CCS C Compiler Manual

PCB / PCM / PCH

October 2015

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OVERVIEW

C Compiler

PCB, PCM and PCH Overview

The PCB, PCM, and PCH are separate compilers. PCB is for 12-bit opcodes, PCM is for 14-bit opcodes, and PCH is for 16-bit opcode PIC® microcontrollers. Due to many similarities, all three compilers are covered in this reference manual. Features and limitations that apply to only specific microcontrollers are indicated within. These compilers are specifically designed to meet the unique needs of the PIC® microcontroller. This allows developers to quickly design applications software in a more readable, high-level language.

IDE Compilers (PCW, PCWH and PCWHD) have the exclusive C Aware integrated development environment for compiling, analyzing and debugging in real-time. Other features and integrated tools can be viewed here.

When compared to a more traditional C compiler, PCB, PCM, and PCH have some limitations. As an example of the limitations, function recursion is not allowed. This is due to the fact that the PIC® has no stack to push variables onto, and also because of the way the compilers optimize the code. The compilers can efficiently implement normal C constructs, input/output operations, and bit twiddling operations. All normal C data types are supported along with pointers to constant arrays, fixed point decimal, and arrays of bits.

Installation

Insert the CD ROM, select each of the programs you wish to install and follow the on-screen instructions.

If the CD does not auto start run the setup program in the root directory.

For help answering the version questions see the "Directories" Help topic.

Key Questions that may come up:

Keep Settings- Unless you are having trouble select this

Link Compiler Extensions- If you select this the file extensions like .c will start the compiler IDE when you double click on files with that extension. .hex files start the CCSLOAD program. This selection can be change in the IDE.

Install MP LAB Plug In- If you plan to use MPLAB and you don't select this you will need to download and manually install the Plug-In.

Install ICD2, ICD3...drivers-select if you use these microchip ICD units.

Delete Demo Files- Always a good idea

Install WIN8 APP- Allows you to start the IDE from the WIN8 Start Menu.

Technical Support

Compiler, software, and driver updates are available to download at:
http://www.ccsinfo.com/download

Compilers come with 30 or 60 days of download rights with the initial purchase. One year maintenance plans may be purchased for access to updates as released.

The intent of new releases is to provide up-to-date support with greater ease of use and minimal, if any, transition difficulty.

To ensure any problem that may occur is corrected quickly and diligently, it is recommended to send an email to: support@ccsinfo.com or use the Technical Support Wizard in PCW. Include the version of the compiler, an outline of the problem and attach any files with the email request. CCS strives to answer technical support timely and thoroughly.

Technical Support is available by phone during business hours for urgent needs or if email responses are not adequate. Please call 262-522-6500 x32.

Directories

The compiler will search the following directories for Include files.

- Directories listed on the command line
- Directories specified in the .CCSPJT file
- The same directory as the source.directories in the ccsc.ini file

By default, the compiler files are put in C:\Program Files\PICC and the example programs are in \PICC\EXAMPLES. The include files are in PICC\drivers. The device header files are in PICC\devices.

The compiler itself is a DLL file. The DLL files are in a DLL directory by default in \PICC\DLL.

It is sometimes helpful to maintain multiple compiler versions. For example, a project was tested with a specific version, but newer projects use a newer version. When installing the compiler you are prompted for what version to keep on the PC. IDE users can change versions using Help>about and clicking "other versions." Command Line users use start>all programs>PIC-C>compiler version.

Two directories are used outside the PICC tree. Both can be reached with start>all programs>PIC-C.

1.) A project directory as a default location for your projects. By default put in "My Documents." This is a good place for VISTA and up.

2.) User configuration settings and PCWH loaded files are kept in %APPDATA%\PICC

File Formats

.c	**This is the source file containing user C source code.**
.h	These are standard or custom header files used to define pins, register, register bits, functions and preprocessor directives.
.pjt	This is the older pre- Version 5 project file which contains information related to the project.
.ccspjt	This is the project file which contains information related to the project.
.lst	This is the listing file which shows each C source line and the associated assembly code generated for that line. The elements in the .LST file may be selected in PCW under Options>Project>Output Files **CCS Basic** — **Standard assembly instructions** **with Opcodes** — Includes the HEX opcode for each instruction **Old Standard** **Symbolic** — Shows variable names instead of addresses
.sym	This is the symbol map which shows each register location and what program variables are stored in each location.
.sta	The statistics file shows the RAM, ROM, and STACK usage. It provides information on the source codes structural and textual complexities using Halstead and McCabe metrics.
.tre	The tree file shows the call tree. It details each function and what functions it calls along with the ROM and RAM usage for each function.
.hex	The compiler generates standard HEX files that are compatible with all programmers. The compiler can output 8-bet hex, 16-bit hex, and binary files.
.cof	This is a binary containing machine code and debugging information. The debug files may be output as Microchip .COD file for MPLAB 1-5, Advanced Transdata .MAP file, expanded .COD file for CCS debugging or MPLAB 6 and up .xx .COF file. All file formats and extensions may be selected via Options File Associations option in Windows IDE.
.cod	This is a binary file containing debug information.
.rtf	The output of the Documentation Generator is exported in a Rich Text File format which can be viewed using the RTF editor or Wordpad.
.rvf	The Rich View Format is used by the RTF Editor within the IDE to view the Rich Text File.
.dgr	The .DGR file is the output of the flowchart maker.
.esym .xsym	These files are generated for the IDE users. The file contains Identifiers and Comment information. This data can be used for automatic documentation generation and for the IDE helpers.
.o	Relocatable object file
.osym	This file is generated when the compiler is set to export a relocatable object file. This file is a .sym file for just the one unit.
.err	Compiler error file
.ccsload	used to link Windows 8 apps to CCSLoad

