 drivers.

Some examples of *Mode* are: *Mode* = 84 (9600 baud, no parity, true), *Mode* = 16780 (2400 baud, no parity, inverted), *Mode* = 27889 (300 baud, even parity, inverted).

If *ParityLabel* is included, this label will be jumped to if a character with bad parity is received. It should only be used if even parity is selected (bit 13 = 1).

An optional *Timeout* and *Label* may be included to allow the program to continue if a character is not received within a certain amount of time. *Timeout* is specified in units of 1 millisecond.

A **DEFINE** allows the use of data bits other than 8 (or 7 with parity). **SER2_BITS** data bits may range from 4 bits to 8 (the default if no **DEFINE** is specified). Enabling parity uses one of the number of bits specified.

Defining **SER2_BITS** to 9 allows 8 bits to be read and written along with a 9th parity bit.

With parity disabled (the default):

Picbasic Pro Statement Reference

```

DEFINE SER2_BITS 4      ' Set Serin2 and Serout2 data bits to 4
DEFINE SER2_BITS 5      ' Set Serin2 and Serout2 data bits to 5
DEFINE SER2_BITS 6      ' Set Serin2 and Serout2 data bits to 6
DEFINE SER2_BITS 7      ' Set Serin2 and Serout2 data bits to 7
DEFINE SER2_BITS 8      ' Set Serin2 and Serout2 data bits to 8 (default)

```

With parity enabled:

```

DEFINE SER2_BITS 5      ' Set Serin2 and Serout2 data bits to 4
DEFINE SER2_BITS 6      ' Set Serin2 and Serout2 data bits to 5
DEFINE SER2_BITS 7      ' Set Serin2 and Serout2 data bits to 6
DEFINE SER2_BITS 8      ' Set Serin2 and Serout2 data bits to 7 (default)
DEFINE SER2_BITS 9      ' Set Serin2 and Serout2 data bits to 8

```

SERIN2 supports many different data modifiers which may be mixed and matched freely within a single **SERIN2** statement to provide various input formatting.

Table 22 Serin2 command modifiers

<i>Modifier</i>	<i>Operation</i>
BIN{1..16}	Receive binary digits
DEC{1..5}	Receive decimal digits
HEX{1..4}	Receive hexadecimal digits
SKIP n	Skip n received characters
STR ArrayVar{n}{\c}	Receive string of n characters optionally ended in character c
WAIT ()	Wait for sequence of characters
WAITSTR ArrayVar{\n}	Wait for character string

Notes

- 1) A variable preceded by **BIN** will receive the ASCII representation of its binary value. For example, if **BIN B0** is specified and **A1000** is received, **B0** will be set to 8.
- 2) A variable preceded by **DEC** will receive the ASCII representation of its decimal value. For example, if **DEC B0** is specified and **A123** is received, **B0** will be set to 123.
- 3) A variable preceded by **HEX** will receive the ASCII representation of its hexadecimal value. For example, if **HEX B0** is specified and **AFF** is received, **B0** will be set to 254.
- 4) **SKIP** followed by a count will skip that many characters in the input stream. For example, **SKIP 4** will skip 4 characters..
- 5) **STR** followed by a byte array variable, count and optional ending character will receive a string of characters. The string length is determined by the count or when the optional character is encountered in the input.
- 6) The list of data items to be received may be preceded by one or more qualifiers between parenthesis after **WAIT**. **SERIN2** must receive these bytes in exact order before receiving the data items. If any byte received does not match the next byte in the qualifier sequence, the qualification process starts over (i.e. the next received byte is compared to the first item in the qualifier list). A *Qualifier* can be a constant, variable or a string constant. Each character of a string is treated as an individual qualifier.

Picbasic Pro Statement Reference

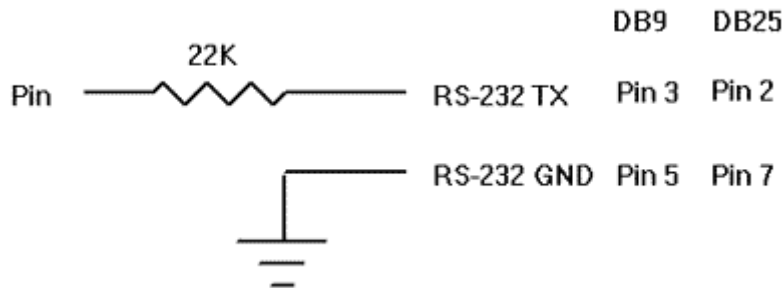
7) **WAITSTR** can be used as **WAIT** above to force **SERIN2** to wait for a string of characters of an optional length before proceeding.

Once any **WAIT** or **WAITSTR** qualifiers are satisfied, **SERIN2** begins storing data in the variables associated with each *Item*. If the variable name is used alone, the value of the received ASCII character is stored in the variable. If variable is preceded by **BIN**, **DEC** or **HEX**, then **SERIN2** converts a binary, decimal or hexadecimal value in ASCII and stores the result in that variable. All non-digits received prior to the first digit of the decimal value are ignored and discarded. The non-digit character which terminates the value is also discarded.

BIN, **DEC** and **HEX** may be followed by a number. Normally, these modifiers receive as many digits as are in the input. However, if a number follows the modifier, **SERIN2** will always receive that number of digits, skipping additional digits as necessary.

SERIN2 assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to the new oscillator value.

While single-chip RS-232 level converters are common and inexpensive, thanks to current RS-232 implementation and the excellent I/O specifications of the PICmicro, most applications don't require level converters. Rather, inverted TTL (*Mode* bit 14 = 1) can be used. A current limiting resistor is suggested (RS-232 is suppose to be short-tolerant).



' Wait until the character "A" is received serially on Pin1 and put next character into

B0

```
SERIN2 1,16780,[wait ("A"),B0]
```

' Skip 2 chars and grab a 4 digit decimal number

```
SERIN2 PORTA.1,84,[skip 2,dec4 B0]
```

```
SERIN2 PORTA.1\PORTA.0,84,100,tlabel,[wait ("x", b0), str ar]
```

Picbasic Pro Statement Reference

5.64. SEROUT

```
SEROUT Pin,Mode, [Item{,Item...}]
```

Sends one or more items to *Pin* in standard asynchronous format using 8 data bits, no parity and one stop (8N1). **SEROUT** is similar to the BS1 Serout command. *Pin* is automatically made an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The *Mode* names (e.g. T2400) are defined in the file MODEDEFS.BAS. To use them, add the line:

```
Include "modedefs.bas"
```

to the top of the PicBasic Pro program. BS1DEFS.BAS and BS2DEFS.BAS already includes MODEDEFS.BAS. Do not include it again if one of these files is already included. The *Mode* numbers may be used without including this file.

Table 23 Serout mode definition

<i>Mode</i>	<i>Mode No.</i>	<i>Baud Rate</i>	<i>State</i>
T2400	0	2400	
T1200	1	1200	
T9600	2	9600	
T300	3	300	Driven True
N2400	4	2400	
N1200	5	1200	
N9600	6	9600	
N300	7	300	Driven Inverted
OT2400	8	2400	
OT1200	9	1200	
OT9600	10	9600	
OT300	11	300	Open True
ON2400	12	2400	
ON1200	13	1200	
ON9600	14	9600	
ON300	15	300	Open Inverted

SEROUT supports three different data types which may be mixed and matched freely within a single **SEROUT** statement.

Picbasic Pro Statement Reference

Table 24 Serout data type modifier

Notes
1) A string constant is output as a literal string of characters.
2) A numeric value (either a variable or a constant) will send the corresponding ASCII character. Most notably, 13 is carriage return and 10 is line feed.
3) A numeric value preceded by a pound sign (#) will send the ASCII representation of its decimal value. For example, if W0 = 123, then #W0 (or #123) will send '1', '2', '3'.

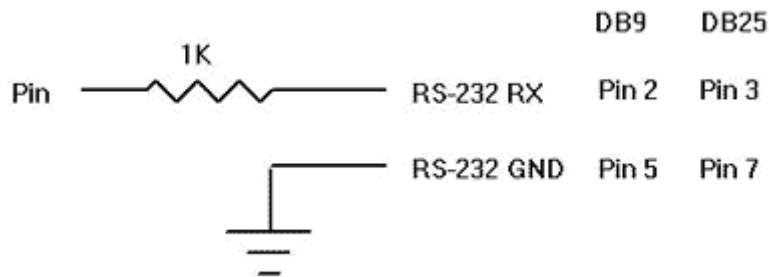
SEROUT assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to the new oscillator value.

In some cases, the transmission rates of **SEROUT** instructions may present characters too quickly to the receiving device. A **DEFINE** adds character pacing to the serial output transmissions. This allows additional time between the characters as they are transmitted. The character pacing **DEFINE** allows a delay of 1 to 65,535 microseconds (.001 to 65.535 milliseconds) between each character transmitted.

For example, to pause 1 millisecond between the transmission of each character:

```
DEFINE CHAR_PACING 1000
```

While single-chip RS-232 level converters are common and inexpensive, thanks to current RS-232 implementation and the excellent I/O specifications of the PICmicro, most applications don't require level converters. Rather, inverted TTL (N300..N9600) can be used. A current limiting resistor is suggested (RS-232 is suppose to be short-tolerant).



```
SEROUT 0,N2400,[#B0,10] ' Send the ASCII value of B0 followed by  
a linefeed out Pin0 serially
```

Picbasic Pro Statement Reference

5.65. SEROUT2

```
SEROUT2 DataPin{\FlowPin},Mode,{Pace,}  
{Timeout,Label,}[Item...]
```

Send one or more *Items* to *DataPin* in standard asynchronous format. **SEROUT2** is similar to the BS2 Serout command. *DataPin* is automatically made an output. The optional *FlowPin* is automatically made an input. *DataPin* and *FlowPin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

The optional flow control pin, *FlowPin*, may be included to help keep data from overrunning the receiver. If it is used, the serial data will not be sent until *FlowPin* is in the proper state. This state is determined by the polarity of the data specified by *Mode*.

An optional *Timeout* and *Label* may be included to allow the program to continue if the *FlowPin* does not change to the enabled state within a certain amount of time. *Timeout* is specified in units of 1 millisecond.

In some cases, the transmission rates of **SEROUT2** instructions may present characters too quickly to the receiving device. It may not be desirable to use an extra pin for flow control. An optional *Pace* can be used to add character pacing to the serial output transmissions. This allows additional time between the characters as they are transmitted. The character pacing allows a delay of 1 to 65,535 milliseconds between each character transmitted.

