

Simple Real-Time Kernels for M68HC05 Microcontrollers

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INTRODUCTION

This application note demonstrates the operation of two different types of simple real-time kernels for the M68HC05 MCUs, namely, a priority-based kernel and a time-based kernel. Assembly source code is provided for each.

WHY USE A REAL-TIME KERNEL?

A kernel is similar to a simple operating system in that it offers very fast software development and gives flexibility that allows new modules to be added without interfering with those already in place. A real-time kernel is easy to debug and encourages the user to develop software in an organized fashion. Two simple real-time kernels are presented in this application note: a priority-based kernel and a time-based kernel.

The priority-based kernel provides a means of executing a number of user-defined tasks, where the order of execution of each task is determined by the priority level assigned by the user. This kernel is used for tasks that vary in their execution times or where interrupts may be common or lengthy.

The time-based kernel executes user-defined tasks at specific, regular time intervals. These tasks are written so that they run immediately and do not require code to determine the timing of their execution. Rather, the user determines the rate of execution. This kernel is ideal for many predicted duration routines with few or short duration interrupts.

Both these examples aim to demonstrate the ease with which software modules can be integrated into a kernel and executed to support different applications.

PRIORITY-BASED KERNEL

Specific features of the priority-based kernel are:

1. This implementation supports three priority levels, although more levels are possible. These will be referred to as Priority 1, 2, and 3, with Priority 1 having the highest ranking.
2. Each priority level is capable of controlling the execution of eight tasks via a task request register.
3. Task addresses are stored, by the user, in a task table located at the end of the program.
4. One bit in each of the priorities' task request registers corresponds to one task in the task table.
5. Within each of the priority levels, bit 0 of the task request register is assigned the highest priority and bit 7 is assigned the lowest priority.
6. A task can change priorities by being entered into more than one position in the task table, which means setting a different bit in one of the request registers.
7. When work is to "start" on a priority level, a copy of the task request register is made. The copy is referred to as the "shadow register." The kernel operates on this copy. The original is then cleared, thus enabling it to be updated with new tasks that require execution.
8. Note that "start" means that the previous operation, carried out by the kernel, will have caused the shadow register to be declared empty, so that all the tasks in that priority at that time will have been completed and their corresponding bits cleared.
9. The Priority 1 shadow register is always updated/checked first.
10. The Priority 2 shadow register is updated/checked only after all the Priority 1 tasks set to execute at that time have been completed, so that the Priority 1 shadow register is empty. Only one Priority 2 task is executed at a time, before starting again on the Priority 1 task request register.
11. The Priority 3 shadow register is updated/checked only after all the Priority 1 tasks and Priority 2 tasks set to execute at that time have been completed, so that the Priority 1 and 2 shadow registers are empty. Only one Priority 3 task is executed at a time, before starting again on the Priority 1 task request register followed by Priority 2.
12. A task that is running can order another task to run by setting the appropriate bit in one of the task request registers.
13. The kernel is capable of supporting interrupts, such as EXT, SCI, TIMER, etc.
14. The kernel supports local and global variables, but the user must manage these carefully, especially when information is being passed between procedures.

NOTE

A task that is running can stop another task which is scheduled to run by clearing the appropriate bit in the correct task request register. However, this may not be advisable and is not supported in this implementation.

SOFTWARE OPERATION

For a task to run, it must be assigned a position in the task table. Each position in the table corresponds to a bit in one of the task request registers. The user's program sets the bit. Execution time has no constraints and any number of tasks may be scheduled to run at any one time.

Here is a basic description of how the software operates. Refer to the flowchart shown in Figure 3.

1. When a priority level is to be operated on, a copy is made of the corresponding task request register. This copy is called the shadow register. The original is then cleared so that it can be updated when new tasks require execution.
2. The kernel checks for bits set in the shadow registers. Any set bits which require execution correspond to particular tasks in the task table.
3. Priority 1 is checked first, starting from bit 0.
4. After all these tasks have been checked and executed, one Priority 2 task is executed.
5. If there are no Priority 2 tasks at this time, a Priority 3 task is executed. If there are no Priority 3 tasks at this time, the kernel updates and then checks the Priority 1 shadow register.
6. Every time a task has been executed, the bit in the shadow register, which corresponds to the task, is cleared.
7. When any one of the shadow registers is declared totally empty, it is updated again by copying the corresponding original task request register. In this way, any new tasks that require execution will be scheduled for execution.
8. After either a Priority 2 task or a Priority 3 task has been executed, the kernel checks the updated Priority 1 shadow register. If there are any Priority 1 tasks to be executed, all of them will be executed before any further Priority 2 or Priority 3 tasks are executed.
9. The whole process is then repeated.

An example of the software operation and steps carried out are shown in Figure 1.

1. Copy the Priority 1 task request register to a shadow register and clear the original. Inspect the Priority 1 shadow register, starting from bit 0 — execute task A, then task C, then task G.
2. Copy the Priority 2 task request register to a shadow register and clear the original.
3. Inspect the Priority 2 shadow register — execute task L.
4. Inspect the updated Priority 1 shadow register — no tasks to execute. Inspect the Priority 2 shadow register — no tasks to execute.
5. Copy the Priority 3 task request register to a shadow register and clear the original. Inspect the Priority 3 shadow register — execute task U.
6. Inspect the updated Priority 1 shadow register — no tasks to execute.
7. Inspect the updated Priority 2 shadow register — no tasks to execute.
8. Inspect the Priority 3 shadow register — execute task X.
9. Inspect the updated Priority 1 task request register.

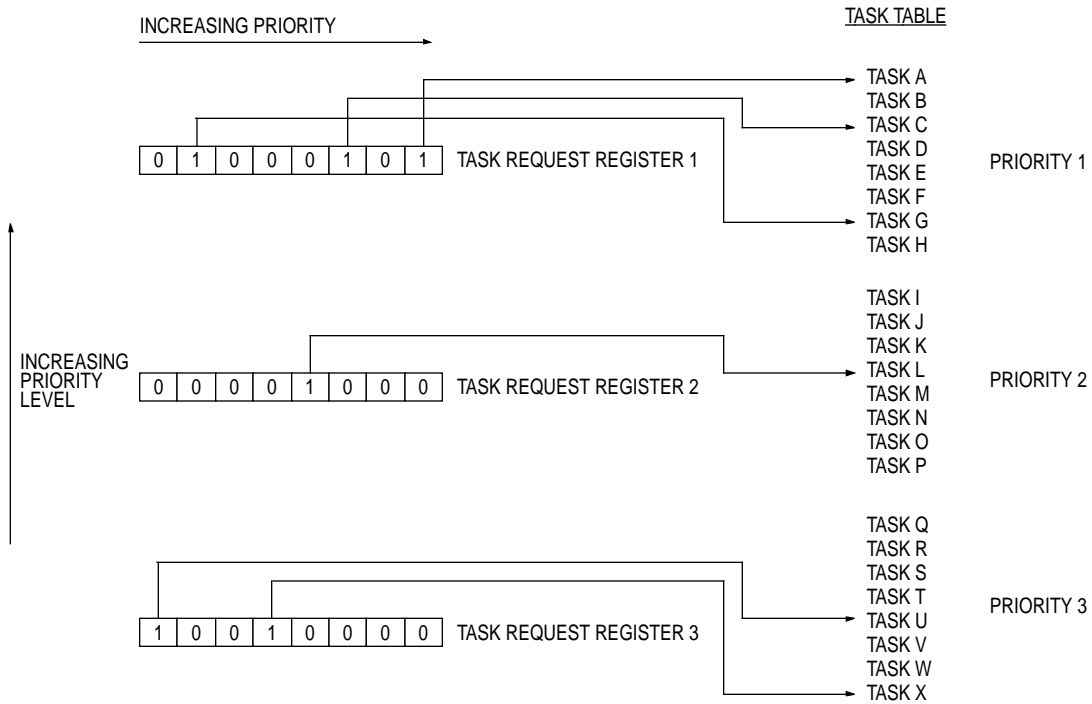


Figure 1. Software Operation Example

Figure 2 shows a change of selected tasks in Priority 1. This involves updating the corresponding bits in the task request register each time a task requires execution.

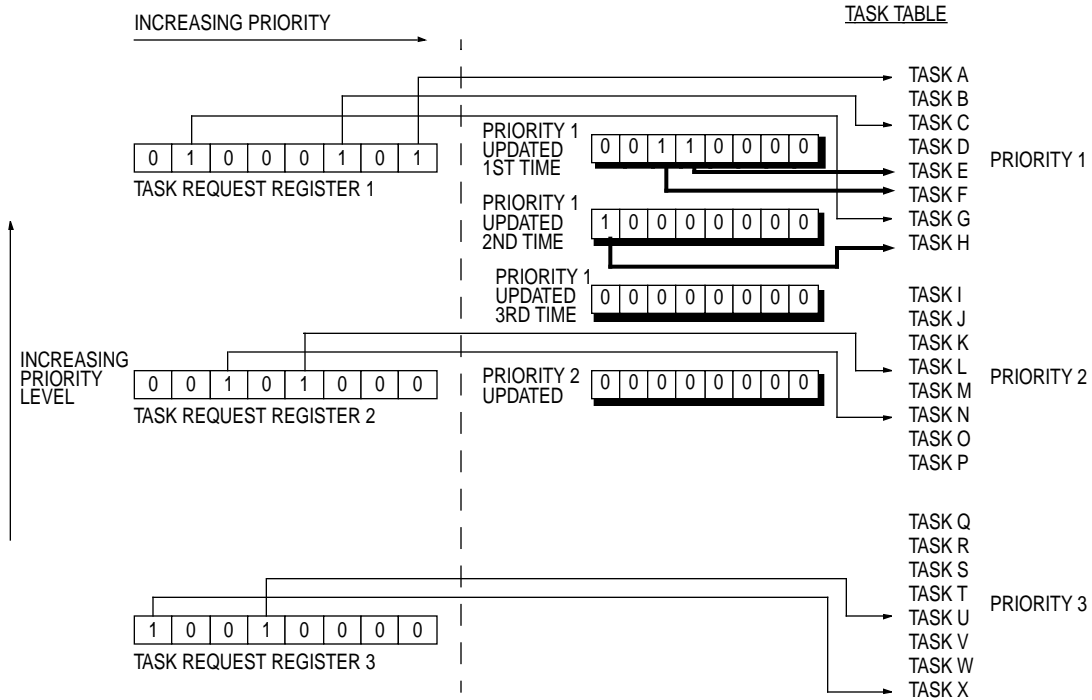


Figure 2. Updating Task Request Registers Example

The priority-based kernel performs these operations:

1. Copy the Priority 1 task request register to a shadow register and clear the original. Inspect the Priority 1 shadow register, starting from bit 0 — execute task A, then task C, then task G.
2. Copy the Priority 2 task request register to a shadow register and clear the original. Inspect the Priority 2 shadow register — execute task L.
3. Inspect the updated Priority 1 task request register (updated 1st time). For example, copy the Priority 1 task request register to a shadow register and clear the original. Inspect the Priority 1 shadow register — execute task E, then task F.
4. Inspect the Priority 2 shadow register again — execute task N.
5. Inspect the updated Priority 1 task request register (updated 2nd time). For example, copy the Priority 1 task request register to a shadow register and clear the original. Inspect the Priority 1 shadow register — execute task H.
6. Inspect the updated Priority 2 task request register (Priority 2 updated). For example, copy the Priority 2 task request register to a shadow register and clear the original. Inspect the Priority 2 shadow register — no tasks to execute.
7. Copy the Priority 3 task request register to a shadow register. Inspect the Priority 3 shadow register — execute task U.
8. Inspect the updated Priority 1 task request register (updated 3rd time). For example, copy the Priority 1 task request register to a shadow register and clear the original. Inspect the Priority 1 shadow register — no tasks left to execute.
9. Inspect the updated Priority 2 task request register — no tasks left to execute.
10. Inspect the Priority 3 shadow register again — execute task X.
11. Inspect the updated Priority 1 task request register.