.ccssiow	used to link Windows 8 apps to Serial Port Monitor

Invoking the Command Line Compiler

The command line compiler is invoked with the following command:

```
     CCSC    [options]    [cfilename]
```

Valid options:

+FB	**Select PCB (12 bit)**	**-D**	**Do not create debug file**
+FM	Select PCM (14 bit)	+DS	Standard .COD format debug file
+FH	Select PCH (PIC18XXX)	+DM	.MAP format debug file
+Yx	Optimization level x (0-9)	+DC	Expanded .COD format debug file
		+DF	Enables the output of an COFF debug file.
+FS	Select SXC (SX)	+EO	Old error file format
+ES	Standard error file	-T	Do not generate a tree file
+T	Create call tree (.TRE)	-A	Do not create stats file (.STA)
+A	Create stats file (.STA)	-EW	Suppress warnings (use with +EA)
+EW	Show warning messages	-E	Only show first error
+EA	Show all error messages and all warnings	+EX	Error/warning message format uses GCC's "brief format" (compatible with GCC editor environments)

The xxx in the following are optional. If included it sets the file extension:

+LNxxx	**Normal list file**	**+O8xxx**	**8-bit Intel HEX output file**
+LSxxx	MPASM format list file	+OWxxx	16-bit Intel HEX output file
+LOxxx	Old MPASM list file	+OBxxx	Binary output file
+LYxxx	Symbolic list file	-O	Do not create object file
-L	Do not create list file		
+P	Keep compile status window up after compile		
+Pxx	Keep status window up for xx seconds after compile		
+PN	Keep status window up only if there are no errors		
+PE	Keep status window up only if there are errors		
+Z	Keep scratch files on disk after compile		
+DF	COFF Debug file		
I+="..."	Same as I="..." Except the path list is appended to the current list		
I="..."	Set include directory search path, for example: I="c:\picc\examples;c:\picc\myincludes" If no I= appears on the command line the .PJT file will be used to supply the include file paths.		
-P	Close compile window after compile is complete		
+M	Generate a symbol file (.SYM)		

-M	Do not create symbol file
+J	Create a project file (.PJT)
-J	Do not create PJT file
+ICD	Compile for use with an ICD
#xxx="yyy"	Set a global #define for id xxx with a value of yyy, example: #debug="true"
+Gxxx="yyy"	Same as #xxx="yyy"
+?	Brings up a help file
-?	Same as +?
+STDOUT	Outputs errors to STDOUT (for use with third party editors)
+SETUP	Install CCSC into MPLAB (no compile is done)
sourceline=	Allows a source line to be injected at the start of the source file. Example: CCSC +FM myfile.c sourceline="#include <16F887.h>"
+V	Show compiler version (no compile is done)
+Q	Show all valid devices in database (no compile is done)

A / character may be used in place of a + character. The default options are as follows:
+FM +ES +J +DC +Y9 -T -A +M +LNlst +O8hex -P -Z

If @filename appears on the CCSC command line, command line options will be read from the specified file. Parameters may appear on multiple lines in the file.

If the file CCSC.INI exists in the same directory as CCSC.EXE, then command line parameters are read from that file before they are processed on the command line.