Mode is used to specify the baud rate and operating parameters of the serial transfer. The low order 13 bits select the baud rate. Bit 13 selects parity or no parity. Bit 14 selects inverted or true level. Bit 15 selects whether it is driven or open.

The baud rate bits specify the bit time in microseconds - 20. To find the value for a given baud rate, use the equation:

$$(1000000 / \text{baud}) - 20$$

Some standard baud rates are listed in the following table.

Table 25 Serout2 Baud rate settings

Baud Rate	Bits 0 - 12
300	3313
600	1646
1200	813
2400	396
4800	188
9600	84
19200	32

Bit 13 selects even parity (bit 13 = 1) or no parity (bit 13 = 0). Normally, the serial transmissions are 8N1 (8 data bits, no parity and 1 stop bit). If parity is selected, the data is sent as 7E1 (7 data bits, even parity and 1 stop bit).

Bit 14 selects the level of the data and flow control pins. If bit 14 = 0, the data is sent in true form for use with RS-232 drivers. If bit 14 = 1, the data is sent inverted. This mode can be used to avoid installing RS-232 drivers.

Bit 15 selects whether the data pin is always driven (bit 15 = 0), or is open in one of the states (bit 15 = 1). The open mode can be used to chain several devices together on the same serial bus.

Some examples of *Mode* are: *Mode* = 84 (9600 baud, no parity, true, always driven), *Mode* = 16780 (2400 baud, no parity, inverted, driven),

Mode = 60657 (300 baud, even parity, inverted, open).

Picbasic Pro Statement Reference

A **DEFINE** allows the use of data bits other than 8 (or 7 with parity). **SER2_BITS** data bits may range from 4 bits to 8 (the default if no **DEFINE** is specified). Enabling parity uses one of the number of bits specified. Defining **SER2_BITS** to 9 allows 8 bits to be read and written along with a 9th parity bit.

Table 26 Define SER2 BITS - parity disabled (the default)

DEFINE	Description
DEFINE SER2_BITS 4	Set Serin2 and Serout2 data bits to 4
DEFINE SER2_BITS 5	Set Serin2 and Serout2 data bits to 5
DEFINE SER2_BITS 6	Set Serin2 and Serout2 data bits to 6
DEFINE SER2_BITS 7	Set Serin2 and Serout2 data bits to 7
DEFINE SER2_BITS 8	Set Serin2 and Serout2 data bits to 8 (default)

Table 27 Define SER2 BITS - With parity enabled:

DEFINE	DESCRIPTION
DEFINE SER2_BITS 4	Set Serin2 and Serout2 data bits to 3
DEFINE SER2_BITS 5	Set Serin2 and Serout2 data bits to 4
DEFINE SER2_BITS 6	Set Serin2 and Serout2 data bits to 5
DEFINE SER2_BITS 7	Set Serin2 and Serout2 data bits to 6
DEFINE SER2_BITS 8	Set Serin2 and Serout2 data bits to 7 (default)
DEFINE SER2_BITS 9	Set Serin2 and Serout2 data bits to 8

SEROUT2 supports many different data modifiers which may be mixed and matched freely within a single **SEROUT2** statement to provide various output formatting.

Table 28 SEROUT2 data modifiers

Modifier	Operation
{I}{S}BIN{1..16}	Send binary digits
{I}{S}DEC{1..5}	Send decimal digits
{I}{S}HEX{1..4}	Send hexadecimal digits
REP c\n	Send character c repeated n times
STR ArrayVar{n}	Send string of n characters
NOTES	
1)	A string constant is output as a literal string of characters.
2)	A numeric value (either a variable or a constant) will send the corresponding ASCII character. Most notably, 13 is carriage return and 10 is line feed.
3)	A numeric value preceded by BIN will send the ASCII representation of its binary value. For example, if B0 = 8 , then BIN B0 (or BIN 8) will send "1000".
4)	A numeric value preceded by DEC will send the ASCII representation of its decimal value. For example, if B0 = 123 , then DEC B0 (or DEC 123) will send "123".
5)	A numeric value preceded by HEX will send the ASCII representation of its hexadecimal value. For example, if B0 = 254 , then HEX B0 (or HEX 254) will send "FE".
6)	REP followed by a character and count will repeat the character, count time. For example, REP A0"\4 will send "0000".
7)	STR followed by a byte array variable and optional count will send a string of

Picbasic Pro Statement Reference

characters. The string length is determined by the count or when a 0 character is encountered in the string.

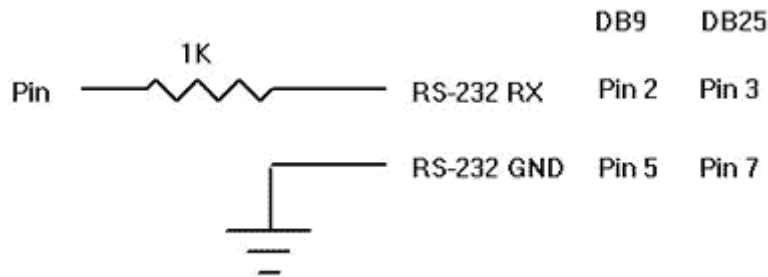
BIN, **DEC** and **HEX** may be preceded or followed by several optional parameters. If any of them are preceded by an **I** (for indicated), the output will be preceded by either a **A%@**, **A#@** or **A\$@** to indicate the following value is binary, decimal or hexadecimal.

If any are preceded by an **S** (for signed), the output will be sent preceded by a **A-A** if the high order bit of the data is set. This allows the transmission of negative numbers. Keep in mind that all of the math and comparisons in PBP are unsigned. However, unsigned math can yield signed results. For example, take the case of **B0 = 9 - 10**. The result of **DEC B0** would be **A255**". Sending **SDEC B0** would give **A-1**" since the high order bit is set. So with a little trickery, the unsigned math of PBP can yield signed results.

BIN, **DEC** and **HEX** may also be followed by a number. Normally, these modifiers display exactly as many digits as are necessary, zero blanked (leading zeros are not sent). However, if a number follows the modifier, **SEROUT2** will always send that number of digits, adding leading zeros as necessary. It will also trim of any extra high order digits. For example, **BIN6 8** would send **A001000**" and **BIN2 8** would send **A00**".

Any or all of the modifier combinations may be used at once. For example, **ISDEC4 B0**. **SEROUT2** assumes a 4MHz oscillator when generating its bit timing. To maintain the proper baud rate timing with other oscillator values, be sure to **DEFINE** the **OSC** setting to the new oscillator value.

While single-chip RS-232 level converters are common and inexpensive, thanks to current RS-232 implementation and the excellent I/O specifications of the PICmicro, most applications don't require level converters. Rather, inverted TTL (*Mode* bit 14 = 1) can be used. A current limiting resistor is suggested (RS-232 is suppose to be short-tolerant).



```
' Send the ASCII value of B0 followed by a linefeed out Pin0 serially at 2400 baud
SEROUT2 0,16780,[dec B0,10]
```

```
' Send "B0 =" followed by the binary value of B0 out PORTA pin 1 serially at 9600
baud
```

```
SEROUT2 PORTA.1,84,["B0=", ihex4 B0]
```

Picbasic Pro Statement Reference

Serin2 Serout2 mode settings

Here is a complete list of the possible mode settings for PicBasic Pro's *Serin2* and *Serout2* commands..

Table 29 Serin2 Serout2 mode settings

Baud Rate	Bit 15 (Output)	Bit 14 (Conversion)	Bit 13 (Parity)	Mode Number
300	Driven	True	None	3313
300	Driven	True	Even*	11505
300	Driven	Inverted	None	19697
300	Driven	Inverted	Even*	27889
300	Open	True	None	36081
300	Open	True	Even*	44273
300	Open	Inverted	None	52465
300	Open	Inverted	Even*	60657
600	Driven	True	None	1646
600	Driven	True	Even*	9838
600	Driven	Inverted	None	18030
600	Driven	Inverted	Even*	26222
600	Open	True	None	34414
600	Open	True	Even*	42606
600	Open	Inverted	None	50798
600	Open	Inverted	Even*	58990
1200	Driven	True	None	813
1200	Driven	True	Even*	9005
1200	Driven	Inverted	None	17197
1200	Driven	Inverted	Even*	25389
1200	Open	True	None	33581
1200	Open	True	Even*	41773
1200	Open	Inverted	None	49965
1200	Open	Inverted	Even*	58157
2400	Driven	True	None	396
2400	Driven	True	Even*	8588
2400	Driven	Inverted	None	16780
2400	Driven	Inverted	Even*	24972
2400	Open	True	None	33164
2400	Open	True	Even*	41356

Picbasic Pro Statement Reference

2400	Open	Inverted	None	49548
2400	Open	Inverted	Even*	57740
4800	Driven	True	None	188
4800	Driven	True	Even*	8380
4800	Driven	Inverted	None	16572
4800	Driven	Inverted	Even*	24764
4800	Open	True	None	32956
4800	Open	True	Even*	41148
4800	Open	Inverted	None	49340
4800	Open	Inverted	Even*	57532
<i>9600 baud may be unreliable with 4MHz clock</i>				
9600	Driven	True	None	84
9600	Driven	True	Even*	8276
9600	Driven	Inverted	None	16486
9600	Driven	Inverted	Even*	24678
9600	Open	True	None	32852
9600	Open	True	Even*	41044
9600	Open	Inverted	None	49254
9600	Open	Inverted	Even*	57446
<i>baud rates below require 8MHz clock or faster</i>				
14400	Driven	True	None	49
14400	Driven	True	Even*	8241
14400	Driven	Inverted	None	16433
14400	Driven	Inverted	Even*	24625
14400	Open	True	None	32817
14400	Open	True	Even*	41009
14400	Open	Inverted	None	49201
14400	Open	Inverted	Even*	57393
<i>baud rates below require 10MHz clock or faster</i>				
19200	Driven	True	None	32
19200	Driven	True	Even*	8224
19200	Driven	Inverted	None	16416
19200	Driven	Inverted	Even*	24608
19200	Open	True	None	32800
19200	Open	True	Even*	40992
19200	Open	Inverted	None	49184
19200	Open	Inverted	Even*	57376
<i>baud rates below require 16MHz clock or faster</i>				
28800	Driven	True	None	15
28800	Driven	True	Even*	8207
28800	Driven	Inverted	None	16399
28800	Driven	Inverted	Even*	24591
28800	Open	True	None	32783

Picbasic Pro Statement Reference

28800	Open	True	Even*	40975
28800	Open	Inverted	None	49167
28800	Open	Inverted	Even	57359
33600	Driven	True	None	10
33600	Driven	True	Even*	8202
33600	Driven	Inverted	None	16394
33600	Driven	Inverted	Even*	24586
33600	Open	True	None	32778
33600	Open	True	Even*	40970
33600	Open	Inverted	None	49162
33600	Open	Inverted	Even	57354
<i>baud rates below require 20MHz clock or faster</i>				
38400	Driven	True	None	6
38400	Driven	True	Even*	8198
38400	Driven	Inverted	None	16390
38400	Driven	Inverted	Even*	24582
38400	Open	True	None	32774
38400	Open	True	Even*	40966
38400	Open	Inverted	None	49158
38400	Open	Inverted	Even	57350

**Parity is odd when DEFINE SER2_ODD 1 is used.*

Picbasic Pro Statement Reference

5.66. SHIF TIN

SHIF TIN *DataPin, ClockPin, Mode, [Var{\Bits}...]*

Clock *ClockPin*, synchronously shift in bits on *DataPin* and store the byte(s) received into *Var*. *ClockPin* and *DataPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

\Bits optionally specifies the number of bits to be shifted in. If it is not specified, 8 bits are shifted in, independent of the variable type.