IMPLEMENTATION

Flowchart 1(Figure 3) explains how the software is designed to operate.

Listing 1 shows how the assembler code is used to implement the priority-based kernel. In this case, the MC68HC05C9 has been chosen as an example. However, the software is designed to support any M68HC(7)05 device with minimal changes to memory organization.

To integrate code into the kernel, the user must enter the address of the routine into the task table. Each 16-bit entry in the table points to a task. This implementation has 26 entries, but there can be as many as the user requires. When a task is to be executed, a corresponding entry in the task table is used as the destination address of a subroutine call. This means that each task must finish with an RTS command.

Unused entries in the task table must point to an RTS command for safety reasons.

The procedure WRITERAM, in Listing 1, controls which task is executed. The task table starts at an arbitrary value of \$400 in the MC68HC05C9 user ROM.

The user controls the program flow using flags. These flags, internal to the task, control which subtask is carried out each time the task is executed.

Task D of Listing 1 shows an example of how code is integrated into the kernel.

The listing also includes an SCI interrupt service routine to demonstrate how the scheduler handles interrupts. This routine is an example of communication between the MCU's SCI and a dumb terminal. The MCU receives an ASCII character, which is sent by the dumb terminal through an RS232 cable. The MCU then translates the 8-bit binary character, representing the ASCII character, into two ASCII characters. These characters, which represent the original hexadecimal equivalent of the received character, then are transmitted back to the terminal.

The routine also shows how other tasks are scheduled to execute.

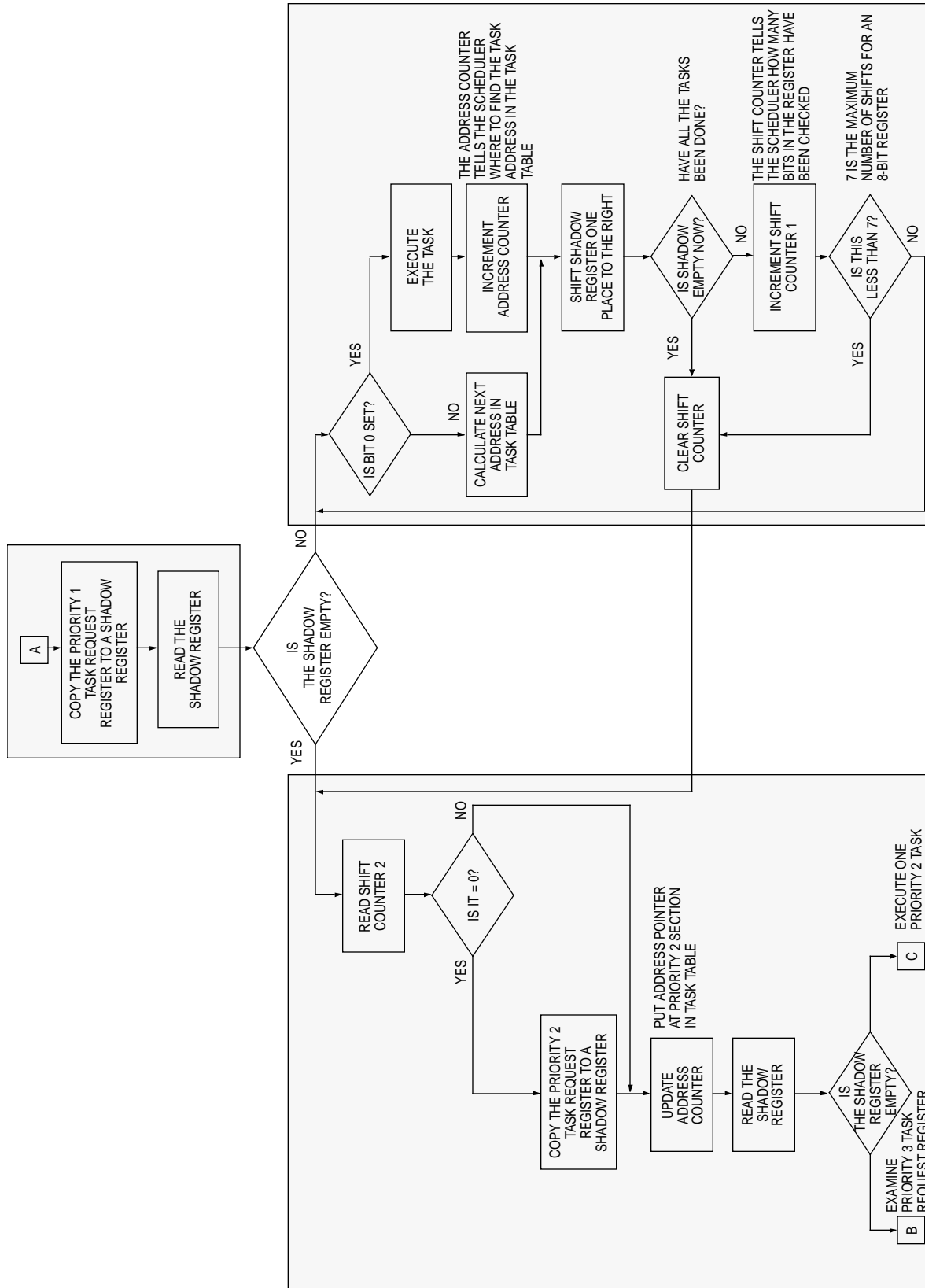


Figure 3. Flowchart 1 (Sheet 1 of 2)

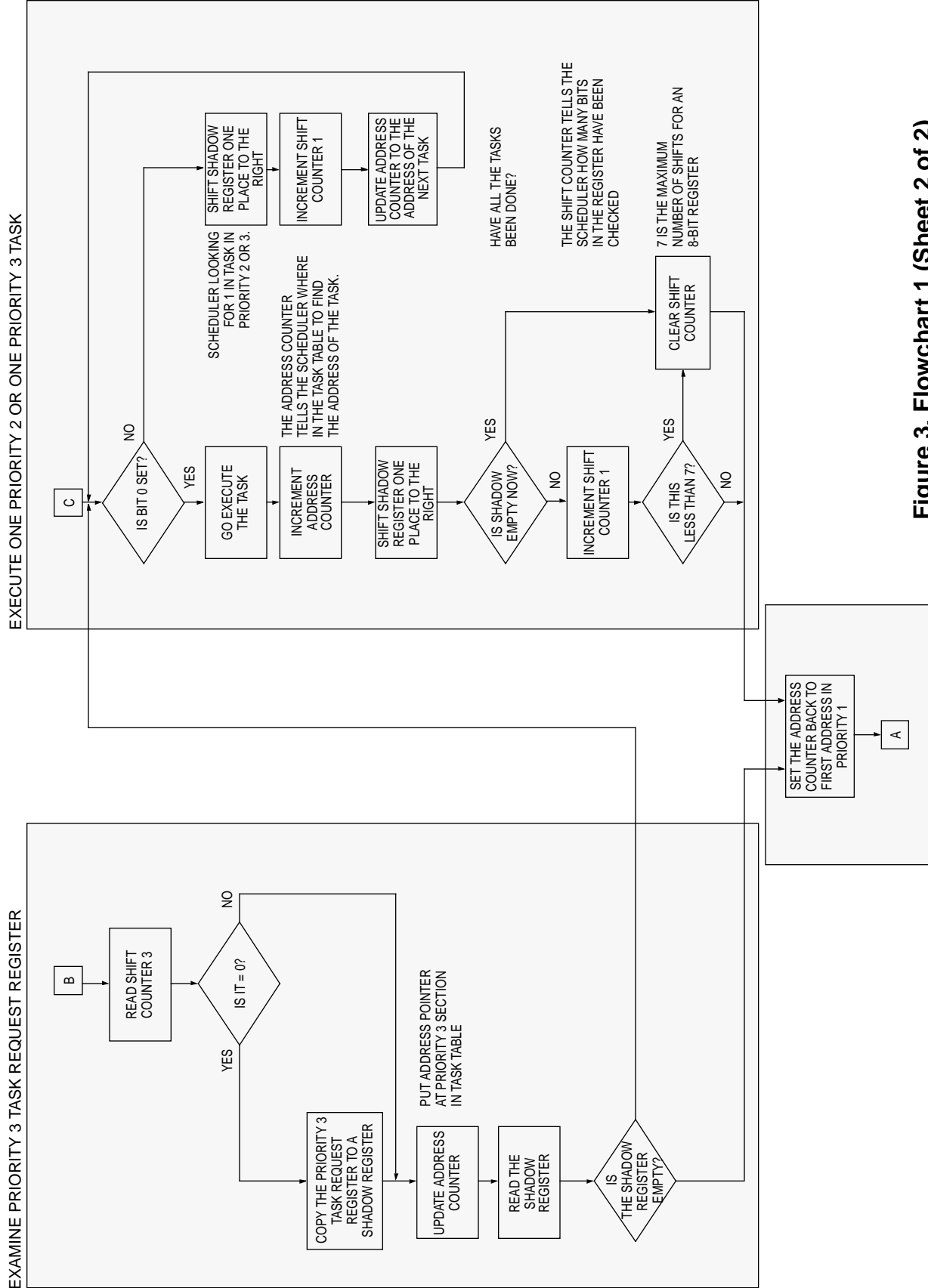


Figure 3. Flowchart 1 (Sheet 2 of 2)