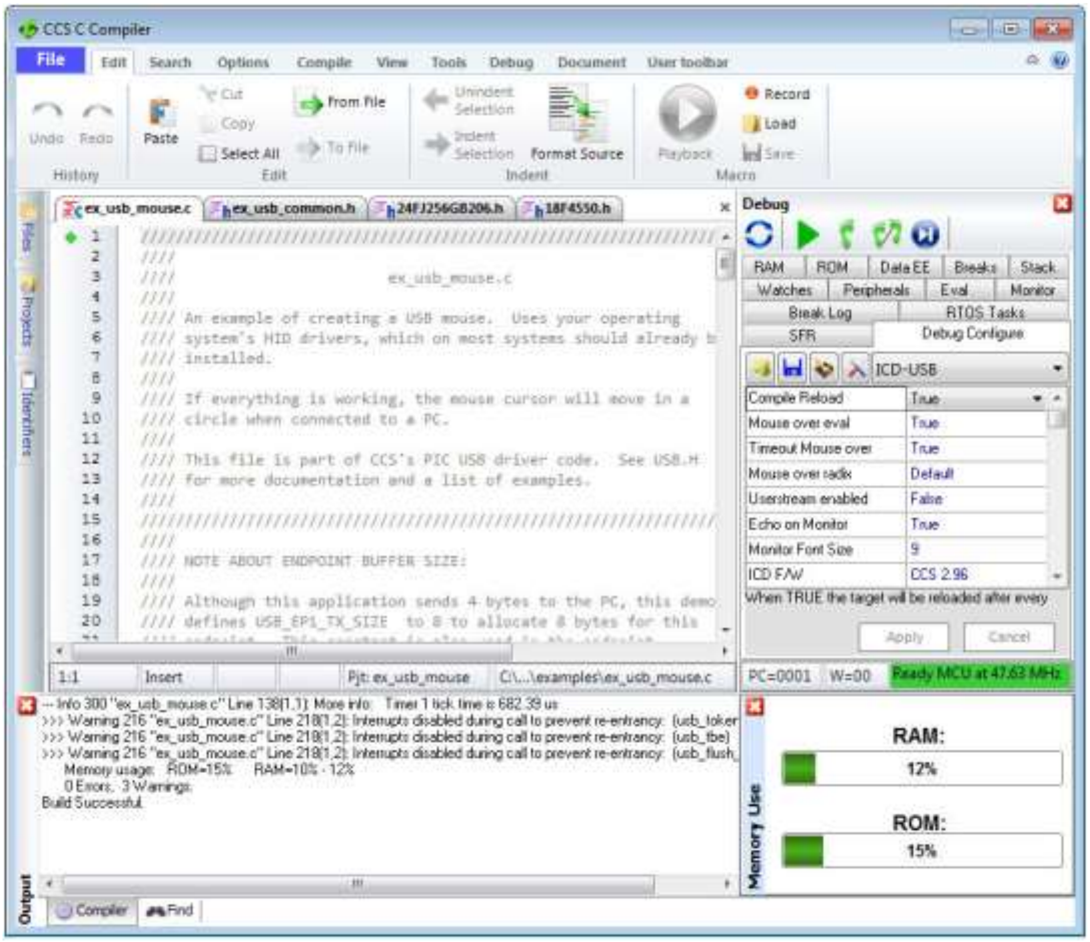
Examples:

```
CCSC +FM C:\PICSTUFF\TEST.C
 CCSC +FM +P +T TEST.C
```

PCW Overview

The PCW IDE provides the user an easy to use editor and environment for developing microcontroller applications. The IDE comprises of many components, which are summarized below. For more information and details, use the Help>PCW in the compiler..

Many of these windows can be re-arranged and docked into different positions.



```
//////////////////////////////////////////////////////////////////////
////
////                         ex_usb_mouse.c
////
//// An example of creating a USB mouse.  Uses your operating
//// system's HID drivers, which on most systems should already b
//// installed.
////
//// If everything is working, the mouse cursor will move in a
//// circle when connected to a PC.
////
//// This file is part of CCS's PIC USB driver code.  See USB.H
//// for more documentation and a list of examples.
////
//////////////////////////////////////////////////////////////////////
////
//// NOTE ABOUT ENDPOINT BUFFER SIZE:
////
//// Although this application sends 4 bytes to the PC, this demo
//// defines USB_EP1_TX_SIZE  to 8 to allocate 8 bytes for this
```

1:1 | Insert | Pjt: ex_usb_mouse | C:\...\examples\ex_usb_mouse.c

Compile Reload	True
Mouse over eval	True
Timeout Mouse over	True
Mouse over radix	Default
Userstream enabled	False
Echo on Monitor	True
Monitor Font Size	9
ICD F/W	CCS 2.96

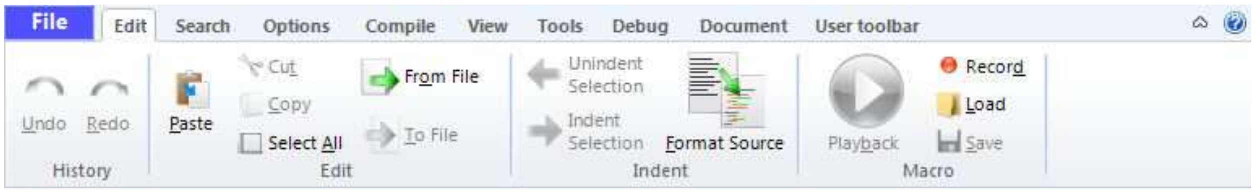
When TRUE the target will be reloaded after every

PC=0001 W=00 Ready MCU at 47.63 MHz

```
--- Info 300 "ex_usb_mouse.c" Line 138(1,1): More info:   Timer 1 tick time is 682.39 us
>>> Warning 216 "ex_usb_mouse.c" Line 218(1,2): Interrupts disabled during call to prevent re-entrancy:  (usb_toker
>>> Warning 216 "ex_usb_mouse.c" Line 218(1,2): Interrupts disabled during call to prevent re-entrancy:  (usb_tbe)
>>> Warning 216 "ex_usb_mouse.c" Line 218(1,2): Interrupts disabled during call to prevent re-entrancy:  (usb_flush_
      Memory usage:   ROM=15%      RAM=10% - 12%
      0 Errors,  3 Warnings.
Build Successful.
```

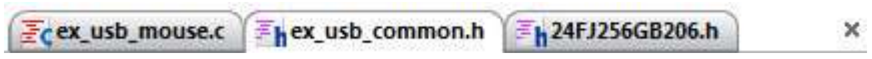
Menu

All of the IDE's functions are on the main menu. The main menu is divided into separate sections, click on a section title ('Edit', 'Search', etc) to change the section. Double clicking on the section, or clicking on the chevron on the right, will cause the menu to minimize and take less space.