The *Mode* names (e.g. **MSBPRE**) are defined in the file `MODEDEFS.BAS`. To use them, add the line:

```
Include "modedefs.bas"
```

to the top of the PicBasic Pro program. `BS1DEFS.BAS` and `BS2DEFS.BAS` already includes `MODEDEFS.BAS`. Do not include it again if one of these files is already included. The *Mode* numbers may be used without including this file.. Some *Modes* do not have a name.

For *Modes* 0-3, the clock idles low, toggles high to clock in a bit, and then returns low. For *Modes* 4-7, the clock idles high, toggles low to clock in a bit, and then returns high.

Table 30 Shiftin Data Modes

<i>Mode No</i>	<i>Operation</i>
0	Shift data in highest bit first. Read data before sending clock Clock idles low.
1	Shift data in lowest bit first. Read data before sending clock. Clock idles low.
2	Shift data in highest bit first. Read data after sending clock. Clock idles low.
3	Shift data in lowest bit first. Read data after sending clock. Clock idles low.
4	Shift data in highest bit first. Read data before sending clock. Clock idles high.
5	Shift data in lowest bit first. Read data before sending clock. Clock idles high.
6	Shift data in highest bit first. Read data after sending clock. Clock idles high.
7	Shift data in lowest bit first. Read data after sending clock. Clock idles high.

The shift clock runs at about 50KHz dependent on the oscillator. The active state is held to a minimum of 2 microseconds. A **DEFINE** allows the active state of the clock to be extended by an additional number of microseconds up to 65,535 (65.535 milliseconds) to slow the clock

Picbasic Pro Statement Reference

rate. The minimum additional delay is defined by the **PAUSEUS** timing. See its section for the minimum for any given oscillator.

For example, to slow the clock by an additional 100 microseconds:

```
DEFINE SHIFT_PAUSEUS 100

SHIFTIN 0,1,MSBPRE,[B0,B1\4]
```

Picbasic Pro Statement Reference

5.67. SHIFTOUT

SHIFTOUT *DataPin, ClockPin, Mode, [Var{\Bits}...]*

Synchronously shift out *Var* on *ClockPin* and *DataPin*. *ClockPin* and *DataPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

\Bits optionally specifies the number of bits to be shifted out. If it is not specified, 8 bits are shifted out, independent of the variable type.

The *Mode* names (e.g. **LSBFIRST**) are defined in the file `MODEDEFS.BAS`. To use them, add the line:

```
Include Amodedefs.bas@
```

to the top of the PicBasic Pro program. `BS1DEFS.BAS` and `BS2DEFS.BAS` already includes `MODEDEFS.BAS`. Do not include it again if one of these files is already included. The *Mode* numbers may be used without including this file. Some *Modes* do not have a name.

For *Modes* 0-1, the clock idles low, toggles high to clock in a bit, and then returns low. For *Modes* 4-5, the clock idles high, toggles low to clock in a bit, and then returns high.

Table 31 SHIFTOUT Data modes

Mode No.	Operation
0	Shift data out lowest bit first. Clock idles low
1	Shift data out highest bit first. Clock idles low.
4	Shift data out lowest bit first. Clock idles high.
5	Shift data out highest bit first. Clock idles high.

The shift clock runs at about 50KHz dependent on the oscillator. The active state is held to a minimum of 2 microseconds. A **DEFINE** allows the active state of the clock to be extended by an additional number of microseconds up to 65,535 (65.535 milliseconds) to slow the clock rate. The minimum additional delay is defined by the **PAUSEUS** timing. See its section for the minimum for any given oscillator.

For example, to slow the clock by an additional 100 microseconds:

```
DEFINE SHIFT_PAUSEUS 100

SHIFTOUT 0,1,MSBFIRST,[B0,B1]
SHIFTOUT PORTA.1, PORTA.2, 1,[wordvar\4]
```

Picbasic Pro Statement Reference

5.68. SLEEP

SLEEP *Period*

Place microcontroller into low power mode for *Period* seconds. *Period* is 16-bits, so delays can be up to 65,535 seconds (just over 18 hours).

SLEEP uses the Watchdog Timer so it is independent of the actual oscillator frequency. The granularity is about 2.3 seconds and may vary based on device specifics and temperature. This variance is unlike the BASIC Stamp. The change was necessitated because when the PICmicro executes a Watchdog Timer reset, it resets many of the internal registers to predefined values. These values may differ greatly from what your program may expect. By running the **SLEEP** command uncalibrated, this issue is sidestepped.

SLEEP 60 ' Sleep for about 1 minute

Picbasic Pro Statement Reference

5.69. SOUND

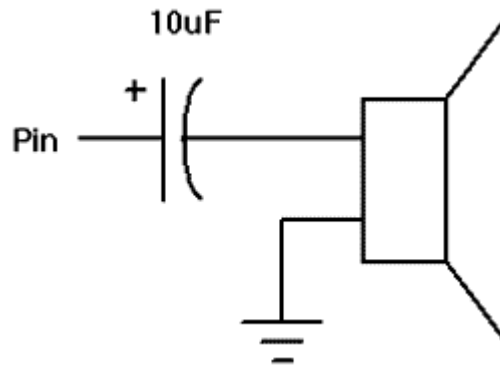
SOUND *Pin*, [*Note*, *Duration*{, *Note*, *Duration*...}]

Generates tone and/or white noise on the specified *Pin*. *Pin* is automatically made an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

Note 0 is silence. *Notes* 1-127 are tones. *Notes* 128-255 are white noise. Tones and white noises are in ascending order (i.e. 1 and 128 are the lowest frequencies, 127 and 255 are the highest). *Note* 1 is about 78.74Hz and *Note* 127 is about 10,000Hz.

Duration is 0-255 and determines how long the *Note* is played in about 12 millisecond increments. *Note* and *Duration* needn't be constants.

SOUND outputs TTL-level square waves. Thanks to the excellent I/O characteristics of the PICmicro, a speaker can be driven through a capacitor. The value of the capacitor should be determined based on the frequencies of interest and the speaker load. Piezo speakers can be driven directly.



SOUND PORTB.7,[100,10,50,10] ' Send 2 sounds consecutively to Pin7

Picbasic Pro Statement Reference

5.70. STOP

STOP

Stop program execution by executing an endless loop. This does not place the microcontroller into low power mode. The microcontroller is still working as hard as ever. It is just not getting much done.

STOP ' Stop program dead in its tracks

Picbasic Pro Statement Reference

5.71. SWAP

SWAP *Variable,Variable*

Exchange the values between 2 variables. Usually, it is a tedious process to swap the value of 2 variables. **SWAP** does it in one statement without using any intermediate variables. It can be used with bit, byte and word variables. Array variables with a variable index may not be used in **SWAP** although array variables with a constant index are allowed.

```
temp = B0          ' Old way
```

```
B0 = B1
```

```
B1 = temp
```

```
SWAP B0, B1      ' New way
```

Picbasic Pro Statement Reference

5.72. TOGGLE

TOGGLE *Pin*

Invert the state of the specified *Pin*. *Pin* is automatically made an output. *Pin* may be a constant, 0 - 15, or a variable that contains a number 0 - 15 (e.g. B0) or a pin name (e.g. PORTA.0).

```
Low 0          ' Start Pin0 as low
TOGGLE 0      ' Change state of Pin0 to high
```

The PORTB.0[cnt] trick does not work with commands, including TOGGLE. With commands, you can use a constant or a variable that specifies a number for the pin. There is a table in the pins section manual that shows which pins are assigned to which numbers.

For example:

```
Toggle 0      ' Toggle PORTB.0
cnt = 0
Toggle cnt    ' Toggle cnt (PORTB.0)
```

For example

The following program will toggle each pin of portB in sequence :

```
CMCON = 7      'Disable PortA comparators.
TRISA = 0      'All PortA pins are outputs.
TRISB = 0      'All PortB pins are outputs.

cnt VAR BYTE   'cnt is the variable used in the FOR..NEXT loop.
PORTB = 0      'Initially, all PortB outputs are low.
```

BEGIN:

```
FOR cnt = 0 to 7      'Loop to change the output state of
TOGGLE cnt          '   PortB pins from 0 to 7.
PAUSE 500           'Wait for half second.
NEXT
>GOTO BEGIN         'Go back to the loop.
```

Picbasic Pro Statement Reference

5.73. USBInit

Support for the PIC16C745 and 765 low-speed USB devices. This support takes the form of three new PBP commands as well as some modifications to the Microchip USB libraries

Support for the PIC16C745 and 765 low-speed USB devices. This support takes the form of three new PBP commands as well as some modifications to the Microchip USB libraries

USBInit needs to be one of the first statements in the program. It will initialize the USB portion of the PICmicro MCU and wait until the USB bus is configured and enabled.

Picbasic Pro Statement Reference

5.74. USBIn

USBIn endpoint, buffer, countvar, label

USBIn gets any available USB data for the endpoint and places it in the buffer. Buffer must be a byte array of suitable length to contain the data. Countvar will contain the number of bytes transferred to the buffer. Label will be jumped to if no data is available.

Picbasic Pro Statement Reference

5.75. USBOut

USBOut endpoint, buffer, count, label

USBOut takes count number of bytes from the buffer and sends them to the USB endpoint. If the USB buffer does not have room for the data because of a pending transmission, no data will be transferred and program execution will continue at label.