TIME-BASED KERNEL

Specific features of the time-based kernel are:

1. This kernel uses the MCU system clock and different counters to allocate time slots for each task to be executed.
2. The timing of execution of these tasks is controlled by the generation of timer interrupts inside the MCU. These interrupts are generated in different ways, depending on the timer that is used.
3. Two kinds of timers are supported in this implementation: the programmable timer and the core timer. The timer used depends on which MCU is being used in the application. Some HC05s have only one of the two timers. The MC68HC05L4, used in this example, has both timers, so the timer required to control the kernel has to be selected by the user before assembling the program.
4. Both timers have a continually incrementing counter which acts as a clock for the kernel. The programmable timer has a free-running counter and the core timer has a timer counter register.
5. When a timer interrupt occurs, a flag is generated by the timer. The programmable timer generates an output compare flag and the core timer generates a core timer overflow flag. A service routine, pointed to by the interrupt vector, is then executed. The flags are tested within the interrupt routine to verify the interrupt source, since the interrupt vector is shared.
6. User-generated interrupt service routines should be kept as short as possible to ensure that maximum time is allowed for each task to execute. Strict testing must be made for the worst case timing of each.
7. A time slice counter determines the minimum time between tasks by counting the timer interrupts.
8. The time slice counter is available as a timer for tasks to use, for example, for delay or debounce routines.
9. A task counter determines exactly which task is to be executed. Each time the time slice counter decides that a task is to be performed, the task counter increments. The kernel then tests which bit in the task counter is clear, and, depending on which bit is clear, a corresponding task is executed.
10. The number of tasks has no limit. The user can have the number required since this is only dependent on the number of bits in the task counter.
11. Tasks that take longer than one time slot to execute can be split into subtasks. For example, this is useful in an EEPROM programming routine where a time delay is required between the procedures. This routine could be divided into:
 - byte erase
 - byte program
 - program verify
12. Flags, internal to the task, are used to control which subtask is to be carried out each time the task is executed.
13. The kernel supports local and global variables, but the user must manage these carefully, especially when information is being passed between procedures.

SOFTWARE OPERATION

Timer Interrupt Generation

In the case of the programmable timer, the output compare interrupt is generated when the free-running counter counts up to equal a pre-determined value of the output compare. This pre-determined value is called the output compare period and is declared at the start of the program, so that the value in the output compare can be updated easily. Setting the output compare period in this way allows for easy adaptation to suit the timing of the application.

When using the core timer, the interrupt is generated each time the core timer counter register rolls over from \$FF to \$00. Thus, the core timer overflow interrupt is generated every 512 microseconds (when using a 4-MHz clock). Unlike the programmable timer, its value cannot be changed.

Task Execution

A time slice period is set at a pre-defined value at the start of the program, again to allow easy adaptation of the routine. The time slice counter will increment each time an interrupt is generated until it reaches the value of the time slice period. When this occurs, the task counter is incremented and, therefore, a task is executed. At this point, the time slice counter is reset, ready to count the next time slice period.

Each of the tasks should take, or be split into subtasks that take, less than one time slice period to execute. The kernel provides a task flag for different task rates, so that tasks should be running at binary power multiples of the time slice period. The fastest task runs at a period of twice the time slice period, the next fastest runs at a period of four times the time slice period, the next task eight times the time slice period and so on. These tasks are referred to as tasks A, B, C, etc. Thus, task H will run at a period of 256 times the time slice period.

Each bit of the task counter corresponds to a task. Each time the task counter is incremented, the task counter byte is tested for the presence of a zero, starting with the least significant bit. When a zero bit is found, the routine aborts the check and the corresponding task is executed. Note that no task is executed when the task counter is all ones (\$FF if one byte). This signifies that a background task or idle loop will be the only activity run for this task period.

There can be as many tasks as there are number of bits in the task counter, and this counter can be as many bytes as the application requires.

It is possible to have several small tasks, rather than one big task, executing inside one time slot. When entering the time slot, the kernel detects which task to execute by inspecting flags controlled by the user routines.

It is also possible to only use some of the time slots available. The unused slots could allow more time for background tasks.

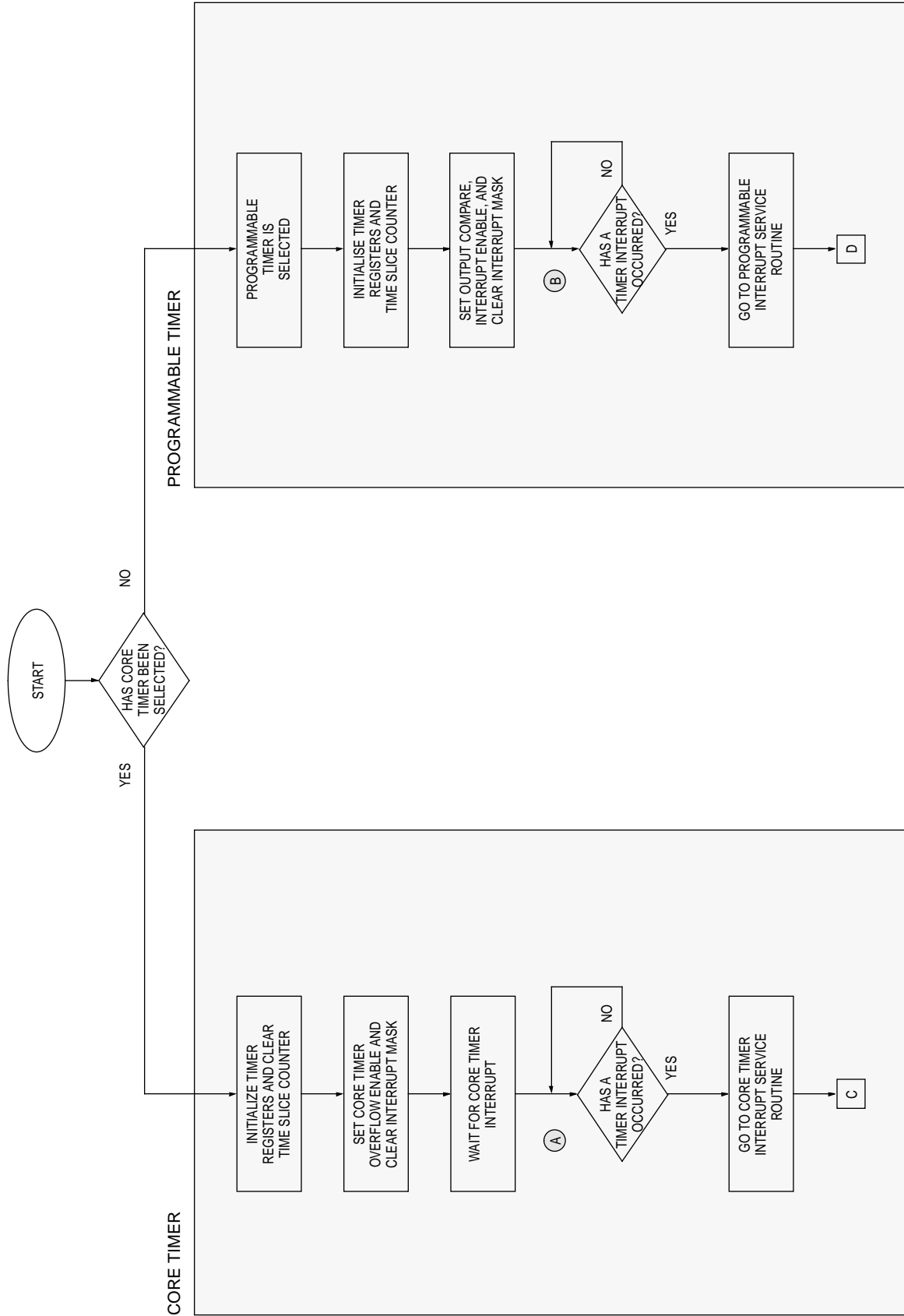


Figure 4. Flowchart 2 (Sheet 1 of 3)

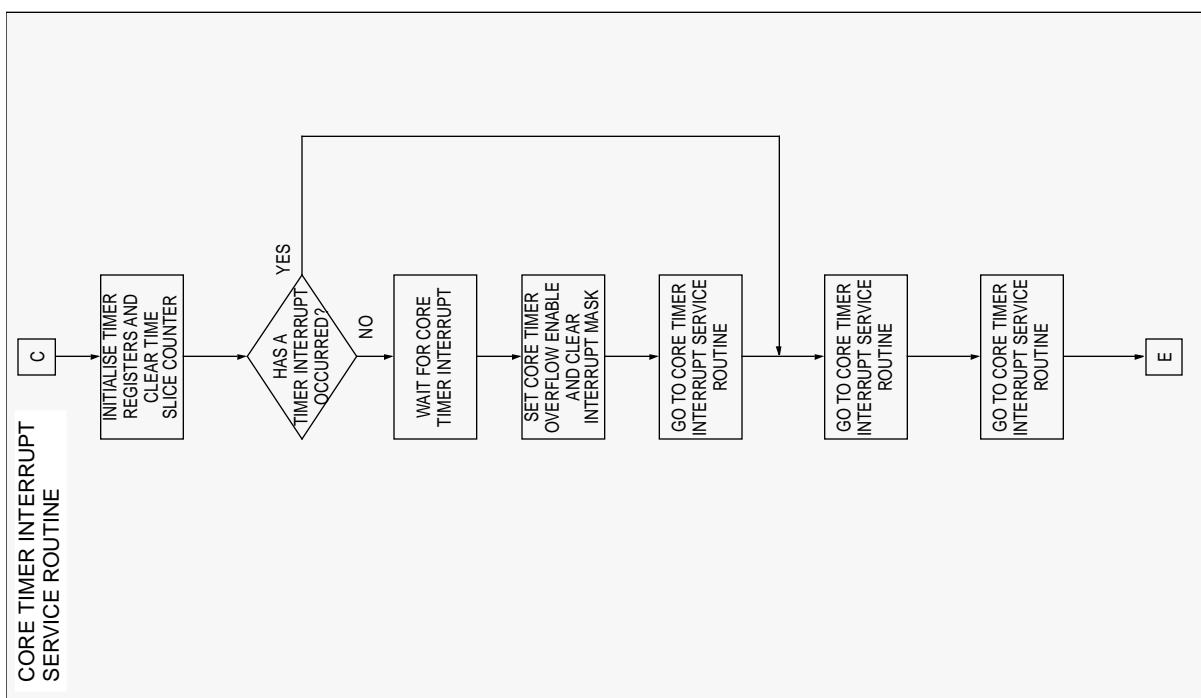
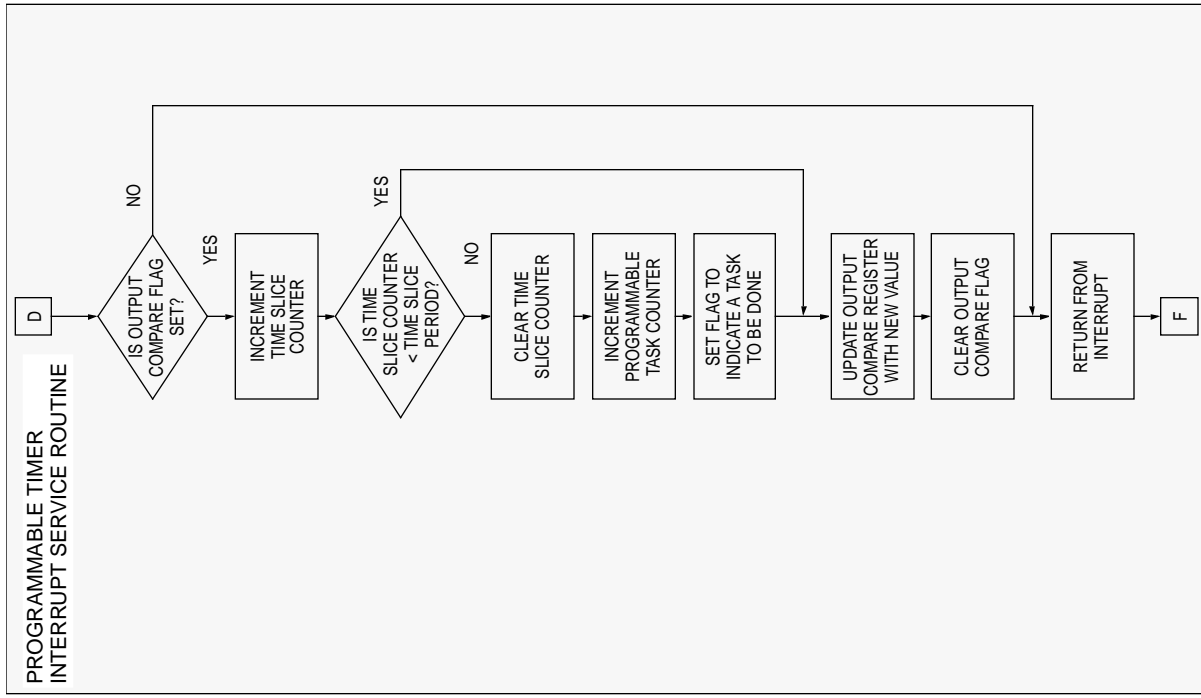