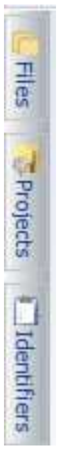


Editor Tabs

All of the open files are listed here. The active file, which is the file currently being edited, is given a different highlight than the other files. Clicking on the X on the right closes the active file. Right clicking on a tab gives a menu of useful actions for that file.



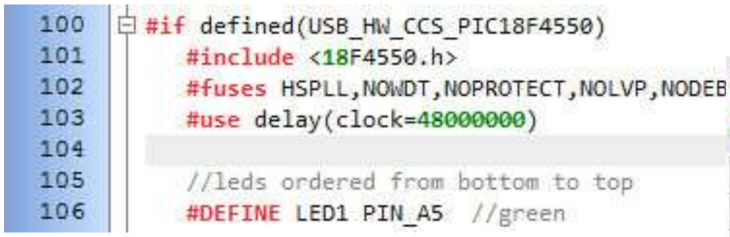
Slide Out Windows



'Files' shows all the active files in the current project. 'Projects' shows all the recent projects worked on. 'Identifiers' shows all the variables, definitions, prototypes and identifiers in your current project.

Editor

The editor is the main work area of the IDE and the place where the user enters and edits source code. Right clicking in this area gives a menu of useful actions for the code being edited.

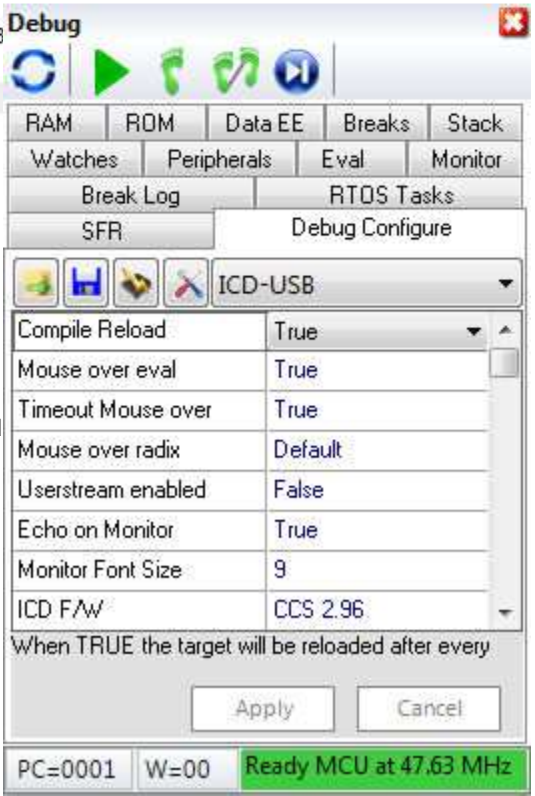


```
#if defined(USB_HW_CCS_PIC18F4550)
   #include <18F4550.h>
   #fuses HSPLL,NOWDT,NOPROTECT,NOLVP,NODEB
   #use delay(clock=48000000)

   //leds ordered from bottom to top
   #DEFINE LED1 PIN_A5   //green
```

Debugging Windows

Debugger control is done in the debugging windows. These windows allow you set breakpoints, single step, watch variables and more.



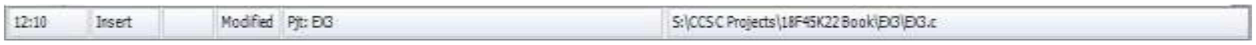
Compile Reload	True
Mouse over eval	True
Timeout Mouse over	True
Mouse over radix	Default
Userstream enabled	False
Echo on Monitor	True
Monitor Font Size	9
ICD F/W	CCS 2.96

When TRUE the target will be reloaded after every

PC=0001 W=00 Ready MCU at 47.63 MHz

Status Bar

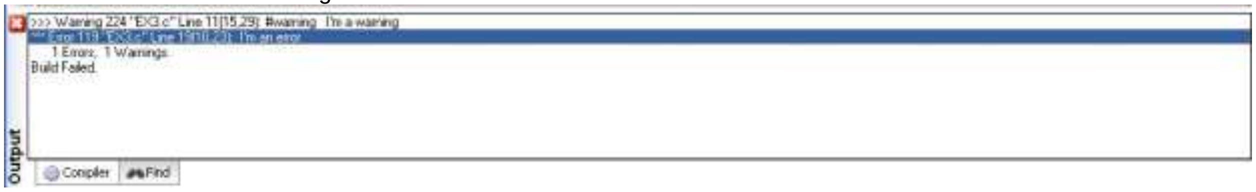
The status bar gives the user helpful information like the cursor position, project open and file being edited.



```
12:10   Insert      Modified   Pjt: EX3      S:\CCS C Projects\18F45K22 Book\EX3\EX3.c
```

Output Messages

Output messages are displayed here. This includes messages from the compiler during a build, messages from the programmer tool during programming or the results from find and searching.



```
>>> Warning 224 "EX3.c" Line 11(15,29): #warning  I'm a warning
*** Error 119 "EX3.c" Line 1[illegible] I'm an error
      1 Errors,  1 Warnings.
Build Failed.
```

PROGRAM SYNTAX

Overall Structure

A program is made up of the following four elements in a file:
Comment
Pre-Processor Directive
Data Definition
Function Definition
    Statements
    Expressions

Every C program must contain a main function which is the starting point of the program execution. The program can be split into multiple functions according to the their purpose and the functions could be called from main or the sub-functions. In a large project functions can also be placed in different C files or header files that can be included in the main C file to group the related functions by their category. CCS C also requires to include the appropriate device file using #include directive to include the device specific functionality. There are also some preprocessor directives like #fuses to specify the fuses for the chip and #use delay to specify the clock speed. The functions contain the data declarations,definitions,statements and expressions. The compiler also provides a large number of standard C libraries as well as other device drivers that can be included and used in the programs. CCS also provides a large number of built-in functions to access the various peripherals included in the PIC microcontroller.