The USB subdirectory contains the modified Microchip USB libraries as well as example programs. USB programs require several additional files to operate (which are in the USB subdirectory), some of which will require modification for your particular application. See the text file in the USB subdirectory for more information on the USB commands.

USB communications is much more complicated than synchronous (Shiftin and Shiftout) and asynchronous (Serin, Serout and so forth) communications. There is much more to know about USB operation that can possibly be described here. The USB information on the Microchip web site needs to be studied. Also, the book "USB Complete" by Jan Axelson may be helpful.

USB support

The USB subdirectory contains the modified Microchip USB libraries as well as example programs. USB programs require several additional files to operate (which are in the USB subdirectory), some of which will require modification for your particular application. See the text file in the USB subdirectory for more information on the USB commands.

USB communications is much more complicated than synchronous (Shiftin and Shiftout) and asynchronous (Serin, Serout and so forth) communications. There is much more to know about USB operation that can possibly be described here. The USB information on the Microchip web site needs to be studied. Also, the book "USB Complete" by Jan Axelson may be helpful.

Picbasic Pro Statement Reference

5.76. WHILE..WEND

WHILE Condition

Statement...

WEND

Repeatedly execute *Statements* **WHILE** *Condition* is true. When the *Condition* is no longer true, execution continues at the statement following the **WEND**. *Condition* may be any comparison expression.

```
i = 1
```

```
WHILE i <= 10
```

```
    Serout 0,N2400,["No:",#,13,10]
```

```
    i = i + 1
```

```
WEND
```

Picbasic Pro Statement Reference

5.77. WRITE

WRITE *Address, Value*

Write *Value* to the on-chip EEPROM at the specified *Address*. This instruction may only be used with a PICmicro that has an on-chip EEPROM data area such as the PIC16F84, PIC16C84 and the PIC16F87x series.

WRITE is used to set the values of the on-chip EEPROM at runtime. To set the values of the on-chip EEPROM at programming-time, use the **DATA** or **EEPROM** statement.

Each **WRITE** is self-timed and takes about 10 milliseconds to execute on a PICmicro.

If interrupts are used in a program, they must be turned off (masked, not **DISABLED**) before executing a **WRITE**, and turned back on (if desired) after the write instruction is complete. An interrupt occurring during a **WRITE** may cause it to fail.

WRITE will not work on devices with on-chip I2C interfaced serial EEPROM like the 12CE67x and 16CE62x parts. Use the **I2CWRITE** instruction instead.

WRITE 5,B0 ‘ Send value in B0 to EEPROM location 5

Picbasic Pro Statement Reference

5.78. WRITECODE

WRITECODE *Address, Value*

Write the word-sized *Value* to the code space at location *Address*.

The PIC16F87x devices allow code to be read and written at run-time. While writing self-modifying code can be a dangerous technique, it does allow non-volatile data storage above 64 - 256 bytes. One must be very careful not to write over active program memory. The listing file may be examined to determine program addresses.

If interrupts are used in a program, they must be turned off (masked, not **DISABLED**) before executing a **WRITECODE**, and turned back on (if desired) after the write instruction is complete. An interrupt occurring during a **WRITECODE** may cause it to fail.

WRITECODE 100,W ' Send value in W to code space location 100

Picbasic Pro Statement Reference

5.79. XIN

```
XIN DataPin,ZeroPin,{Timeout,Label,}[Var{, . . .}]
```

Receive X-10 data and store the House Code and Key Code in *Var*.

XIN is used to receive information from X-10 devices that can send such information. X-10 modules are available from a wide variety of sources under several trade names. An interface is required to connect the microcontroller to the AC power line. The TW-523 for two-way X-10 communications is required by **XIN**. This device contains the power line interface and isolates the microcontroller from the AC line. Since the X-10 format is patented, this interface also covers the license fees.

DataPin is the automatically made an input to receive data from the X-10 interface.

ZeroPin is automatically made an input to received the zero crossing timing from the X-10 interface. Both pins should be pulled up to 5 volts with 4.7K resistors. *DataPin* and *ZeroPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

An optional *Timeout* and *Label* may be included to allow the program to continue if X-10 data is not received within a certain amount of time. *Timeout* is specified in AC power line half-cycles (approximately 8.33 milliseconds).

XIN only processes data at each zero crossing of the AC power line as received on

ZeroPin. If there are no transitions on this line, **XIN** will effectively wait forever.

If *Var* is word-sized, each House Code received is stored in the upper byte of the word. Each received Key Code is stored in the lower byte of the word. If *Var* is a byte, only the Key Code is stored.

The House Code is a number between 0 and 15 that corresponds to the House Code set on the X-10 module A through P.

The Key Code can be either the number of a specific X-10 module or the function that is to be performed by a module. In normal practice, first a command specifying the X-10 module number is sent, followed by a command specifying the function desired. Some functions operate on all modules at once so the module number is unnecessary. Hopefully, later examples will clarify things. Key Code numbers 0-15 correspond to module numbers 1-16. **XOUT** below lists the functions as well as the wiring information.

```
housekey var      word
```

```
      ' Get X-10 data
loop:  XIN PORTA.2,PORTA.0,[housekey]

      ' Display X-10 data on LCD
      Lcdout $fe,1,"House=#",#housekey.byte1, "Key=#",#housekey.byte0

      Goto loop ' Do it forever

      ' Check for X-10 data, go to nodata if none
      XIN PORTA.2,PORTA.0,1,nodata,[housekey]
```

Picbasic Pro Statement Reference

5.80. XOUT

XOUT *DataPin*, *ZeroPin*, [*HouseCode**KeyCode*{\Repeat}{, ...}]

Send *HouseCode* followed by *KeyCode*, *Repeat* number of times in X-10 format. If the optional *Repeat* is left off, 2 times (the minimum) is assumed. *Repeat* is usually reserved for use with the Bright and Dim commands.

XOUT is used to send control information to X-10 modules. These modules are available from a wide variety of sources under several trade names. An interface is required to connect the microcontroller to the AC power line. Either the PL-513 for send only, or the TW-523 for two-way X-10 communications are required. These devices contain the power line interface and isolate the microcontroller from the AC line. Since the X-10 format is patented, these interfaces also cover the license fees.

DataPin is the automatically made an output to send data to the X-10 interface. *ZeroPin* is automatically made an input to received the zero crossing timing from the X-10 interface. It should be pulled up to 5 volts with a 4.7K resistor. *DataPin* and *ZeroPin* may be a constant, 0-15, or a variable that contains a number 0-15 (e.g. B0) or a pin name (e.g. PORTA.0).

XOUT only processes data at each zero crossing of the AC power line as received on *ZeroPin*. If there are no transitions on this line, **XOUT** will effectively wait forever.

HouseCode is a number between 0 and 15 that corresponds to the House Code set on the X-10 module A through P. The proper *HouseCode* must be sent as part of each command.

The *KeyCode* can be either the number of a specific X-10 module or the function that is to be performed by a module. In normal practice, first a command specifying the X-10 module number is sent, followed by a command specifying the function desired. Some functions operate on all modules at once so the module number is unnecessary. Hopefully, later examples will clarify things. *KeyCode* numbers 0-15 correspond to module numbers 1-16.

The *KeyCode* (function) names (e.g. **unitOn**) are defined in the file `MODEDEFS.BAS`. To use them, add the line:

```
Include "modedefs.bas"
```

to the top of the PicBasic Pro program. `BS1DEFS.BAS` and `BS2DEFS.BAS` already includes `MODEDEFS.BAS`. Do not include it again if one of these files is already included. The *KeyCode* numbers may be used without including this file.

Table 32 XIN/XOUT commands

<i>KeyCode</i>	<i>KeyCode No.</i>	<i>Operation</i>
unitOn	%10010	Turn module on
unitOff	%11010	Turn module off
unitsOff	%11100	Turn all modules off
lightsOn	%10100	Turn all light modules on
lightsOff	%10000	Turn all light modules off
bright	%10110	Brighten light module
dim	%11110	Dim light module

Wiring to the X-10 interfaces requires 4 connections. Output from the X-10 interface (zero crossing and receive data) are open-collector and require a pull up resistor of around 4.7K to 5 volts. Wiring tables for each interface is shown below:

Picbasic Pro Statement Reference

Table 33 PL-513 Wiring (X10)

Wire No.	Wire Color	Connection
1	Black	Zero crossing output
2	Red	Zero crossing common
3	Green	X-10 transmit common
4	Yellow	X-10 transmit input

Table 34 TW-523 Wiring (X10)

Wire No.	Wire Color	Connection
1	Black	Zero crossing output
2	Red	Common
3	Green	X-10 receive output
4	Yellow	X-10 transmit input

```
house  var    byte
unit   var    byte
```

```
Include "modedefs.bas"
```

```
house = 0          ' Set house to 0 (A)
```

```
unit = 8           ' Set unit to 8 (9)
```

```
' Turn on unit 8 in house 0
```

```
XOUT PORTA.1,PORTA.0,[house\unit,house\unitOn]
```

```
' Turn off all the lights in house 0
```

```
XOUT PORTA.1,PORTA.0,[house\lightsOff]
```

```
' Blink light 0 on and off every 10 seconds
```

```
XOUT PORTA.1,PORTA.0,[house\0]
```

```
loop:  XOUT PORTA.1,PORTA.0,[house\unitOn]
```

```
Pause 10000          ' Wait 10 seconds
```

```
XOUT PORTA.1,PORTA.0,[house\unitOff]
```

```
Pause 10000          ' Wait 10 seconds
```

```
Goto loop
```

Picbasic Pro Program Structure

6. Structure of a Compiled Program

PBP is designed to be easy to use. Programs can be compiled and run with little thought to PBP's internal workings. Some people, however, only have confidence in a product when they understand its internal workings. Others are just plain curious.

This section is for them. It describes the files used and output generated by PBP and gives some idea of exactly what is going on.

6.1. Target Specific Headers

Three target specific header files are used when a program is compiled. One is used by PBP, the other two are included for use by the assembler.

A file with the name of the microcontroller followed by the extension `.BAS` contains chip specific information needed by PBP. This includes the memory profile of the chip, which library it uses, and includes for the definition of the variables it needs. For the PIC16F84, the default microcontroller, the file is named `16F84.BAS`.

A file with the name of the microcontroller followed by the extension `.INC` is included in the generated `.ASM` file to give the assembler information about the chip, including the default configuration parameters (oscillator mode, Watchdog Timer setting, etc.). For the PIC16F84, the file is named `16F84.INC`.

Finally, the assembler has its own include file that defines the addresses of the microcontroller registers. This file is usually named something on the order of `M16F84.INC`.