Figure 4. Flowchart 2 (Sheet 2 of 3)

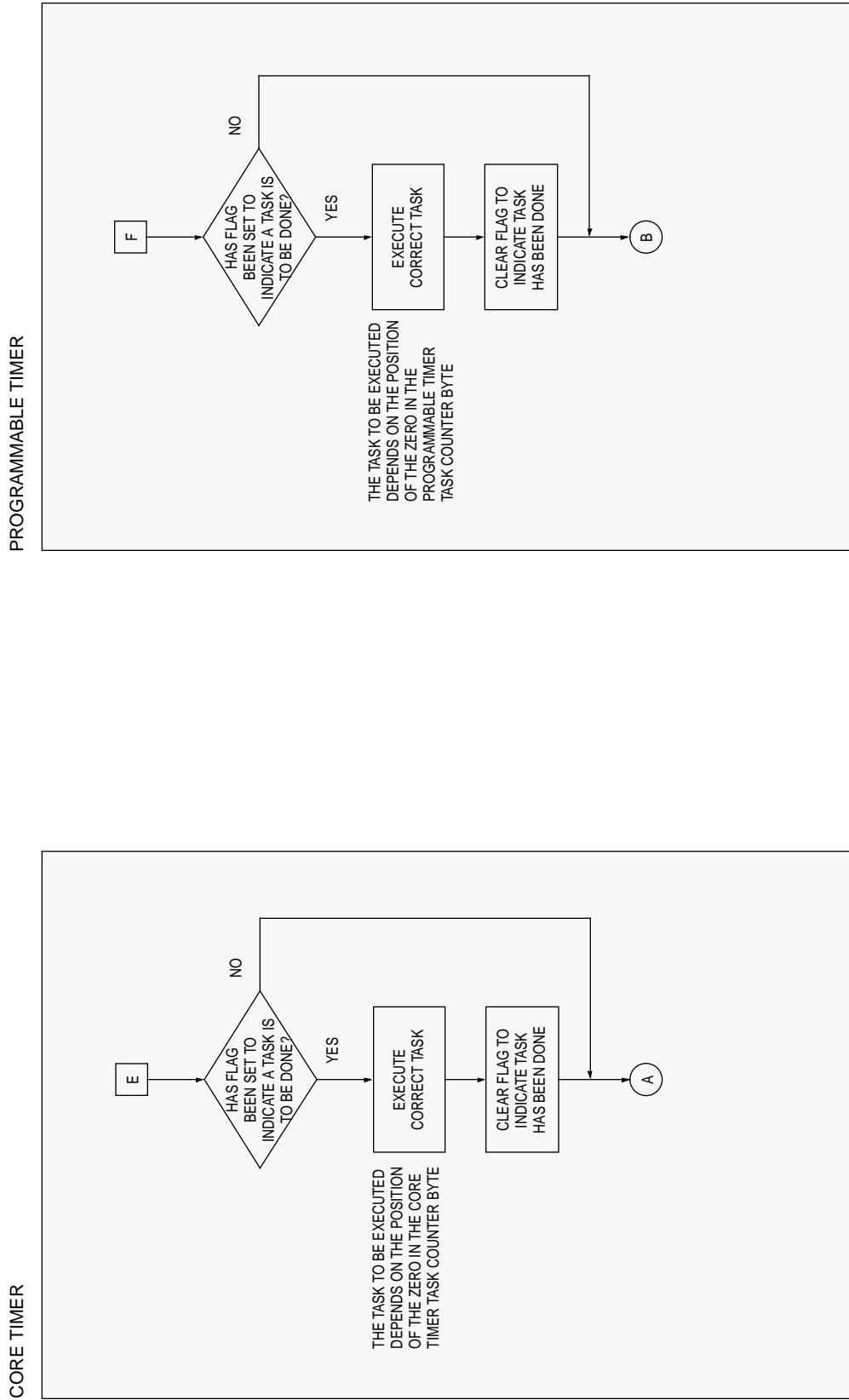


Figure 4. Flowchart 2 (Sheet 3 of 3)

Example 1 assumes the programmable timer is being used and a 5 ms time slice period is required, the most frequent task executing every 10 ms. The 5 ms time slice period is obtained by multiplying the internal system clock (2 μs) by an output compare period set at 250, multiplied by a time slice period set at 10. This gives an interrupt every 500 μs and a task executed every 5 ms (500 μs x 10).

The sequence of the task execution using the programmable timer in this way is shown in Figure 5.

The execution repetition period of each task = 5 x 2n, where n = position number of the letter in the alphabet, for example, task B's execution repetition period = 5 x 2(2) = 20 ms.

The task to be executed is dependent on the bit position of the 0, starting inspection from the LSB of the task counter byte.

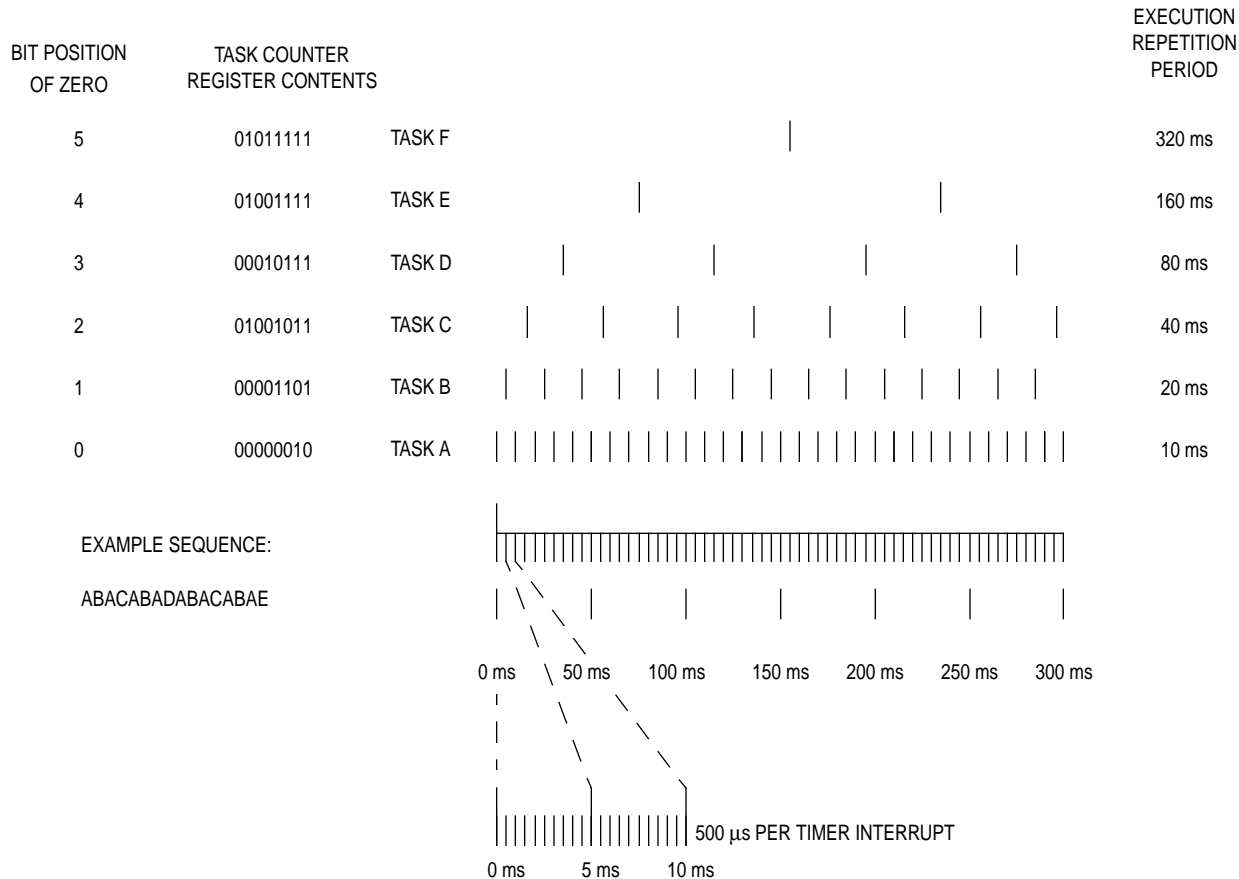


Figure 5. Example 1 — Sequence of Task Execution for Programmable Timer

Example 2 assumes the core timer is being used and that a 5.1 ms time slice period is required, the most frequent task executing every 10.2 ms. The 5.1 ms time slice period is obtained by multiplying the internal system clock (2 μs), multiplied by 255, which is the number the core timer counter register counts up to before rolling over to \$00, multiplied by a time slice period of 10. This gives an interrupt every 510 μs and a task executed every 5.1 ms (510 μs x 10).