Comment

Comments – Standard Comments
A comment may appear anywhere within a file except within a quoted string. Characters between /* and */ are ignored. Characters after a // up to the end of the line are ignored.

Comments for Documentation Generator
The compiler recognizes comments in the source code based on certain markups. The compiler recognizes these special types of comments that can be later exported for use in the documentation generator. The documentation generator utility uses a user selectable template to export these comments and create a formatted output document in Rich Text File Format. This utility is only available in the IDE version of the compiler. The source code markups are as follows.

Global Comments
These are named comments that appear at the top of your source code. The comment names are case sensitive and they must match the case used in the documentation template.
For example:
```
//*PURPOSE This program implements a Bootloader.
//*AUTHOR John Doe
```

A '//' followed by an * will tell the compiler that the keyword which follows it will be the named comment. The actual comment that follows it will be exported as a paragraph to the documentation generator.
Multiple line comments can be specified by adding a : after the *, so the compiler will not concatenate the comments that follow. For example:
```
/**:CHANGES
    05/16/06   Added PWM loop
    05/27.06   Fixed Flashing problem
*/
```

Variable Comments

A variable comment is a comment that appears immediately after a variable declaration. For example:

```
int seconds; // Number of seconds since last entry
long day,     // Current day of the month,   /* Current Month */
long year;      // Year
```

Function Comments

A function comment is a comment that appears just before a function declaration. For example:

```
// The following function initializes outputs
void function_foo()
{
        init_outputs();
}
```

Function Named Comments

The named comments can be used for functions in a similar manner to the Global Comments. These comments appear before the function, and the names are exported as-is to the documentation generator.

For example:

```
//*PURPOSE This function displays data in BCD format
void display_BCD( byte n)
{
        display_routine();
 }
```

Trigraph Sequences

The compiler accepts three character sequences instead of some special characters not available on all keyboards as follows:

Sequence	Same as
??=	#
??(	[
??/	\
??)	]
??'	^
??<	{
??!	|
??>	}
??-	~

Multiple Project Files

When there are multiple files in a project they can all be included using the #include in the main file or the sub-files to use the automatic linker included in the compiler. All the header files, standard libraries and driver files can be included using this method to automatically link them.

For example: if you have main.c, x.c, x.h, y.c,y.h and z.c and z.h files in your project, you can say in:

main.c	**#include <device header file>**
	#include<x.c>
	#include<y.c>
	#include <z.c>

x.c	#include <x.h>
y.c	#include <y.h>
z.c	#include <z.h>

In this example there are 8 files and one compilation unit. Main.c is the only file compiled.

Note that the #module directive can be used in any include file to limit the visibility of the symbol in that file.

To separately compile your files see the section "multiple compilation units".

Multiple Compilation Units

Multiple Compilation Units are only supported in the IDE compilers, PCW, PCWH, PCHWD and PCDIDE.   When using multiple compilation units, care must be given that pre-processor commands that control the compilation are compatible across all units. It is recommended that directives such as #FUSES, #USE and the device header file all put in an include file included by all units. When a unit is compiled it will output a relocatable object file (*.o) and symbol file (*.osym).

There are several ways to accomplish this with the CCS C Compiler. All of these methods and example projects are included in the MCU.zip in the examples directory of the compiler.

Full Example Program

Here is a sample program with explanation using CCS C to read adc samples over rs232:

```
///////////////////////////////////////////////
/////////
///  This program displays the min and max of
30,   ///
///  comments that explains what the program
does,  ///
///  and A/D samples over the RS-232
interface.     ///
///////////////////////////////////////////////
/////////

#include <16F887.h>                          //
preprocessor directive that
                                             //
selects the chip PIC16F887
```

```
#fuses NOPROTECT                            //
Code protection turned off
#use delay(crystal=20mhz)                   //
preprocessor directive that
                                            //
specifies the clock type and speed
#use rs232(baud=9600, xmit=PIN_C6, rcv=PIN_C7) //
preprocessor directive that
                                            //
includes the rs232 libraries

void main() {                               //
main function
   int i, value, min, max;                  //
local variable declaration
   printf("Sampling:");                     //
printf function included in the
                                            //
RS232 library
   setup_port_a( ALL_ANALOG );              //
A/D setup functions- built-in
   setup_adc( ADC_CLOCK_INTERNAL );         //
Internal clock always works
   set_adc_channel( 0 );                    //
Set channel to AN0
   do {                                     // do
forever statement
      min=255;
      max=0;
      for(i=0; i<=30; ++i) {                //
Take 30 samples
         delay_ms(100);                     //
Wait for a tenth of a second
         value = read_adc();                //
A/D read functions- built-in
         if(value<min)                      //
Find smallest sample
            min=value;
         if(value>max)                      //
Find largest sample
            max=value;
      }
      printf("\n\rMin: %2X  Max:
%2X\n\r",min,max);
   } while (TRUE);
}
```