6.2. The Library Files

PBP includes a set of library files that contain all of the code and definition files for a particular group of microcontrollers. In the case of 14-bit core PICmicros, these files start with the name `PBPPIC14`.

`PBPPIC14.LIB` contains all of the assembly language subroutines used by the compiler.
`PBPPIC14.MAC` contains all of the macros that call these subroutines. Most PicBasic Pro commands consist of a macro and an associated library subroutine.

`PBPPIC14.RAM` contains the `VAR` statements that allocate the memory needed by the library.

`PIC14EXT.BAS` contains the external definitions that tells PBP all of the 14-bit core PICmicro register names.

6.3. PBP Generated Code

A PicBasic Pro compiled program is built in several stages. First PBP creates the `.ASM` file. It then builds a custom `.MAC` file that contains only the macros from the macro library that are used in the `.ASM` file. If everything is error free up to this point, it spawns the assembler.

The assembler generates its own set of files. These include the `.HEX` final output file and possibly listing and debugging files.

Picbasic Pro Program Structure

6.4. .ASM File Structure

The `.ASM` file has a very specific structure. Things must be done in a particular order for everything to work out properly.

The first item placed in the file is an equate defining which assembler is to be used, followed by an `INCLUDE` to tell the assembler which microprocessor is the target and give it some basic information, such as the configuration data.

Next, all of the variable allocations and aliasing is listed. EEPROM initialization is next, if called for.

An `INCLUDE` for the macro file is then placed in the file, followed by an `INCLUDE` for the library subroutines.

Finally, the actual program code is incorporated. This program code is simply a list of macros that were generated from the PicBasic Pro lines.

Picbasic Pro Other Considerations

7. Other PicBasic Pro Considerations

7.1. How Fast is Fast Enough?

By default, the PicBasic Pro Compiler generates programs intended to be run on a PICmicro with a 4MHz crystal or ceramic resonator. All of the time-sensitive instructions assume a 1 microsecond instruction time for their delays. This allows a **PAUSE 1000 1000**, for example, to wait 1 second and the **SERIN** and **SEROUT** command=s baud rates to be accurate.

There are times, however, when it would be useful to run the PICmicro at a frequency other than 4MHz. Even though the compiled programs move along at a pretty good clip, it might be nice to run them even faster. Or maybe it is desirable to do serial input or output at 19,200 baud rather than the current top speed of 9600 baud.

PicBasic Pro programs may be run at clock frequencies other than 4MHz in a couple of different ways. The first is to simply use an oscillator other than 4MHz and don=t tell PBP. This can be a useful technique if you pay attention to what happens to the time dependent instructions.

If you wish to run the serial bus at 19,200 as described above, you would simply clock the microcontroller with an 8MHz crystal rather than a 4MHz crystal. This, in effect, makes everything run twice as fast, including the **SERIN** and **SEROUT** commands. If you tell **SERIN** or **SEROUT** to run at 9600 baud, the doubling of the crystal speed will double the actual baud rate to 19,200 baud.

However, keep in mind commands such as **PAUSE** and **SOUND** will also run twice as fast. The **PAUSE 1000 1000** mentioned above would only wait .5 seconds with an 8MHz crystal before allowing program execution to continue.

The other technique is to use a different oscillator frequency and tell PBP of your intentions. This is done through the use of a **DEFINE**. **DEFINE**, as demonstrated in the **LCDOUT** command in a previous section, is used to tell PBP to use something other than its defaults.

Normally, PBP defaults to using a 4MHz oscillator. Adding the statement:

```
DEFINE OSC 8
```

near the beginning of the PicBasic Pro program tells PBP to assume an 8MHz oscillator will be used instead.

Picbasic Pro Other Considerations

The acceptable oscillator definitions are:

Table 35 Oscillator definitions

<i>OSC</i>	<i>Minimum delay</i>
3 (3.58)	20us
4	24us
8	12us
10	8us
12	7us
16	5us
20	3us
25*	
32*	2us
33*	2us
40**	2us

* PIC17Cxxx and PIC18Cxxx only.

** PIC18Cxxx only.

Telling PBP the oscillator frequency allows it to compensate and produce the correct timing for **COUNT**, **DEBUG**, **DTMFOUT**, **FREQOUT**, **HSERIN**, **HSEROUT**, **I2CREAD**, **I2CWRITE**, **LCDOUT**, **PAUSE**, **PAUSEUS**, **SERIN**, **SERIN2**, **SEROUT**, **SEROUT2**, **SHIFIN**, **SHIFOUT**, **SOUND**, **XIN** and **XOUT**.

Changing the oscillator frequency may also be used to enhance the resolution of the **PULSIN**, **PULSOUT** and **RCTIME** instructions. At 4MHz these instructions operate with a 10 microsecond resolution. If a 20MHz crystal is used, the resolution is increased 5 times to 2 microseconds. There is a tradeoff however. The pulse width is still measured to a 16-bit word variable. With a 2 microsecond resolution, the maximum measurable pulse width would be 131,070 microseconds.

Going the other direction and running with a 32.768KHz oscillator is problematic. It may be desirable to attempt this for reduced power consumption reasons and it will work to some extent. The **SERIN** and **SEROUT** commands will be unusable and the Watchdog Timer may cause the program to restart periodically. Experiment to find out if your particular application is possible at this clock speed. It doesn't hurt to try.

7.2. Configuration Settings

As mentioned earlier, the default configuration settings for a particular device is set in the `.INC` file with the same name as the device, e.g. `16F84.INC`. These settings can be changed at the time the device is physically programmed.

The oscillator defaults to XT on most devices. This is the setting for the default 4MHz oscillator. If a faster oscillator is used, this setting must be changed to HS. Devices with internal oscillators default to INTRC.

The Watchdog Timer is enabled by PBP. It is used, along with the TMR0 prescaler, to support the **NAP** and **SLEEP** instructions. If neither of the instructions are used in a program, the Watchdog Timer may be disabled and the prescaler used for something else.

Code Protect defaults to off but may be set to on when the device is physically programmed. Do not code protect a windowed device.

See the Microchip data sheet for the particular device for the configuration data specific to that part.

Picbasic Pro Other Considerations

7.3. RAM Usage

In general it is not necessary to know how RAM is allocated by PBP in the microcontroller. PBP takes care of all the details so the programmer doesn't have to. However there are times when this knowledge could be useful.

Variables are stored in the PICmicro's RAM registers. The first available RAM location is \$0C for the PIC16F84 and some of the smaller PICmicros, and \$20 for the PIC16C74 and other larger PICmicros. Refer to the Microchip PICmicro data books for the actual location of the start of the RAM registers for a given microcontroller.

The variables are assigned to RAM sequentially in a particular order. The order is word arrays first (if any), followed by byte and bit arrays. Then space is allocated for words, bytes and finally individual bits. Bits are packed into bytes as possible. This order makes the best use of available RAM. (For PIC18Cxxx devices, arrays are allocated last.)

Arrays must fit into a single bank on most PICmicros. They may not cross a bank boundary. This effectively limits the length of an individual array. See the previous section on arrays for these limits.

You can suggest to PBP a particular bank to place the variable in:

```
penny VAR WORD BANK0
nickel VAR BYTE BANK1
```

If specific bank requests are made, those are handled first. If there is not enough room in a requested bank, the first available space is used and a warning is issued.

You can even set specific addresses for variables. In most cases, it is better to let PBP handle the memory mapping for you. But in some cases, such as storage of the W register in an interrupt handler, it is necessary to define a fixed address. This may be done in a similar manner to bank selection:

```
w_store VAR BYTE $20
```

Several system variables, using about 24 bytes of RAM, are automatically allocated by the compiler for use by library subroutines. These variables are allocated in the file `PBPPIC14.RAM` and must be in bank 0 (or bank A on 18Cxxx devices).

User variables are prepended with an underscore (`_`) while system variables have no underscore so that they do not interfere with each other.

```
R0 VAR WORD SYSTEM
```

BASIC Stamp variables B0 - B25 and W0 - W12 are not automatically allocated. It is best to create your own variables using the `VAR` instruction. However if you want these variables to be created for you, simply include the appropriate file, `BS1DEFS.BAS` or `BS2DEFS.BAS`, at the beginning of the PicBasic Pro program. These variables allocate space separate and apart from any other variables you may later create. This is different than the BS2 where using the canned variables and user created variables can get you into hot water.

Additional temporary variables may be generated automatically by the compiler to help it sort out equations. A listing of these variables, as well as the entire memory map, may be seen in the generated `.ASM` or `.LST` file.

If there is not enough RAM memory available for the variables, an unable to fit variable in memory error message will be issued.

7.4. Reserved Words

Reserved words are simply that - words that are reserved for use by the compiler and may not be defined as either variable names or labels. These reserved words may be the names of commands, pseudo-ops, variable types or the names of the PICmicro registers.

The pseudo-ops, variable types and commands keywords are listed in their appropriate sections. The names of the PICmicro registers are defined in the file `PIC14EXT.BAS`. If the

Picbasic Pro Other Considerations

files `BS1DEFS.BAS`, `BS2DEFS.BAS` or `MODEDEFS.BAS` are included, the definitions inside essentially become reserved words and may not be redefined.

7.5. Life After 2K

Yes, there is life after 2K using the PicBasic Pro Compiler.

PICmicros have a segmented code space. PICmicro instructions in 14-bit core parts such as Call and Goto only have enough bits within them to address 2K of program space. To get to code outside the 2K boundary, the PCLATH register must be set before each Call or Goto. PBP automatically sets these PCLATH bits for you. There are a few restrictions imposed, however. The PicBasic Pro library must fit entirely into page 0 of code space. Normally this is not an issue as the library is the first thing in a PicBasic Pro program and the entire library is smaller than 2K. However, attention must be paid to this issue if additional libraries are used.

Assembly language interrupt handlers must also fit into page 0 of code space. Putting them at the beginning of the PicBasic Pro program should make this work. See the upcoming section on assembly language for more information.

The addition of instructions to set the PCLATH bits does add overhead to the produced code. PBP will set the PCLATH bits for any PICmicro code that crosses a 2K boundary or for any forward references on PICmicros with more than 2K of code space.

There are specific PicBasic Pro instructions to assist with the 2K issues.

BRANCHL was created to allow branching to labels that may be on the other side of a 2K boundary. If the PICmicro has 2K or less of program space, **BRANCH** should be used as it takes up less space than **BRANCHL**. If the microcontroller has more than 2K of code space, and you cannot be certain that **BRANCH** will always act within the same page, use **BRANCHL**. The assembler may issue a warning that a page boundary has been crossed. This is normal and is there to suggest that you check for any **BRANCHes** that may cross a page boundary.