The sequence of task execution using the core timer in this way is shown in Figure 6.

The execution repetition period of each task = 5.1 x 2n, where n = position number of the letter in the alphabet, for example, task B's execution repetition period = 5.1 x 2(2) = 20.4 ms.

The task to be executed is dependent on the bit position of the 0, starting inspection from the LSB of the task counter byte.

BIT POSITION OF ZERO	TASK COUNTER REGISTER CONTENTS	TASK	EXECUTION REPETITION PERIOD
5	01011111	TASK F	326.4 ms
4	01001111	TASK E	163.2 ms
3	00010111	TASK D	81.6 ms
2	01001011	TASK C	40.8 ms
1	00001101	TASK B	20.4 ms
0	00000010	TASK A	10.2 ms

EXAMPLE SEQUENCE:

ABACABADABACABAE

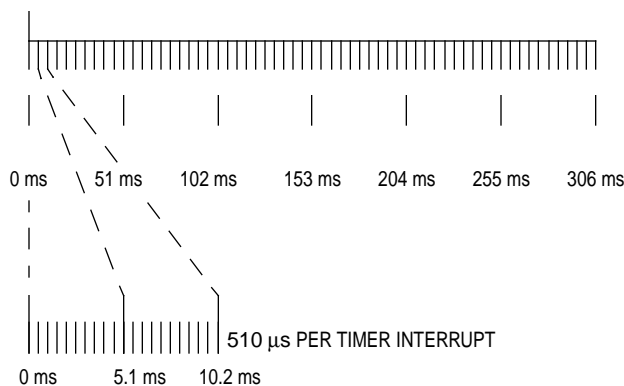


Figure 6. Example 2 — Sequence of Task Execution for Core Timer

IMPLEMENTATION

Flowchart 2 (Figure 4) explains how the software is designed to operate.

Listing 2 shows the assembly code used to implement the time-based kernel. The 68HC05L4 was chosen to demonstrate the use of both timers in the software.

Code is integrated into this kernel in modules. Each of these modules is entered like a subroutine and so must finish with the RTS command.

Note that the slots not filled with user tasks also must have an RTS.

This implementation has only eight time slots; however, this can be extended by making the task counter larger.

Listing 2 shows simple tasks in order to demonstrate where the user's tasks are placed. Each task toggles a different port pin on port B of the device.

A good example of the time-based kernel in operation is in the application note titled *Telephone Handset with DTMF using the MC68HC05F4*, Freescale document number AN488/D. In this example, the kernel has been used, along with flags on entry to each routine, to control the program flow.

Also note that, when developing software to integrate into the kernel, worst case timing analysis is required to ensure correct operation.

SUMMARY

In summary, the priority-based kernel offers a very simple way to execute software modules in an application, where the number of tasks may vary depending on the conditions resulting from a particular operation. Tasks are selected to execute merely by setting a bit in one of the task request registers, provided the user's software modules are positioned correctly in the task table.

The time-based kernel provides a means of executing a number of tasks at specific, regular time intervals. The execution of the task, once the kernel has entered the time slot automatically, is dependent on flags being set to control the software. This could be useful in an application where time of day events require recording.

Both kernels encourage group development and module reuse, which together have proven to offer a much more efficient way of developing software.



```

*****
*
*                                     COPYRIGHT (c) *
*
*               LISTING 1
*               *****
*
* FILE NAME: PRIORITY.ASM
*
*
* PURPOSE: The purpose of this software is to provide a means of executing
*           a number of user defined tasks, where the order of execution of
*           each task is determined by the level of priority that the task is
*           assigned by the user.
*
*
* TARGET DEVICE: 68HC(7)05
*
*
* MEMORY USAGE(bytes)  RAM: 22 BYTES      ROM: 640 BYTES
*
*
* ASSEMBLER:  IASM05                      VERSION: 3.02
*
*
* DESCRIPTION:  This Priority Scheduler uses 3 task request register
*               (for 3 different priority levels) to organise the user
*               defined tasks into different priorities. Each bit
*               in each of the 3 task request registers corresponds
*               to one task in a Task Table, located at the end of the
*               program. The user is simply required to enter a task into
*               the appropriate position in the task table and set the
*               corresponding bit in the correct task request register.
*               The prefix PS refers to PRIORITY SCHEDULER.
*
*
* AUTHOR: Joanne Santangeli  LOCATION: EKB  LAST EDIT DATE: 9/DEC/94
*
*
* UPDATE HISTORY
*
* REV      AUTHOR      DATE      DESCRIPTION OF CHANGE
* ---      -
* 1.0      JS          9/12/94    INITIAL RELEASE
*
*
*=====
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*
*****

```



* MEMORY AND PORT DECLARATIONS *

ROM EQU \$180 ;User ROM are for the 705C9
RAM EQU \$50 ;RAM are for 705C9
VECTOR EQU \$3FF4 ;Start of vector addresses
TABLE EQU \$400 ;Start address of task table
PORTA EQU \$00 ;Port A declaration
DDRA EQU \$04 ;Port A Data Direction declaration
PORTB EQU \$01 ;Port B declaration
DDRB EQU \$05 ;Port B Data Direction Register
BRATE EQU \$0D ;Baud rate register
SCCR1 EQU \$0E ;SCI control register 1
SCCR2 EQU \$0F ;SCI control register 2
SCDAT EQU \$11 ;SCI data register
SCSR EQU \$10 ;SCI status register

* PRIORITY SCHEDULER CONSTANTS *

LSB EQU 0 ;Bit 0 of task request registers
DO_TASK EQU 1 ;Flag to say do Priority 1 task
TRY_PR3 EQU 2 ;Flag to say check Priority 3
GO_PR1 EQU 3 ;Flag to say go back to Priority 1

* EXAMPLE TASK CONSTANT *

FINAL EQU 4 ;To indicate last time round Task D
ORG RAM

* PRIORITY SCHEDULER VARIABLES *

JUMPLONG RMB 8 ;Space to write a procedure in RAM
PR_LEVEL RMB 1 ;Holds the priority level number
TASKREQ RMB 3 ;Task request register
SHADOWTASK RMB 3 ;Copy of the task request register
ADD_POINTER RMB 1 ;Points to address in task table
SHIFTCNT RMB 3 ;Number of shifts done on
TASKTEMP RMB 1 ;Copy of SHADOWTASK for BRSET comm
SYSFLAG RMB 1 ;Location for system holding flags
SETTASKS RMB 1 ;In SCI routine to set tasks to run



* EXAMPLE TASK VARIABLES *

```
DELAY_VAR      RMB      1      ;Variable used in example routine
TIME_ON        RMB      1      ;Variable used in example routine
NUM_ON_LEDS    RMB      1      ;Controls seq of LEDS in example
APP_FLAG_REG   RMB      1      ;Variable used in example routine
TEMP           RMB      1      ;Used in SCI interrupt service routine
TEMPLO         RMB      1      ;Used in SCI interrupt service routine
TEMPHI         RMB      1      ;Used in SCI interrupt service routine

                ORG      ROM
```

* MAIN PROGRAM *

```
SCHED05        JSR      INITIAL ;Initialise Port A & RAM
                CLI      ;Clear Interrupt Mask
SCHED99        JMP      PSCHED  ;Priority scheduler
```

* PROCEDURES *

*
* NAME: INITIAL
*
* PURPOSE: To initialise ports and clear all RAM locations used in the
 program.
*
* SUBROUTINES USED: CLEAR
*
* DESCRIPTION: Procedure sets all Port A pins as outputs
*

```
INITIAL        CLR      PORTA   ;Clear Port A
                LDA      #$FF   ;Set all pins as outputs
                STA      DDRA   ;
                JSR      CLEAR   ;Go to clear RAM locations
                RTS
```

CLEAR CLRX ;
CLEAR05 CLR RAM,X ;Clear RAM location
 INCX ;Go to next location
 CPX #\$20 ;Cleared all the locations ?
 BLO CLEAR05 ;If not go clear next location
 RTS ;Otherwise, exit

```

*****
* NAME: PSCHED
*
* PURPOSE: This procedure is the control routine for the priority
* scheduler. It controls which priority level task request
* register is inspected at what time.
*
* ENTRY CONDITIONS: The prioritys' task request registers will have
* been filled with flags corresponding to tasks in
* the task table that the user wishes to execute, or
* indeed if a task has set another task to execute, a
* flag will be set in the task request register.
* All the RAM locations and port A will have been
* initialised.
*
* EXIT CONDITIONS: This procedure is never exited.
*
* SUBROUTINES USED: PRIOR_1, PRIOR_2, PRIOR_3OR3, PRIOR_3, WRITERAM,
* COPY, CHECKBIT0, SHIFTRREG, INCSHIFT, CLRSHIFT,
* INC_LEVEL, UPDATE.
*
* EXTERNAL VARIABLES USED: JUMPLONG, PR_LEVEL, TASKREQ, SHADOWTASK,
* ADD_POINTER, SHIFTCNT, TASKTEMP, SYSFLAG,
* NUM_ON_LEDS, TIME_ON, NUM_FLASH, DELAY_VAR.
*
* DESCRIPTION: 1. When a priority level is to be operated on, a copy will
* be made of the corresponding task request register. The
* original will then be cleared so that it can be updated
* when new tasks require execution.
*
* 2. Priority 1 will be checked first, starting form bit 0
*
* 3. After all these tasks have been checked and executed,
* one Priority 2 task will be executed.
*
* 4. If there are no Priority2 tasks at this time, a Priority
* 3 task will be executed.
*
* 5. Every time a task has been executed, the bit in the
* copied task request register, which corresponds to the
* task, shall be cleared.
*
* 6. When any one of the copied task request registers is
* declared totally empty, it shall be updated again by
* copying the original corresponding task request register
* In this way, any new tasks that require execution may be
* given a time slot in which to execute.
*
* 7. After either a Priority 2 task or Priority 3 task has
* been executed, the scheduler will then go back and check
* the updated Priority 1 task request register. If there
* are any Priority 1 tasks to be executed, they will all
* be executed before any further Priority 2 or Priority 3
* tasks.
*
* 8. The whole process will then be repeated.
*****