STATEMENTS

Statements

STATEMENT	Example

if (expr) stmt; [else stmt;]	`if (x==25)`
	`   x=0;`
	`else`
	`   x=x+1;`

while (expr) stmt;	`while (get_rtcc()!=0)`
	`   putc(‘n’);`

do stmt while (expr);	`do {`
	`   putc(c=getc());`
	`} while (c!=0);`

for (expr1;expr2;expr3) stmt;	`for (i=1;i<=10;++i)`
	`   printf(“%u\r\n”,i);`

switch (expr) {
case cexpr: stmt; //one or more case
[default:stmt]
... }
	`switch (cmd) {`
	`   case 0:  printf(“cmd 0”);break;`
	`   case 1: printf(“cmd 1”);break;`
	`   default: printf(“bad cmd”);break;`
	`}`

return [expr];	`return (5);`
goto label;	`goto loop;`
label: stmt;	`loop: i++;`
break;	`break;`
continue;	`continue;`
expr;	`i=1;`
;	`;`

{[stmt]}
 	
Zero or more
	`{a=1;`
	` b=1;}`

declaration;	`int i;`

Note: Items in [ ] are optional

if

if-else
The if-else statement is used to make decisions.
The syntax is:

```
  if (expr)
       stmt-1;
  [else
       stmt-2;]
```

The expression is evaluated; if it is true stmt-1 is done. If it is false then stmt-2 is done.

else-if
This is used to make multi-way decisions.
The syntax is:

```
   if (expr)
       stmt;
  [else if (expr)
       stmt;]
   ...
  [else
       stmt;]
```

The expressions are evaluated in order; if any expression is true, the statement associated with it is executed and it terminates the chain. If none of the conditions are satisfied the last else part is executed.

Example:
```
if (x==25)
    x=1;
else
    x=x+1;
```

Also See: Statements

while

While is used as a loop/iteration statement.
The syntax is:

```
while (expr)
  statement
```

The expression is evaluated and the statement is executed until it becomes false in which case the execution continues after the statement.

Example:
```
while (get_rtcc()!=0)
   putc('n');
```

Also See: Statements

do-while

do-while: Differs from *while* and *for* loop in that the termination condition is checked at the bottom of the loop rather than at the top and so the body of the loop is always executed at least once. The syntax is:

```
 do
    statement
 while   (expr);
```

The statement is executed; the expr is evaluated. If true, the same is repeated and when it becomes false the loop terminates.

Also See: Statements , While

for

For is also used as a loop/iteration statement.
The syntax is:

```
for (expr1;expr2;expr3)
  statement
```

The expressions are loop control statements. expr1 is the initialization, expr2 is the termination check and expr3 is re-initialization. Any of them can be omitted.

Example:

```
for (i=1;i<=10;++i)
   printf("%u\r\n",i);
```

Also See: Statements

switch

Switch is also a special multi-way decision maker.
The syntax is

```
switch (expr) {
   case const1: stmt sequence;
                      break;
   ...
   [default:stmt]
}
```

This tests whether the expression matches one of the constant values and branches accordingly.
If none of the cases are satisfied the default case is executed. The break causes an immediate exit, otherwise control falls through to the next case.

Example:

```
switch (cmd) {
    case 0:printf("cmd 0");
           break;
    case 1:printf("cmd 1");
           break;
    default:printf("bad cmd");
            break; }
```

Also See: Statements

return

return
A **return** statement allows an immediate exit from a switch or a loop or function and also returns a value.

The syntax is:

return(expr);

Example:
```
return (5);
```

Also See: Statements

goto

goto
The goto statement cause an unconditional branch to the label.

The syntax is:
goto label;

A label has the same form as a variable name, and is followed by a colon. The goto's are used sparingly, if at all.

Example:
```
goto loop;
```

Also See: Statements

label

label
The label a goto jumps to.
The syntax is:

label: stmnt;

Example:
```
loop: i++;
```

Also See: Statements

break

break.
The break statement is used to exit out of a control loop. It provides an early exit from while, for ,do and switch.
The syntax is

break;

It causes the innermost enclosing loop (or switch) to be exited immediately.

Example:
```
break;
```

Also See: Statements

continue

The **continue** statement causes the next iteration of the enclosing loop(While, For, Do) to begin.
The syntax is:

continue;

It causes the test part to be executed immediately in case of do and while and the control passes the re-initialization step in case of for.