Assembly Language Programming

8. Assembly Language Programming

Assembly language routines can be a useful adjunct to a PicBasic Pro Compiler program. While in general most tasks can be done completely in PicBasic Pro, there are times when it might be necessary to do a particular task faster, or using a smaller amount of code space, or just differently than the compiler does it. At those times it is useful to have the capabilities of an in-line assembler.

It can be beneficial to write most of a program quickly using the PicBasic Pro language and then sprinkle in a few lines of assembly code to increase the functionality. This additional code may be inserted directly into the PBP program or included as another file.

8.1. Two Assemblers - No Waiting

Upon execution, PBP first compiles the program into assembly language and then automatically launches an assembler. This converts the assembler output into the final .HEX file which can be programmed into a microcontroller.

Two different assemblers may be used with PBP: PM, our PICmicro Macro Assembler, and MPASM, Microchip's assembler. PM is included with the compiler while MPASM must be obtained directly from Microchip via their web site or is included with their PICmicro programmers.

There are benefits and drawbacks to using each assembler. PM is handy because it is included as part of PBP. It is also much faster than MPASM and can assemble much larger programs in DOS. PM includes an 8051-style instruction set that is more intuitive than the Microchip mnemonics. For complete information on the PICmicro Macro Assembler, see the PM.TXT file on disk.

MPASM, on the other hand, has the capability of creating a .COD file. This file contains additional information that can be very useful with simulators and emulators. MPASM is also more compatible with the wide variety of assembly language examples found on the web and in Microchip's data books.

PBP defaults to using PM. To use MPASM with PBP, simply copy all of the MPASM files into their own subdirectory, perhaps named MPASM. This subdirectory must also be in the DOS PATH.

MPASM may be used with PBP in two ways. If the command line option "-ampasm" is used, MPASM will be launched following compilation to complete the process. MPASM will display its own screen with its progress.

```
PBP -ampasm filename
```

Alternatively, the command line option "-amp" will launch MPASM in quiet mode and only display any errors. However, the launcher consumes additional memory that is therefore not available to MPASM.

```
PBP -amp filename
```

For maximum memory availability to MPASM, the command line option "-ampasm" should be used or the Windows version of MPASM should be used. In any case, MPASM is not included with PBP and must be obtained from Microchip.

Assembly Language Programming

8.2. Programming in Assembly Language

PBP programs may contain a single line of assembly language preceded by an `Aat@` symbol (`@`), or one or more lines of assembly code preceded by the `ASM` keyword and ended by the keyword and ended by the `ENDASM` keyword. Both keywords appear on their lines alone.

```
@      bsf      PORTA,0
```

Asm

```
      bsf      STATUS,RP0  
      bcf      TRISA,0  
      bcf      STATUS,RP0
```

Endasm

The lines of assembly are copied verbatim into the assembly output file. This allows the PBP program to use all of the facilities of PM, the PICmicro Macro Assembler. This also, however, requires that the programmer have some familiarity with the PBP libraries. PBP's notational conventions are similar to other commercial compilers and should come as no shock to programmers experienced enough to attempt in-line assembly.

All identifier names defined in a PBP program are similarly defined in assembly, but with the name preceded with an underscore (`_`). This allows access to user variables, constants, and even labeled locations, in assembly.

Thus, any name defined in assembly starting with an underscore has the possibility of conflicting with a PBP generated symbol. If conflict is avoided, can these underscored assembly values be accessed from PBP? No. Remember, the underscored names generated by PBP are only shadows of the actual information defined in the compiler. Since in-line assembly is copied directly to the output file and not processed by the compiler, the compiler not only lacks any type or value information about assembly symbols, it is completely unaware that they exist. If variables are to be shared between assembly and PBP, you must define the variables in PBP.

Just as underscored symbols have possible conflicts, so do symbols not starting with underscores. The problem is internal library identifiers. Luckily, most library identifiers contain a '?' or make reference to one of the working registers (such as `RP0`). Avoiding such names should reduce problems. If you should have a name collision, the compiler will report the duplicate definitions as an error.

In assembly language the comment designator changes from the single quote (`>`) in PicBasic Pro to a semicolon (`;`).

```
' PicBasic Pro comment
```

```
; Assembly language comment
```

8.3. Placement of In-line Assembly

PBP statements execute in order of appearance in the source. The organization of the code is as follows: Starting at location 0, the reset vector, PBP inserts some startup code followed by a jump to `INIT`. Next, the called-for library subroutines are stuffed in. At the end of the library is `INIT`, where any additional initialization is completed. Finally, at the label `MAIN`, the compiled PicBasic Pro statement code is added.

The first executable line that appears in the PicBasic Pro source is where the program starts execution. That statement literally appears in memory right behind the controller's startup and library code, right after the `MAIN` label.

The tendency of programmers is to place their own library functions written using the in-line assembler either before or after their code. In light of the above explanation, this could create some obvious problems. If they appear early in the program, the assembly routines execute prior to any PBP instructions (some programmers will invariably exploit this feature). If they appear at the tail of the program, execution which "falls off the end" of the PBP statements may mysteriously find themselves unintentionally executing assembly routines.

Assembly Language Programming

There are a couple of deciding factors as to where might be the best place to insert assembly language subroutines. If the entire program fits into 2K (one code page), place your assembly routines after your PBP code. If you need to terminate your program, explicitly place an **END** or **STOP** statement at the end of your code rather than floating off into space.

If the program is longer than 2K, it could make more sense to put the assembly language routines at the beginning of the PBP program. This should ensure them of being in the first code page so that you know where to find them. This is the way assembly language interrupt routines should be handled.

If the routines are placed at the front, you must include a **GOTO** (or **JMP**) around the code to the first executable PBP statement. See the section on interrupts for an example of this.

The actual code for the assembly language routines may be included in your program or in a separate file. If a routine is used by only one particular PicBasic Pro program, it would make sense to include the assembler code within the PBP source file. This routine can then be accessed using the **CALL** command.

If it is used by several different PBP programs, a separate file containing the assembly routines can simply be included at the appropriate place in the PicBasic Pro source:

```
Asm
        Include "myasm.inc"
Endasm
```

8.4. Another Assembly Issue

PICmicro registers are banked. PBP keeps track of which register bank it is pointing to at all times. It knows if it is pointing to a TRIS register, for example, it needs to change the bank select bits before it can access a PORT.

It also knows to reset the bank select bits to 0 before making a Call or a Jump. It does this because it can't know the state of the bank select bits at the new location. So anytime there is a change of locale or a label that can be called or jumped to, the bank select bits are zeroed.

It also resets the bank select bits before each **ASM** and the **@** assembler shortcut. Once again, the assembler routine won't know the current state of the bits so they are set to a known state. The assembler code must be sure to reset the bank select bits before it exits, if it has altered them.

Interrupts

9. Interrupts

Interrupts can be a scary and useful way to make your program really difficult to debug.

Interrupts are triggered by hardware events, either an I/O pin changing state or a timer timing out and so forth. If enabled (which by default they aren't), an interrupt causes the processor to stop whatever it is doing and jump to a specific routine in the microcontroller called an interrupt handler.

Interrupts are not for the faint of heart. They can be very tricky to implement properly, but at the same time they can provide very useful functions. For example, an interrupt could be used to buffer serial input data behind the scenes while the main PicBasic Pro program is off doing something else. (This particular usage would require a microcontroller with a hardware serial port.)

There are many ways to avoid using interrupts. Quickly polling a pin or register bit instead is usually fast enough to get the job done. Or you can check the value of an interrupt flag without actually enabling interrupts.

However, if you just gotta do it, here are some hints on how to go about it.

The PicBasic Pro Compiler has two different mechanisms to handle interrupts. The first is simply to write the interrupt handler in assembler and tack it onto the front of a PBP program. The second method is to use the PicBasic Pro statement **ON INTERRUPT**. Each method will be covered separately, after we talk about interrupts in general.

9.1. Interrupts in General

When an interrupt occurs, the PICmicro stores the address of the next instruction it was supposed to execute on the stack and jumps to location 4. The first thing this means is that you need an extra location on the hardware stack, which is only 8 deep to begin with.

The PicBasic Pro library routines can use up to 4 stack locations themselves. The remaining 4 are reserved for **CALLs** and nested BASIC **GOSUBs**. You must make sure that your **GOSUBs** are only nested 3 deep at most with no **CALLs** within them in order to have a stack location available for the return address. If your interrupt handler uses the stack (by doing a Call or **GOSUB** itself for example), you'll need to have additional stack space available.

Once you have dealt with the stack issues, you need to enable the appropriate interrupts. This usually means setting the INTCON register. Set the necessary enable bits along with Global Interrupt Enable. For example:

```
INTCON = %10010000
```

enables the interrupt for RB0/INT. Depending on the actual interrupt desired, you may also need to set the PIE register.

Refer to the Microchip PICmicro data books for additional information on how to use interrupts. They give examples of storing processor context as well as all the necessary information to enable a particular interrupt. This data is invaluable to your success. Finally, select the best technique with which to handle your particular interrupts.

Interrupts

9.2. Interrupts in BASIC

The easiest way to write an interrupt handler is to write it in PicBasic Pro in conjunction with the **ON INTERRUPT** statement. **ON INTERRUPT** tells PBP to activate its internal interrupt handling and to jump to your BASIC interrupt handler as soon as it can after receiving an interrupt. Which brings us the first issue.

Using **ON INTERRUPT**, when an interrupt occurs PBP simply flags the event and immediately goes back to what it was doing. It does not immediately vector to your interrupt handler. Since PBP statements are not re-entrant (PBP must finish the statement that is being executed before it can begin a new one) there could be considerable delay (latency) before the interrupt is handled.

As an example, lets say that the PicBasic Pro program just started execution of a `Pause 10000` when an interrupt occurs. PBP will flag the interrupt and continue with the **PAUSE**. It could be up to 10 seconds later before the interrupt handler is executed. If it is buffering characters from a serial port, many characters will be missed.

To minimize the problem, use only statements that don't take very long to execute. For example, instead of `Pause 10000`, use `Pause 1` in a long **FOR . .NEXT** loop. This will allow PBP to complete each statement more quickly and handle any pending interrupts.

If interrupt processing needs to occur more quickly than can be provided by **ON INTERRUPT**, interrupts in assembly language should be used.

Exactly what happens when **ON INTERRUPT** is used is this: A short interrupt handler is placed at location 4 in the PICmicro. This interrupt handler is simply a Return. What this does is send the program back to what it was doing before the interrupt occurred. It doesn't require any processor context saving. What it doesn't do is re-enable Global Interrupts as happens using an `Retfie`.