```



```

PSCHED      JSR      PRIOR_1      ;Examine & Execute Priority 1 tasks
PSCHED05    JSR      PRIOR_2      ;Examine Priority 2 task request reg
PSCHED10    JSR      PRIOR_2OR3   ;Executes one Priority 2 or 3 task
           BRSET    TRY_PR3,SYSFLAG,PSCHED15 ;Go to examine Priority 3
           BRA      PSCHED      ;Go back to Priority 1
PSCHED15    JSR      PRIOR_3      ;Examine Priority 3
PSCHED99    BRA      PSCHED10     ;Go & execute a Priority 2 or 3 task

```

```

*****
*
* NAME: PRIOR_1
*
* PURPOSE:      To examine the Priority 1 task request register and execute
*               all the Priority 1 tasks set to execute at that time.
*
* EXIT CONDITIONS:  All Priority 1 task set to execute at that time
*                   have been completed.
*
*****

```

```

PRIOR_1      CLRX      ;
           STX      PR_LEVEL     ;Set priority level to 1
           JSR      COPY        ;Copy task req reg to a temp loc
           LDA      SHADOWTASK,X ;Read this temporary location
PRIOR1_05    BEQ      PRIOR1_99   ;If its empty, go try Priority 2
           JSR      CHECKBIT0    ;Otherwise,go check bit 0
           BRSET    DO_TASK,SYSFLAG,PRIOR1_10;If bit 0 set,go do a task
           BRA      PRIOR1_15    ;Otherwise shift right
PRIOR1_10    JSR      WRITERAM    ;Go write subroutine in RAM
           JSR      JUMPLONG     ;Go execute the correct task
           INC      ADD_POINTER   ;Update address pointer
PRIOR1_15    BCLR     DO_TASK,SYSFLAG ;Clear flag to say done the task
           JSR      SHIFTRREG    ;Shift tempoary register to right
           LDA      SHADOWTASK,X ;Read the temporary register
           BEQ      PRIOR1_99   ;If reg now empty,go to Priority 2
           JSR      INCSHIFT     ;Otherwise, increment shift counter
           LDA      SHIFTCNT,X   ;Read value in shift counter
           CMP      #$07        ;Completed max number of shifts ?
           BHI      PRIOR1_99   ;If so, go try Priority 2
           BRA      PRIOR1_05   ;If not, try next bit in Priority 1
PRIOR1_99    RTS

```



```

*****
*
* NAME: PRIOR_2
*
* PURPOSE:   To examine the Priority 2 task request register
*
* ENTRY CONDITIONS:   All priority 1 tasks have been executed.
*
* EXIT CONDITIONS:   A flag is set to say either, go execute one Priority
*                   task, or go examine the Priority 3 task request
*                   register.
*
*****

```

```

PRIOR_2      JSR      CLRSHIFT      ;Clear previous shift counter
             JSR      INC_LEVEL     ;Increment priority level
             LDA      SHIFTCNT,X    ;Read present shift counter
             BNE     PRIOR2_05      ;If it <> 0,update address pointer
             JSR      COPY          ;Copy task req reg to a temp loc
PRIOR2_05    JSR      UPDATE        ;Update address pointer
             ADD     #$10           ;Set address pointer to start of
             STA     ADD_POINTER    ;correct section in the task table
             LDX     PR_LEVEL       ;
             LDA     SHADOWTASK,X   ;Read the temporary location
             BEQ     PRIOR2_10      ;If its empty, set flag TRY_PR3
             BRA     PRIOR2_99      ;Otherwise, exit
PRIOR2_10    BSET    TRY_PR3,SYSFLAG ;Set flag to say try Priority 3
PRIOR2_99    RTS

```

```
*****
*
* NAME: PRIOR_2OR3
*
* PURPOSE: To execute either one Priority 2 or Priority 3 task.
*
* ENTRY CONDITIONS:      Flag set to say execute either a Priority 2 or
*                        Priority 3 task.
*
* EXIT CONDITIONS:      Either a Priority 2 task or a Priority 3 task has
*                        been executed.
*
*****
```

```
PRIOR_2OR3      BRSET   TRY_PR3,SYSFLAG,PRIOR23_99;If TRY_PR3 set, exit
                BRSET   GO_PR1,SYSFLAG,PRIOR23_20;If GO_PR1 set go PRIOR23
PRIOR23_05      JSR     CHECKBIT0      ;Otherwise try bit 0 in reg
                BRSET   DO_TASK,SYSFLAG,PRIOR23_10;If bit 0 set, go do task
                JSR     SHIFTREG       ;Otherwise, shift reg to the right
                JSR     INCSHIFT       ;Increment shift counter
                BRA     PRIOR23_05     ;Go check next bit
PRIOR23_10      JSR     WRITERAM       ;Go to write procedure in RAM
                JSR     JUMPLONG       ;Go to execute the task
                BCLR    DO_TASK,SYSFLAG ;Clear flag to say done task
                JSR     SHIFTREG       ;Shift reg to the right
                LDA     SHADOWTASK,X   ;Read the temporary location
                BEQ     PRIOR23_15     ;If now empty, go to PRIOR23_10
                JSR     INCSHIFT       ;Otherwise,increment shift counter
                LDA     SHIFTCNT,X     ;Read value of shift counter
                CMP     #$07           ;Done max number of shifts ?
                BLS     PRIOR23_20     ;If not, go to PRIOR23_15
PRIOR23_15      JSR     CLRSHIFT       ;Go clear shift counter
PRIOR23_20      CLRA                    ;Set address pointer back to
                STA     ADD_POINTER    ;start of Priority 1 addresses
                BCLR    GO_PR1,SYSFLAG ;Clear flag, go back to Priority 1
PRIOR23_99      RTS
```

```
*****
*
* NAME: PRIOR_3
*
* PURPOSE:      To examine the Priority 3 task request register
*
*
* ENTRY CONDITIONS:  All the Priority 1 and Priority 2 tasks set to
*                   execute at that time have been completed.
*
* EXIT CONDITIONS:  A flag is set to say either go execute a Priority 3
*                   or go back to check Priority 1 task request register
*
*****
```

```
PRIOR_3      JSR      INC_LEVEL      ;Increment priority level
             LDA      SHIFTCNT,X    ;Read shift counter
             BNE     PRIOR3_05     ;If empty,go update address pointer
             JSR     COPY           ;Copy task req reg to a temp loc
PRIOR3_05    JSR     UPDATE         ;Update address pointer
             ADD     #$20          ;Set pointer to correct section
             STA     ADD_POINTER    ;in the task table
             BCLR   TRY_PR3,SYSFLAG ;Clear flag
             LDX    PR_LEVEL       ;Read the temporary task
             LDA     SHADOWTASK,X   ;request register
             BEQ    PRIOR3_10      ;If empty set flag,go to Priority 1
             BRA    PRIOR3_99      ;Otherwise,go try bit 0
PRIOR3_10    BSET   GO_PR1,SYSFLAG ;
PRIOR3_99    RTS
```




```

*****
*
* NAME: WRITERAM
*
* PURPOSE:      To write a subroutine in RAM so that the scheduler can
*                access a 16-bit address, which is the address of the task in
*                the task table.
*
* ENTRY CONDITIONS:  A flag has been set to say a task is to be executed
*
* EXIT CONDITIONS:  The task corresponding to the bit set in the copy
*                of the task request register has been executed.
*
* DESCRIPTION:      The opcode for "JSR" is copied to memory. Then the
*                high byte and low byte are copied to different
*                memory locations. Then the opcode for "RTS" is
*                copied to memory. We then carry out the subroutine
*                at the address in the task table.
*
*****

```

```

WRITERAM      LDX      ADD_POINTER      ;Read the address in task table
              LDA      #$CD             ;Read the opcode for "JSR"
              STA      JUMPLONG         ;Copy it to location in memory
              LDA      TASKTABLE,X      ;Read the high byte of address
              STA      JUMPLONG+1       ;Copy this to next loc in JUMPLONG
              INCX                      ;Increment address
              STX      ADD_POINTER      ;
              LDA      TASKTABLE,X      ;Read the low byte of the address
              STA      JUMPLONG+2       ;Copy this to next loc in JUMPLONG
              LDA      #$81             ;Read in the opcode for "RTS"
              STA      JUMPLONG+3       ;Copy this at next loc in JUMPLONG

WRITERAM99    RTS

```

```

*****
*
* NAME: COPY
*
* PURPOSE: Makes a copy of the original task request register.
*
*****

```

```

COPY          LDX      PR_LEVEL         ;Read the task request register
              LDA      TASKREQ,X        ;
              STA      SHADOWTASK,X     ;Copy it to a temporary location
              CLR      TASKREQ,X        ;Clear original
              RTS

```



```

*****
*
* NAME: CHECKBIT0
*
* PURPOSE: Checks the first bit in the task request register to see if
*          it is set. If so, a flag is set to say a task is to be
*          executed. If not the address pointer in the task table is
*          updated to point to the next task in the task table.
*
*****

```

```

CHECKBIT0      LDX      PR_LEVEL      ;Copy temporary location
               LDA      SHADOWTASK,X  ;to another temporary location so
               STA      TASKTEMP      ;can do a BRSET command
               BRSET    LSB,TASKTEMP,CHECK05;Bit 0 set,go execute a task
               INC      ADD_POINTER    ;Otherwise update address pointer
               INC      ADD_POINTER    ;to point to next task in task table
               BRA      CHECK99        ;
CHECK05        BSET     DO_TASK,SYSFLAG ;Set flag to say do a task
CHECK99        RTS

```

```

*****
*
* NAME: SHIFTRREG
*
* PURPOSE: This subroutine shifts the copied task request register one
*          place to the right, so that it can search for a bit set in
*          position zero.
*
*****

```

```

SHIFTRREG      LDX      PR_LEVEL      ;Perform logical shift right on
               LDA      SHADOWTASK,X  ;temporary location
               LSRA                      ;
               STA      SHADOWTASK,X  ;
               RTS

```

```

*****
*
* NAME: INCSHIFT
*
* PURPOSE: This routine increments the shift counter of the priority
*          level being operated on. A maximum of 7 shifts is
*          allowed in an 8-bit register, so this controls how many
*          more bits in the register to check for a set bit.
*
*****

```

```

INCSHIFT       LDX      PR_LEVEL      ;
               LDA      SHIFTCNT,X    ;Read shift counter
               INCA                      ;Increment shift counter
               STA      SHIFTCNT,X    ;
               RTS