Example:
```
continue;
```

Also See: Statements

expr

The syntax is:
expr**;**

Example:
```
i=1;
```

Also See: Statements

;

Statement: **;**

Example:
```
;
```

Also See: Statements

stmt

Zero or more semi-colon separated.
The syntax is:

{[stmt**]}**

Example:
```
{a=1;
 b=1;}
```

Also See: Statements

EXPRESSIONS

Constants

123	Decimal
123L	Forces type to & long (UL also allowed)
123LL	Forces type to & int32;
0123	Octal
0x123	Hex
0b010010	Binary
123.456	Floating Point
123F	Floating Point (FL also allowed)
123.4E-5	Floating Point in scientific notation
'x'	Character
'\010'	Octal Character
'\xA5'	Hex Character
'\c'	Special Character. Where c is one of: \n Line Feed - Same as \x0a \r Return Feed - Same as \x0d \t TAB - Same as \x09 \b Backspace - Same as \x08 \f Form Feed - Same as x0c \a Bell - Same as \x07 \v Vertical Space - Same as \x0b \? Question Mark - Same as \x3f \' Single Quote - Same as \x22 \" Double Quote - Same as \x22 \\ A Single Backslash - Same as \x5c
"abcdef"	String (null is added to the end)

Identifiers

ABCDE	Up to 32 characters beginning with a non-numeric. Valid characters are A-Z, 0-9 and _ (underscore). By default not case sensitive Use #CASE to turn on.
ID[X]	Single Subscript
ID[X][X]	Multiple Subscripts
ID.ID	Structure or union reference
ID->ID	Structure or union reference

Operators

+	**Addition Operator**
+=	Addition assignment operator, x+=y, is the same as x=x+y
[ ]	Array subscrip operator
&=	Bitwise and assignment operator, x&=y, is the same as x=x&y
&	Address operator
&	Bitwise and operator
^=	Bitwise exclusive or assignment operator, x^=y, is the same as x=x^y
^	Bitwise exclusive or operator
l=	Bitwise inclusive or assignment operator, xl=y, is the same as x=xly
l	Bitwise inclusive or operator
?:	Conditional Expression operator
- -	Decrement
/=	Division assignment operator, x/=y, is the same as x=x/y
/	Division operator
==	Equality
>	Greater than operator
>=	Greater than or equal to operator
++	Increment
*****	Indirection operator

!=	Inequality
<<=	Left shift assignment operator, x<<=y, is the same as x=x<<y
<	Less than operator
<<	Left Shift operator
<=	Less than or equal to operator
&&	Logical AND operator
!	Logical negation operator
||	Logical OR operator
.	Member operator for structures and unions
%=	Modules assignment operator x%=y, is the same as x=x%y
%	Modules operator
***=**	Multiplication assignment operator, x*=y, is the same as x=x*y
*****	Multiplication operator
~	One's complement operator
>>=	Right shift assignment, x>>=y, is the same as x=x>>y
>>	Right shift operator
->	Structure Pointer operation
-=	Subtraction assignment operator, x-=y, is the same as x=x- y
-	Subtraction operator
sizeof	Determines size in bytes of operand

See also: Operator Precedence

Operator Precedence

PIN DESCENDING PRECEDENCE				**Associativity**
(expr)	exor++	expr->expr	expr.expr	Left to Right
++expr	expr**++**	**- -**expr	expr **- -**	Left to Right
!expr	**~**expr	**+**expr	**-**expr	Right to Left
(type)expr	*****expr	**&**value	**sizeof**(type)	Right to Left
expr*expr	expr/expr	expr**%**expr		Left to Right
expr+expr	expr**-**expr			Left to Right
expr<<expr	expr**>>**expr			Left to Right
expr<expr	expr**<=**expr	expr**>**expr	expr**>=**expr	Left to Right

expr==expr	expr**!=**expr		Left to Right
expr&expr			Left to Right
expr^expr			Left to Right
expr | expr			Left to Right
expr&& expr			Left to Right
expr || expr			Left to Right
expr ? expr: expr			Right to Left
lvalue = expr	lvalue**+=**expr	lvalue**-=**expr	Right to Left
lvalue*=expr	lvalue**/=**expr	lvalue**%=**expr	Right to Left
lvalue>>=expr	lvalue**<<=**expr	lvalue**&=**expr	Right to Left
lvalue^=expr	lvalue**|=**expr		Right to Left
expr, expr			Left to Right

(Operators on the same line are equal in precedence)

DATA DEFINITIONS

Data Definitions

This section describes what the basic data types and specifiers are and how variables can be declared using those types. In C all the variables should be declared before they are used. They can be defined inside a function (local) or outside all functions (global). This will affect the visibility and life of the variables.

A declaration consists of a type qualifier and a type specifier, and is followed by a list of one or more variables of that type.
For example:

```
     int a,b,c,d;
     mybit e,f;
     mybyte g[3][2];
     char *h;
     colors j;
     struct data_record data[10];
     static int i;
     extern long j;
```

Variables can also be declared along with the definitions of the *special* types.
For example:

```
     enum colors{red, green=2,blue}i,j,k;  // colors is the enum type and
     i,j,k
                                           //are variables of that type
```

SEE ALSO:
Type Specifiers/ Basic Types
Type Qualifiers
Enumerated Types
Structures & Unions
typedef
Named Registers

Type Specifiers

Basic Types

Type-Specifier	Range			
	Size	Unsigned	Signed	Digits
int1	1 bit number	0 to 1	N/A	1/2
int8	8 bit number	0 to 255	-128 to 127	2-3
int16	16 bit number	0 to 65535	-32768 to 32767	4-5

int32	32 bit number	0 to 4294967295	-2147483648 to 2147483647	9-10
float32	32 bit float	-1.5 x 10^{45} to 3.4 x 10^{38}		7-8

C Standard Type	Default Type
short	int1
char	unsigned int8
int	int8
long	int16
long long	int32
float	float32
double	N/A

Note: All types, except float char , by default are un-signed; however, may be preceded by unsigned or signed (Except int64 may only be signed) . Short and long may have the keyword INT following them with no effect. Also see #TYPE to change the default size.