A Call to a short subroutine is placed after each statement in the PicBasic Pro program once an **ON INTERRUPT** is encountered. This short subroutine checks the state of the Global Interrupt Enable bit. If it is off, an interrupt is pending so it vectors to the users interrupt handler. If it is still set, the program continues with the next BASIC statement, after which, the GIE bit is checked again, and so forth.

When the **RESUME** statement is encountered at the end of the BASIC interrupt handler, it sets the GIE bit to re-enable interrupts and returns to where the program was before the interrupt occurred. If **RESUME** is given a label to jump to, execution will continue at that location instead. All previous return addresses will be lost in this case.

DISABLE stops PBP from inserting the Call to the interrupt checker after each statement. This allows sections of code to execute without the possibility of being interrupted. **ENABLE** allows the insertion to continue.

A **DISABLE** should be placed before the interrupt handler so that it will not keep getting restarted every time the GIE bit is checked.

If it is desired to turn off interrupts for some reason after **ON INTERRUPT** is encountered, you must not turn off the GIE bit. Turning off this bit tells PBP an interrupt has happened and it will execute the interrupt handler forever. Instead set:

```
INTCON = $80
```

This disables all the individual interrupts but leaves the Global Interrupt Enable bit set.

One final note about interrupts in BASIC: If the program uses the form:

```
loop: Goto loop
```

and expects to be interrupted, it isn't going to happen. Keep in mind the interrupt flag is checked after each instruction. There really isn't a place for the check after a **GOTO**. It immediately jumps to the loop with no interrupt check. Some other statement must be placed in the loop for the interrupt check to happen.

Interrupts

9.3. Interrupts in Assembler

Interrupts in assembly language are a little trickier.

Since you have no idea of what the processor was doing when it was interrupted, you have no idea of the state of the W register, the STATUS flags, PCLATH or even what register page you are pointing to. If you need to alter any of these, and you probably will, you must save the current values so that you can restore them before allowing the processor to go back to what it was doing before it was so rudely interrupted. This is called saving and restoring the processor context.

If the processor context, upon return from the interrupt, is not left exactly the way you found it, all kinds of subtle bugs and even major system crashes can and will occur.

This of course means that you cannot even safely use the compiler's internal variables for storing the processor context. You cannot tell which variables are in use by the library routines at any given time.

You should create variables in the PicBasic Pro program for the express purpose of saving W, the STATUS register and any other register that may need to be altered by the interrupt handler. These variables should not be otherwise used in the BASIC program.

While it seems a simple matter to save W in any RAM register, it is actually somewhat more complicated. The problem occurs in that you have no way of knowing what register bank you are pointing to when the interrupt happens. If you have reserved a location in Bank0 and the current register pointers are set to Bank1, for example, you could overwrite an unintended location. Therefore you must reserve a RAM register location in each bank of the device at the same offset.

As an example, let's choose the 16C74(A). It has 2 banks of RAM registers starting at \$20 and \$A0 respectively. To be safe, we need to reserve the same location in each bank. In this case we will choose the first location in each bank. A special construct has been added to the **VAR** command to allow this:

```
wsave var byte $20 system
wsave1 var byte $a0 system
```

This instructs the compiler to place the variable at a particular location in RAM. In this manner, if the save of W "punches through" to another bank, it will not corrupt other data. The interrupt routine should be as short and fast as you can possibly make it. If it takes too long to execute, the Watchdog Timer could timeout and really make a mess of things. The routine should end with an **Retfie** instruction to return from the interrupt and allow the processor to pick up where it left off in your PicBasic Pro program.

The best place to put the assembly language interrupt handler is probably at the very beginning of your PicBasic Pro program. This should ensure that it is in the first 2K to minimize boundary issues. A **GOTO** needs to be inserted before it to make sure it won't be executed when the program starts. See the example below for a demonstration of this.

If the PICmicro has more than 2K of code space, an interrupt stub is automatically added that saves the W, STATUS and PCLATH registers into the variables **wsave**, **ssave** and **psave**, before going to your interrupt handler. Storage for these variables must be allocated in the BASIC program:

```
wsave var      byte $20 system
wsave1 var     byte $a0 system      ' If device has RAM in bank1
wsave2 var     byte $120 system    ' If device has RAM in bank2
wsave3 var     byte $1a0 system    ' If device has RAM in bank3
ssave varbyte bank0 system
psave var      byte bank0 system
```

You must restore these registers at the end of your assembler interrupt handler. If the PICmicro has 2K or less of code space, the registers are not saved. Your interrupt handler must save and restore any used registers.

Finally, you need to tell PBP that you are using an assembly language interrupt handler and where to find it. This is accomplished with a **DEFINE**:

Interrupts

```
DEFINE INTHAND Label
```

Label is the beginning of your interrupt routine. PBP will place a jump to this *Label* at location 4 in the PICmicro.

```
' Assembly language interrupt example
```

```
    led        var        PORTB.1
```

```
    wsave varbyte $20 system
```

```
    ssave var byte bank0 system
```

```
    psave var byte bank0 system
```

```
Goto start ' Skip around interrupt handler
```

```
' Define interrupt handler
```

```
define INTHAND myint
```

```
' Assembly language interrupt handler
```

```
asm
```

```
; Save W, STATUS and PCLATH registers
```

```
myint    movwf    wsave
          swapf   STATUS, W
          clrf    STATUS
          movwf   ssave
          movf    PCLATH, W
          movwf   psave
```

```
; Insert interrupt code here
```

```
; Save and restore FSR if used
```

```
        bsf      _led      ; Turn on LED (for example)
```

```
; Restore PCLATH, STATUS and W registers
```

```
        movf    psave, W
        movwf   PCLATH
        swapf   ssave, W
        movwf   STATUS
        swapf   wsave, F
        swapf   wsave, W
        retfie
```

```
endasm
```


Interrupts

```
' PicBasic Pro program starts here
start: Low led      ' Turn LED off

' Enable interrupt on PORTB.0
      INTCON = %10010000
loop:  Goto loop ' Wait here till interrupted
```

Appendix A

Appendix A

Summary of Microchip Assembly Instruction Set

ADDLW	k
ADDWF	f,d
ANDLW	k
ANDWF	f,d
BCF	f,b
BSF	f,b
BTFSC	f,b
BTFSS	f,b
CALL	k
CLRF	f
CLRW	
CLRWDI	
COMF	f,d
DECF	f,d
DECFSZ	f,d
GOTO	k
INCF	f,d
INCFSZ	f,d
IORLW	k
IORWF	f,d
MOVF	f,d
MOVLW	k
MOVWF	f
NOP	
RETFIE	
RETLW	k
RETURN	
RLF	f,d
RRF	f,d
SLEEP	
SUBLW	k
SUBWF	f,d
SWAPF	f,d
XORLW	k
XORWF	f,d

b - bit address

Appendix A

d - destination; 0 = w, 1 = f

f - register file address

k - literal constant

PBP V2.4

PBP Version 2.4

Version Information

Version 2.3 of the PicBasic Pro Compiler adds support for the 16-bit core PIC18Cxxx devices.

18Cxxx Information

The 16-bit core 18Cxxx PICmicros may now be used with the PicBasic Pro Compiler. MPASM or MPASMWIN must be used as the assembler as PM does not support the 18Cxxx devices. Simply specify the assembler and device type on the command line using the -a and -p options:

```
PBP -ampasm -p18c452 filename
```

Early PIC18Cxxx devices do not include the LFSR assembler op-code. By default, PBP will not use the LFSR op-code but will use a longer method instead. If the 18Cxxx device does have the LFSR op-code, a Define may be added to the BASIC program to tell PBP to use it:

```
Define USE_LFSR 1
```

17Cxxx Information

The 16-bit core 17Cxxx PICmicros may now be used with the PicBasic Pro Compiler. Simply specify the device type on the command line using the -p option:

```
PBP -p17c752 filename
```

The 17Cxxx device TRIS registers are actually named DDR (data direction register). In place of using TRIS to set the input/output direction, use DDR:

PBP V2.4

```
DDRB = 0      ' Set PORTB to all output
```

There is no data direction register for PORTA.

New I2CRead and I2CWrite STR Modifier

A new modifier, STR, has been added to the I2CRead and I2CWrite statements. This allows arrays to be read and written to a single page in a SEEPROM. The data must fit in a single SEEPROM page. The page size is dependent on the particular SEEPROM device. The STR modifier is followed by the byte- or word-sized array name, which is followed by a backslash (\) and count (the number of array elements to be read or written):

```
I2CRead dpin, cpin, control, address, [STR arrayvar\cnt]
I2CWrite dpin, cpin, control, address, [STR arrayvar\cnt]
```

Any number of data items, separated by commas, may be read or written. If a word-sized array is read or written, the low order byte will be read and written first. This is the opposite order in which words are usually read and written to an I2C device.

```
a  var  byte[8]
i  var  byte
```

```
For i = 0 To 7
  a[i] = i + 10
Next i
I2CWrite PORTC.4, PORTC.3, $a0, 0, [STR a\8]
Pause 10
```

New Lcdin Instruction

LCDs have RAM onboard that is used for character memory. Most LCDs have more RAM available that is necessary for the displayable area. This RAM can be written using the Lcdout instruction. The Lcdin instruction allows

PBP V2.4

this RAM to be read:

```
Lcdin {address,}[variable{,...}]
```

CG RAM runs from address \$40 to \$7f. Display data RAM starts at address \$80.

It is necessary to connect the LCD read/write line to a PICmicro pin so that it may be controlled to select either a read (Lcdin) or write (Lcdout) operation. Two Defines control the pin address:

```
Define LCD_RWREG PORTE ' LCD read/write pin port  
Define LCD_RWBIT 2 ' LCD read/write pin bit
```

New Lcdout Defines

Two Defines have been added to Lcdout. They allow the LCD transfer timing to be set.

```
Define LCD_COMMANDUS 2000 ' Set command delay time in us  
Define LCD_DATAUS 50 ' Set data delay time in us
```

New Readcode and Writecode Instructions

The new PIC16F87x devices allow the program code space to be read and written at run time. While writing self-modifying code is a dangerous technique, it does allow additional non-volatile data storage above the usual 64-256 bytes.

Two new instructions have been added to PBP to allow reading and writing the program code space: Readcode and Writecode. All that is necessary is to specify an address and the word to be read or written:

```
Readcode address, wordvariable  
Writecode address, wordvalue
```

PBP V2.4

Be very sure not to write over the actual program or severe problems can occur. Also keep in mind the word size is 14-bits for the 16F87x devices. This means you can only store values from 0 - 16383. The upper 2 bits of the word cannot be used.