```

```
*****
*
* NAME: CLRSHIFT
*
* PURPOSE:      To clear the present priority's shift counter before
*               starting work on another.
*
*****
```

```
CLRSHIFT      LDX      PR_LEVEL      ;Clear previous priority shift
              LDA      SHIFTCNT,X    ;counter
              CLRA
              STA      SHIFTCNT,X    ;
              RTS
```

```
*****
*
* NAME: INC_LEVEL
*
* PURPOSE:      Increments the priority level when finished working on the
*               present one.
*
*****
```

```
INC_LEVEL     LDX      PR_LEVEL      ;Increment prority level
              INCX
              STX      PR_LEVEL      ;
              RTS
```

```
*****
*
* NAME: UPDATE
*
* PURPOSE:      Sets the address pointer to the start of the section in
*               the task table which holds the addresses for the tasks
*               in that priority.
*
*****
```

```
UPDATE        LDX      PR_LEVEL      ;
              LDA      SHIFTCNT,X    ;Update address pointer to point
              LDX      #$02          ;to start of correct section
              MUL
              RTS                    ;in the task table
```

```
*****
* TASK TABLE *
*****
```

```

                                ORG      TABLE
TASKTABLE      FDB      TASKA
                FDB      DUMMY           ;Unused entries point to dummy tasks
                FDB      DUMMY
                FDB      TASKD
                FDB      DUMMY
                FDB      DUMMY
                FDB      TASKG
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      TASKL
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY

```

```

FDB      DUMMY
                FDB      DUMMY
                FDB      DUMMY
                FDB      TASKU
                FDB      DUMMY
                FDB      DUMMY
                FDB      TASKX

```

```
*****
*                       * TASKS FOLLOW *                       *
*****
```

```

DUMMY      RTS           ;Dummy task

TASKA      LDA      #$01           ;Example module
                STA      PORTB
                RTS

TASKD      LDA      #$10           ;Load in decimal 16
TASKD_05   STA      NUM_ON_LEDS    ;Store this value in memory
TASKD_10   LDA      NUM_ON_LEDS    ;Read this value
                BNE     TASKD_12    ;If not empty, go to decrement
                BSET    FINAL,APP_FLAG_REG;Set flag to exit after o/p a zero
TASKD_12   BRA      TASKD_15      ;Go to copy vaue back to memory
                DECA     ;Decrement number shown on LEDs

```



```

TASKD_15      STA      NUM_ON_LEDS      ;Copy value back to memory
              LSLA                      ;Shift left
              LSLA                      ;      "
              LSLA                      ;      "
              LSLA                      ;      "
              STA      PORTA             ;Send value to Port A
              LDA      #$25             ;Load in HEX 25
              STA      TIME_ON          ;Store this value in memory
TASKD_20      JSR      DELAY             ;Go to DELAY subroutine
              DEC      TIME_ON          ;Decrement the value in TIME_ON
              LDA      TIME_ON          ;Read the value
              BNE      TASKD_20         ;If <> 0, go back to delay again
              BRSET   FINAL,APP_FLAG_REG,TASKD_99;If flag set, exit
              BRA      TASKD_10         ;Otherwise, go to output next number
TASKD_99      BCLR    FINAL,APP_FLAG_REG;Clear flag before leaving routine
              RTS                       ;Exit

```

```

DELAY        LDA      #$FF             ;Simple delay routine
OUTLP        DECA                      ;Keep looping round OUTLP until
              BNE      OUTLP           ;accumulator is zero
              INC      DELAY_VAR       ;Increment counter
              LDA      DELAY_VAR       ;Read counter value
              CMP      #$CC            ;Does it equal HEX CC
              BLS      DELAY           ;If not go back and start agin
DELAY99      RTS                       ;Otherwise, exit

```

```

TASKG        LDA      #$04             ;Example module
              STA      PORTB
              RTS
TASKL        LDA      #$08             ;Example module
              STA      PORTB
              RTS
TASKU        LDA      #$10             ;Example module
              STA      PORTB
              RTS
TASKX        LDA      #$20             ;Example module
              STA      PORTB
              RTS

```

* SCI INTERRUPT SERVICE ROUTINE *

```

DATA        JSR      GETDATA          ;Checks for received data
              STA      TEMP           ;Store received ASCII data in temp
              AND      #$0F           ;Convert LSB of ASCII char to HEX
              ORA      #$30           ;$3(LSB) = "LSB"
              CMP      #$39           ;3A-3F need to change to 41-46

```

```

        BLS      ARN1      ;Branch if 30-39 OK
        ADD      #7        ;Add offset
ARN1    STA      TEMPLO    ;Store LSB of HEX in TEMPLO
        LDA      TEMP      ;Read the original ASCII data
        LSRA     ;Shift right 4 bits
        LSRA     ;
        LSRA     ;
        LSRA     ;
        ORA      #$30     ;ASCII for N is $3N
        CMP      #$39     ;3A-3F need to change to 41-46
        BLS      ARN2     ;Branch if 30-39
        ADD      #7        ;Add offset
ARN2    STA      TEMPHI    ;MS nibble of HEX to TEMPHI
        LDA      #$0D     ;Load HEX value for "<LF>"
        BSR      SENDATA  ;Line feed
        LDA      #$24     ;Load HEX value "$"
        BSR      SENDATA  ;Print dollar sign
        LDA      TEMPHI    ;Get high half of HEX value
        BSR      SENDATA  ;Print
        LDA      TEMPLO    ;Get low half of HEX value
        BSR      SENDATA  ;Print

        CLRX     ;These seven lines demonstrate
        CLR      SETTASKS ;how flags are set in the Priority 1
        BSET     0,SETTASKS ;(X=0) task request register in order
        BSET     1,SETTASKS ;to set the corresponding tasks to
        BSET     2,SETTASKS ;run. SETTASKS is used as a temporary
        LDA      SETTASKS ;register since the operation
        STA      TASKREQ,X ;BSET 0,TASKREQ,0, for instance,
        RTI      ;cannot be done.

GETDATA BRCLR    5,SCSR,GETDATA ;RDRF = 1 ?
        LDA      SCDAT      ;OK, get data
        RTS

SENDATA BRCLR    7,SCSR,SENDATA ;TDRE = 1 ?
        STA      SCDAT      ;OK, send data
        RTS

SPI      RTI
TIRQ     RTI
IRQ      RTI
SWI      RTI

ORG      VECTOR

FDB      SPI      ;SPI interrupt vector
FDB      DATA    ;SCI interrupt vector
FDB      TIRQ     ;Timer interrupt vector
FDB      IRQ      ;External interrupt vector
FDB      SWI      ;Software interrupt vector
FDB      SCHED05  ;Reset interrupt vector

```



```

*****
*
*                                     Copyright (c) 1993 *
*
*                                     LISTING 2
*                                     *****
*
* File name:  TIME_BASED.ASM
*
* Purpose: To co-ordinate the timing of exection of different
*          modules using the internal Free-Running Counter along
*          with the Output Compare or the Core Timer along with the
*          Core Timer Overflow funtion.
*          If the free-running counter is used to co-ordinate the
*          timing the tasks, which ever one it is, will be executed
*          every 4ms.
*          If the Core Timer is used, the tasks will be executed
*          every 5.12ms.
*
* Target device: 68HC705L4
*
* Memory usage: ROM: 236 BYTES      RAM:  8 BYTES
*
* Assembler: IASM05 - Integrated Assembler  Version :  3.02
*
* Description: Using the different timing registers inside the MCU
*              and setting up separate counters, the time intervals
*              between the execution of the different tasks can be
*              controlled using the Free-Running Counter along with
*              the Output Compare function or the Core Timer Counter
*              Register along with the Core Timer Overflow Flag.
*              If the programmable timer is used, an interrupt will
*              occur when the value in the Ouput Compare Register
*              equals the value of the Free-Running Counter.
*              If the Core Timer is used, an interrupt will occur
*              when the Core Timer Counter register rolls over from
*              $FF to $00.
*              In this program it is at every 10 interrupts that a
*              task is executed.
*
*
* SUBROUTINES
* -----
*
* Author: Joanne Santangeli Location:EKB      Created : 17 Jun 93
*                                         Last modified : 26 Aug 93
*
* Update history
* Rev   Author   Date   Description of change
* ---   -
* 0.1   JS       26/9/93 INITIAL RELEASE
*
*****

```



```

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```

```

*****
* PORT DECLARATIONS *
*****

```

```

PORTB      EQU      $01      ;Direct address - Port C
DDR        EQU      $05      ;Data direction register - Port C

```

```

*****
* MEMORY *
*****

```

```

ROM        EQU      $2100    ;User ROM area in the MC68HC05L4
RAM        EQU      $0050    ;RAM area in the MC68HC05L4
VECTOR     EQU      $3FF6    ;Start of vector address

```

```

*****
* CORE TIMER DECLARATIONS *
*****

```

```

TS_CTCSR   EQU      $08      ;Core Timer Control & Status Register
                                     ;CTOF,RTIF,CTOFE,RTIE,-,-,RT1,RT0
TV_CTCR    EQU      $09      ;Core Timer Counter Register

```

```

*****
* PROGRAMMABLE TIMER DECLARATIONS *
*****

```

```

TV_TCHA    EQU      $10      ;Timer A Counter Register (High)
TV_TCLA    EQU      $11      ;Timer A Counter Register (Low)
TV_ACHA    EQU      $12      ;Timer A Alt Counter Register (high)
TV_ACLA    EQU      $13      ;Timer A Alt Counter Register (low)
TV_TCRA    EQU      $0A      ;Timer A Control Register

```




```

TV_TSRA      EQU      $0B      ;Timer A Status Register
TV_ICHA      EQU      $0C      ;Input Capture A Register (High)
TV_ICLA      EQU      $0D      ;Input Capture A Register (Low)
TV_OCHA      EQU      $0E      ;Output Compare A Register (High)
TV_OCLA      EQU      $0F      ;Output Compare A Register (Low)

```

```

*****
* THE FOLLOWING ARE USED TO DETERMINE THE TASK TIMING *
*****

```

```

TW_OCPER     EQU      $C8      ;Output Compare Period set to 200
TW_TSPER     EQU      $0A      ;Time Slice Period set to 10

```

```

*****
* VARIABLE DECLARATIONS *
*****

```

```

                                ORG      RAM

TV_TSCP      RMB      1        ;Programmable Timer Slice Counter
TV_TSCC      RMB      1        ;Core Timer Time Slice Counter
TV_TSKCP     RMB      1        ;Programmable Timer Task Counter
TV_TSKCC     RMB      1        ;Core Timer Task Counter
TV_TSKC      RMB      1        ;Task Counter used to find task
TV_OPT       RMB      1        ;Option whether Core or Programmable
                                ;Timer is used
TV_DTASK     RMB      1        ;To check if a task is to be carried
                                ;out at that interrupt
TV_STORE     RMB      1        ;Bit 1 of this variable is clear or
                                ;set depending on if a timer
                                ;interrupt has occurred or not when
                                ;using the Programmable Timer

```