PBP V2.4

New Shiftin / Shiftout Modes

New modes have been added to Shiftin and Shiftout to allow the serial clock to start from either state. Normally the clock starts low and then toggles high and back to low to clock in or out the data. The new mode settings allow the clock to start high and then toggle low and back to high to clock out the data.

New Shift Define

A new Define allows the active state of the shift clock to be extended beyond its usual 2 microseconds to slow down the shift clock. A value up to 65535 microseconds may be used. The minimum value depends on the oscillator and may be found in the documentation for Pauseus.

```
Define SHIFT_PAUSEUS 100
```

Microchip ICD

PicBasic Pro may be used with Microchip's ICD (In-Circuit Debugger). The ICD requires certain resources from the target processor including access to 6 RAM registers and the first location of code space.

Several files have been created to allocate these locations to the ICD and remove them from the resources the PicBasic Pro program has access to. When it is desired to use the ICD, simply include one of these files at the beginning of the PicBasic Pro program.

For PIC16F876 and 877:

```
Include "ICDDEFS.BAS"
```

For PIC16F873 and 874:

```
Include "ICDDEFS1.BAS"
```


PBP V2.4

For PIC16F870, 16F871 and 872:

```
Include "ICDDEFS2.BAS"
```

OPTION Register

The actual name of the OPTION register for use by PicBasic Pro is OPTION_REG. This is the Microchip compatible name so that it can be used within MPLAB. The names of the registers that PicBasic Pro can use may be found in the files PIC14EXT.BAS, PIC17EXT.BAS and PIC18EXT.BAS.

GPIO, TRISIO Registers

The actual name of the port and TRIS register for use by PicBasic Pro for the 12C67x parts is GPIO and TRISIO. This is the Microchip compatible name so that it can be used within MPLAB. The names of the registers that PicBasic Pro can use may be found in the files PIC14EXT.BAS, PIC17EXT.BAS and PIC18EXT.BAS.

Aliases

The PicBasic Pro Compiler allows multiple variable names to point to the same RAM locations. These are generally called aliases. Aliases should only be applied to the originally created variable. There should be no aliases to an alias.

Line Extension Character "_"

A statement may be extended to the next line by adding the line extension character, an underscore ("_"), to the end of it as shown:

```
Branch b0, [label0, label1, label2,_  
label3, label4]
```

PBP V2.4

Additional I2C Defines

Two new Defines are available for use with the I2CREAD and I2CWRITE instructions: I2C_HOLD and I2C_SCLOUT. Using:

```
Define I2C_HOLD 1
```

causes the I2C instruction to wait indefinitely for slow devices. There is no timeout in this case. The PICmicro will wait forever, if necessary, for the I2C bus to be ready.

```
Define I2C_SCLOUT 1
```

changes the mode for the I2C SCL (clock) line. It is usually run open-collector, requiring an external pullup resistor but allowing for multiple masters to control the bus. This Define causes it to output both high and low states, eliminating the external resistor on SCL.

Debugin / On Debug Instructions

Some new instructions have been added to PicBasic Pro to allow programs to be debugged more easily.

Debugin is the converse of Debug. It will read serial input from a fixed pin at a fixed baud rate (the same baud rate as Debug). Several new Defines may be used in conjunction with Debugin:

```
Define DEBUGIN_REG PORTB      ' Debugin pin port
Define DEBUGIN_BIT 0          ' Debugin pin bit
Define DEBUGIN_MODE 1        ' Debugin mode: 0 = true, 1 = inverted
```

If none of the Defines are specified, the Debug settings (or defaults) will be used.

Any of the Hserin2 modifiers, with the exception of parity, may be used with Debugin:

PBP V2.4

```
Debugin {Timeout, Label,}[Item{,...}]
```

```
Debugin [B0, dec W1]
```

Also new are the instructions On Debug Goto, Disable Debug and Enable Debug. These instructions allow a monitor program to be written that can take control of the program in between each PicBasic Pro instruction.

The method by which this happens is similar to the method used by On Interrupt Goto. Once On Debug Goto is encountered, a call to the specified debug label is inserted before each PicBasic Pro instruction in the program. Disable Debug prevents the insertion of this call while Enable Debug resumes the insertion of the call.

A monitor routine may be written that is activated before each instruction. This routine can send data to an LCD or to a serial comm program. Any program information may be displayed or even altered in this manner. A small monitor program example is posted on the melabs web site.

A definition is required to provide a word-sized variable to store the address the program was at before the monitor routine was called by On Debug Goto:

```
DEBUG_ADDRESS var word bank0 system
```

An additional definition may be used to return the level of the current program stack:

```
DEBUG_STACK var byte bank0 system
```

This level should not be greater than 4 in a PicBasic Pro program. The supplied variable will be incremented at each Gosub and decremented at each Return.

The actual stack contents may be saved by creating an array variable with a specific name to which the addresses will be saved:

```
DEBUG_STACK_ADDR var word[4] bank0 system
```

PBP V2.4

When PicBasic Pro sees this variable defined, It will store the return address of each Gosub it encounters into this array. `DEBUG_STACK`, above, must also be defined to use the stack address array.

Also added are `Disable Interrupt` and `Enable Interrupt`. These instructions disable and enable the placement of interrupt check calls in the program as `Disable` and `Enable` previously did. `Disable` and `Enable` have be altered to stop and start the insertion of both `On Interrupt Goto` and `On Debug Goto` calls.

PBP V2.4

Microchip's Floating Point Routines

The PicBasic Pro Compiler has several built-in data types: bits, bytes and words, along with arrays of each. All of these types are unsigned integers. This means there is no decimal point so real or floating point numbers cannot be represented. There are several workarounds for this, including multiplying each value by 10 or 100 for calculations and dividing back when it is time to display the value.

Microchip has developed several different floating point routines in assembler and placed them on their web site. These routines can be integrated into a PicBasic Pro program and called, if floating point is a necessity. While it is not that difficult, it is not obvious how to make this work properly. The necessary PicBasic Pro source code to integrate either the 24-bit or 32-bit Microchip floating point routines into your program, [FP.ZIP](#), may be downloaded. The appropriate floating point routines (Microchip's AN575) are included in this zip. The PicBasic Pro programs must be compiled using the -ampasm switch to invoke Microchip's assembler. If you don't have their assembler, it also may be downloaded from their web site.

```
PBP -p16f84 -ampasm fp
```

The routines are accessed in PicBasic Pro by setting up specific integer variables (aint and bint) and performing a GOSUB to a floating point routine. The first routine should convert the integer value (aint) to a floating point value. Generally, floating point operations occur between 2 numbers, so a second integer (bint) should also be converted. Next a GOSUB to the required floating point operation, multiply for example, is performed. Finally, the floating point number is converted back into an integer (aint) so that PicBasic Pro can use it again. These GOSUB routines are created in an additional PicBasic Pro file that must be INCLUDED at the beginning of the program. The readme files included in the zip explain the procedures in more detail. Also, several example programs are included. Below is one example program that demonstrates the use of the libraries.

Floating point test program

```
include "fp0c.bas"    ' Include file for 'F84 (24-bit)
' include "fp20.bas"  ' Include file for most other PICmicros (24-bit)
' include "fp0c32.bas" ' Include file for 'F84 (32-bit)
' include "fp2032.bas" ' Include file for most other PICmicros (32-bit)
' include "fp17.bas"  ' Include file for 17Cxxx (24-bit)
' include "fp1732.bas" ' Include file for 17Cxxx (32-bit)
' include "fp18.bas"  ' Include file for 18Cxxx (24-bit)
' include "fp1832.bas" ' Include file for 18Cxxx (32-bit)
Pause 500    ' Wait for LCD to start
' Demonstrate floating point multiply
aint = 10
Gosub itofa  ' Convert int to float
bint = 20
Gosub itofb  ' Convert int to float
Gosub fpmul  ' FP multiply (10 * 20)
Gosub ftoia  ' Convert float to int
Lcdout $fe, 1, "*" ", dec aint
```

PBP V2.4

```
    Pause 1000
' Demonstrate floating point divide
    Gosub itofa ' Convert int back to float (200)
    bint = 3
    Gosub itofb ' Convert int to float
    Gosub fpdiv ' FP divide (200 / 3)
    Gosub ftoia ' Convert float to int
    Lcdout $fe, 1, "/", dec aint
' Demonstrate floating point remainder
    aint = 200
    Gosub itofa ' Convert int to float
    bint = 3
    Gosub itofb ' Convert int to float
    Gosub fpdiv ' FP divide (200 / 3)
    bint = 100
    Gosub itofb ' Convert int to float
    Gosub fpmul ' Multiply by 100 to move remainder up 2 places
    Gosub ftoia ' Convert float to int
    aint = aint // 100 ' Get to the remainder
    Lcdout ".", dec2 aint
    End
```

PBP V2.4

FURTHER INFORMATION

17Cxxx Information

The 16-bit core 17Cxxx PICmicros may now be used with the PicBasic Pro Compiler. Simply specify the device type on the command line using the -p option:

```
PBP -p17c752 filename
```

There is no data direction (TRIS) register for PORTA. Therefore, commands that rely on the TRIS register for their operation, such as I2CRead and I2CWrite, may not be used on PORTA.

Hserin and Hserout work with the first USART only. On devices that have two USARTs, use the register names to directly access the second USART.

OPTION Register

The actual name of the OPTION register for use by PicBasic Pro is OPTION_REG. This is the Microchip compatible name so that it can be used within MPLAB. The names of the registers that PicBasic Pro can use may be found in the files PIC12EXT.BAS, PIC14EXT.BAS, PIC17EXT.BAS and PIC18EXT.BAS.

GPIO, TRISIO Registers

The actual name of the port and TRIS register for use by PicBasic Pro for the 12C5xx and 12C67x parts is GPIO and TRISIO. These are the Microchip compatible names so that they can be used within MPLAB. The names of the registers that PicBasic Pro can use may be found in the files PIC12EXT.BAS, PIC14EXT.BAS, PIC17EXT.BAS and PIC18EXT.BAS.

Appendix B

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Contact Information

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(719) 520-1867 fax

<http://www.melabs.com>

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PICmicro data sheets, CD-ROMs and literature may be obtained from:

Microchip Technology Inc.

2355 W. Chandler Blvd.

Chandler AZ 85224-6199

(602) 786-7200

(602) 899-9210 fax

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Information