```

                                ORG      ROM      ;Absolute address label for this
                                ;section of ROM (MC68HC705L4)

```

```

*****
* MAIN PROGRAM *
*****

```

```

T_SCHD05     BSET     0,TV_OPT   ;Set a flag to determine which timer
                LDA     #$FF     ;Set PB7-PB0 as outputs
                STA     DDRB     ;
                CLR     PORTB    ;Clear Port B
                CLR     TV_TSKCC ;Clear Core Timer Task Counter
                CLR     TV_TSKCP ;Clear Programmable Timer Task Counter

T_SCHD10     BRSET   0,TV_OPT,T_SCHD99;Branch to choose the
                JMP     T_CORE05  ;Core Timer or the
T_SCHD99     JMP     T_PROG05    ;Programmable Timer

```

```

*****
* SUBROUTINES *
*****

*****
*
* Name: T_PROG05
*
* Subroutine: Performs co-ordination of task execution using the
*             Output Compare function of the Programmable Timer.
*
* Stack space used(bytes): 2
*
* Subroutines used: T_PRIN05,T_TASK05
*
* External variables used: TW_OCPER,TW_TSPER,TV_TSKCP,TV_OPT
*
* Description: This subroutine initially sets the first Output
*             Compare. It then waits for a timer interrupt to which
*             it seivces with an interrupt sevice routine. The
*             Output Compare is then updated and the Ouput Compare
*             flag is cleared. The routine then jumps to a
*             subroutine to find the particular task and
*             carries it out.
*
*****

T_PROG05      LDA      TV_TSRA      ;Clear Timer Status Register
              LDA      TV_OCLA      ;Compare flag cleared
              LDA      TV_TCLA      ;Timer overflow cleared
              LDA      TV_ICLA      ;Input capture flag cleared
              CLR      TV_OCHA      ;Clear Output Compare (High)
              CLR      TV_OCLA      ;Clear Output Compare (Low)
              CLR      TV_TSCP      ;Clear Time Slice Counter
              LDA      #$40         ;Load ACCA with 01000000
              STA      TV_TCRA      ;Set Output Compare Interrupt enable
PROG10        CLI
PROG15        BRSET   0,TV_DTASK,PROG20;If bit is set,go to task routine
              BRA     PROG15        ;If not set,wait for next interrupt
PROG20        JSR     T_TASK05      ;Jump to task routine
              BCLR   0,TV_DTASK     ;Clear task bit
PROG99        BRA     PROG10        ;Go wait for next interrupt

```

```

*****
*
* Name:T_CORE05
*
* Subroutine: Performs co-ordination of task execution using the
*             Core Timer Counter Register along with the Core Timer
*             overflow flag.
*
* Stack space used(bytes): 4
*
* Subroutines used: T_CRIN05,T_TASK05
*
* External variables used: TW_TSPER,T_TSKCC
*
* Description: This subroutine initially sets the Core Timer Overflow
*             Enable. It then waits for an interrupt (ie. when Core
*             Timer Counter Register rolls over frrom $FF to $00 )
*             After returning from servicing the interrupt, it
*             checks to see if the Task Counter has been written to
*             If so, another subroutine is called to find which task
*             is to be executed and then this particular task is
*             carried out. The routine then waits for the next
*             interrupt.
*
*****

```

```

T_CORE05      CLR      TV_TSCC      ;Clear Core Time Slice Counter
              CLRA      ;Clear ACCA
              STA      TS_CTCSR    ;Verify Overflow Flag is clear
              LDA      #$23       ;Load ACCA with 00100011
              STA      TS_CTCSR    ;Set Core Timer Overflow Enable,
                                  ;RT1 & RT0
CORE10        WAIT      ;Wait for Interrupt
              BRSET    0,TV_DTASK,CORE20;If task bit set,go to task routine
              BRA      CORE10     ;If not,go wait for next interrupt
CORE20        JSR      T_TASK05    ;Jump to task routine
              BCLR     0,TV_DTASK  ;Clear task bit
              BRA      CORE10     ;Go to wait for next interrupt

```

```

*****
* INTERRUPT SERVICE ROUTINES *
*****

*****
*
* Name: T_PRIN05
*
* Subroutine: Checks if a task is to be carried out at this
*             interrupt and updates the Output Compare register.
*
* Stack space used(bytes): 4
*
* Subroutines used: none
*
* External variables used: TW_TSPER,,TV_TSKCP,TW_OCPER
*
* Description: This interrupt sevice routine finds out if a task
*              by incrementing a Time Slice Counter. Each time the
*              interrupt sevice routine is called the counter is
*              incremented. Only when this counter equals ten, is
*              a task carried out.
*              After deciding whether a task is to be carried out,
*              the Output Compare Register is updated, ready to
*              for another interrupt and the Output Compare Flag
*              is cleared.
*
*****

T_PRIN05      BRCLR    6,TV_TSRA,PRIN99;Checks for Output Compare Flag
              INC     TV_TSCP      ;Inrement Time Slice Counter
              LDA     TV_TSCP      ;Read the Time Slice Counter
              CMP     #TW_TSPER    ;Compare contents of ACCA with 10
              BLO    PRIN10        ;If < 10, branch back to T_SCHED10
              CLR     TV_TSCP      ;If = 10, clear Time Slice Counter
              INC     TV_TSKCP     ;Increment Task Counter
              BSET    0,TV_DTASK    ;Set task bit
PRIN10        LDA     TV_OCLA      ;Read high byte of Output Compare
              ADD     #TW_OCPER    ;Load #200 into ACCA
              STA     TV_OCLA      ;Store in Output Compare (Low)
              LDA     TV_OCHA      ;Read Output Compare (High)
              ADC     #$00         ;Add the contents of the Carry bit
              STA     TV_OCHA      ;Store at Output Compare (High)
              LDA     TV_OCLA      ;Read Output Compare (low)
              STA     TV_OCLA      ;Write back to Output Compare (low)
PRIN99        RTI                ;Return from Timer Interrupt

```



```

*****
*
* Name:T_CRIN05
*
* Subroutine: This routine finds if a tassk is to be carried out at
*             this interrupt. It also clears the Core Timer Overflow
*             flag.
*
* Stack space used (bytes) : 4
*
* Subroutines used: none
*
* External varaibles used: TW_TSPER,TV_TSKCC
*
* Description: Initially finds if Time Slice Counter equals
*             Time Slice Period. If so, the Slice counter is cleared
*             and the Task Counter is incremented. The Core Timer
*             Overflow Flag is then reset.
*
*****

```

```

T_CRIN05      INC      TV_TSCC      ;Increment Core Time Slice Counter
              LDA      TV_TSCC      ;Read Time Slice Counter
              CMP      #TW_TSPER    ;Compare this to Time Slice Period
              BLO      CRIN10       ;If < 10,go to update status register
              CLR      TV_TSCC      ;If = 10, clear Time Slice Counter
              INC      TV_TSKCC     ;Increment Core Task Counter
              BSET     0,TV_DTASK    ;Set task bit
CRIN10        LDA      #$23         ;Load ACCA with 00100011
              STA      TS_CTCSR     ;Clear Overflow Flag
              RTI      ;Return from Interrupt

```

```

*****
*
* Name: T_TASK05
*
* Subroutine: Routine to find out which task is to be done and
*             carries it out accordingly.
*
* Stack space used(bytes): 4
*
* Subroutines used: none
*
* External varaibles used: TV_TSKCC,TV_TSKCP
*
* Description: Depending on which bit contains a zero in the Task
*             Counter determines which task is to be carried out.
*             The task to be executed detected and carried out.
*             Each example task shown here each writes a logic
*             high to a different pin at Port B to demonstrate how
*             the tasks are scheduled.
*
*****

```



```

*****
* TASK TABLE *
*****

T_TASK05      LDA      TV_TSKCC      ;Read Core Timer Task Counter
              BNE      TASK15      ;Check if Core Timer or
TASK10        LDA      TV_TSKCP      ;Programmable has been used
TASK15        STA      TV_TSKC      ;Stores task in memory
              BRCLR    0,TV_TSKC,TASK20 ;If bit 0 clear,go to Task A
              BRCLR    1,TV_TSKC,TASK25 ;If bit 1 clear,go to Task B
              BRCLR    2,TV_TSKC,TASK30 ;If bit 2 clear,go to Task C
              BRCLR    3,TV_TSKC,TASK35 ;If bit 3 clear,go to Task D
              BRCLR    4,TV_TSKC,TASK40 ;If bit 4 clear,go to Task E
              BRCLR    5,TV_TSKC,TASK45 ;If bit 5 clear,go to Task F
              BRCLR    6,TV_TSKC,TASK50 ;If bit 6 clear,go to Task G
              BRCLR    7,TV_TSKC,TASK55 ;If bit 7 clear,go to Task H
              CLRA      ;Clear Port B if Task
              STA      PORTB      ;Counter at #$FF
              RTS      ;Return from routine
TASK20        JSR      T_20      ;Jump to first module
              RTS      ;
TASK25        JSR      T_25      ;Jump to second module
              RTS      ;
TASK30        JSR      T_30      ;Jump to third module
              RTS      ;
TASK35        JSR      T_35      ;Jump to fourth module
              RTS      ;
TASK40        JSR      T_40      ;Jump to fifth module
              RTS      ;
TASK45        JSR      T_45      ;Jump to sixth module
              RTS      ;
TASK50        JSR      T_50      ;Jump to seventh module
              RTS      ;
TASK55        JSR      T_55      ;Jump to eighth module
              RTS      ;

```

```

*****
* TASKS FOLLOW *
*****

T_20          LDA    #$01                ;Example module
              STA    PORTB
              RTS

T_25          LDA    #$02                ;Example module
              STA    PORTB
              RTS

T_30          LDA    #$04                ;Example module
              STA    PORTB
              RTS

T_35          LDA    #$08                ;Example module
              STA    PORTB
              RTS

T_40          LDA    #$10                ;Example module
              STA    PORTB
              RTS

T_45          LDA    #$20                ;Example module
              STA    PORTB
              RTS

T_50          LDA    #$40                ;Example module
              STA    PORTB
              RTS

T_55          LDA    #$80                ;Example module
              STA    PORTB
              RTS

IRQ           RTI
SWI           RTI

              ORG    VECTOR

              FDB    T_PRIN05            ;Programmable Interrupt Vector
              FDB    T_CRIN05            ;Core Timer Interrupt Vector
              FDB    IRQ                 ;Hardware Int
              FDB    SWI                 ;Software Int
              FDB    T_SCHD05            ;RESET Interrupt Vector

```

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