SHORT INT1 is a special type used to generate very efficient code for bit operations and I/O. Arrays of bits (INT1 or SHORT) in RAM are now supported. Pointers to bits are not permitted. The device header files contain defines for BYTE as an int8 and BOOLEAN as an int1.

Integers are stored in little endian format. The LSB is in the lowest address. Float formats are described in common questions.

SEE ALSO: Declarations, Type Qualifiers, Enumerated Types, Structures & Unions, typedef, Named Registers

Type Qualifiers

Type-Qualifier	
static	Variable is globally active and initialized to 0. Only accessible from this compilation unit.
auto	Variable exists only while the procedure is active. This is the default and AUTO need not be used.
double	Is a reserved word but is not a supported data type.
extern	External variable used with multiple compilation units. No storage is allocated. Is used to make otherwise out of scope data accessible. there must be a non-extern definition at the global level in some compilation unit.
register	Is allowed as a qualifier however, has no effect.
_ fixed(n)	Creates a fixed point decimal number where *n* is how many decimal places to implement.

unsigned	Data is always positive. This is the default data type if not specified.
signed	Data can be negative or positive.
volatile	Tells the compiler optimizer that this variable can be changed at any point during execution.
const	Data is read-only. Depending on compiler configuration, this qualifier may just make the data read-only -AND/OR- it may place the data into program memory to save space. (see #DEVICE const=)
rom	Forces data into program memory. Pointers may be used to this data but they can not be mixed with RAM pointers.
void	Built-in basic type. Type void is used to indicate no specific type in places where a type is required.
readonly	Writes to this variable should be dis-allowed
_bif	Used for compiler built in function prototypes on the same line
__attribute__	Sets various attributes

SEE ALSO: Declarations, Type Specifiers, Enumerated Types, Structures & Unions, typedef, Named Registers

Enumerated Types

enum enumeration type: creates a list of integer constants.

enum [id] { [id [= cexpr]] }

One or more comma separated

The id after **enum** is created as a type large enough to the largest constant in the list. The ids in the list are each created as a constant. By default the first id is set to zero and they increment by one. If a = cexpr follows an id that id will have the value of the constant expression an d the following list will increment by one.

For example:

```
   enum colors{red, green=2, blue};          // red will be 0, green will be 2 and
                                             // blue will be 3
```

SEE ALSO: Declarations, Type Specifiers, Type Qualifiers, Structures & Unions, typedef, Named Registers

Structures and Unions

Struct structure type: creates a collection of one or more variables, possibly of different types, grouped together as a single unit.

struct[*] [id] { type-qualifier [*****] id [:bits]; } [id]

One or more, semi-colon separated

Zero or more

For example:

```
struct data_record {
   int   a[2];
   int  b : 2; /*2 bits */
   int    c : 3; /*3 bits*/
   int d;
} data_var;                     //data_record is a structure type
                                //data_var is a variable
```

Union type: holds objects of different types and sizes, with the compiler keeping track of size and alignment requirements. They provide a way to manipulate different kinds of data in a single area of storage.

union[*] [id] { type-qualifier [*****] id [:bits]; } [id]

One or more, semi-colon separated

Zero or more

For example:

```
union u_tab {
   int ival;
   long lval;
   float fval;
   };                           //u_tag is a union type that can hold a float
```

SEE ALSO: Declarations, Type Specifiers, Type Qualifiers, Enumerated Types, typedef, Named Registers

typedef

If **typedef** is used with any of the basic or special types it creates a new type name that can be used in declarations. The identifier does not allocate space but rather may be used as a type specifier in other data definitions.

typedef [type-qualifier] [type-specifier] [declarator];

For example:

```
typedef int mybyte;                 // mybyte can be used in declaration
                                    to
                                    // specify the int type
typedef short mybit;                // mybyte can be used in declaration
                                    to
                                    // specify the int type
typedef enum {red,                  //colors can be used to declare
green=2,blue}colors;
                                    //variable of this enum type
```

SEE ALSO: Declarations, Type Specifiers, Type Qualifiers, Structures & Unions, Enumerated Types, Named Registers

Non-RAM Data Definitions

CCS C compiler also provides a custom qualifier *addressmod* which can be used to define a memory region that can be RAM, program eeprom, data eeprom or external memory. *Addressmod* replaces the older *typemod* (with a different syntax).

The usage is :

```
addressmod
(name,read_function,write_function,start_address,end_address,
share);
```

Where the read_function and write_function should be blank for RAM, or for other memory should be the following prototype:

```
// read procedure for reading n bytes from the memory starting at
location addr
void read_function(int32 addr,int8 *ram, int nbytes){
}

//write procedure for writing n bytes to the memory starting at
location addr
void write_function(int32 addr,int8 *ram, int nbytes){

}
```

For RAM the share argument may be true if unused RAM in this area can be used by the compiler for standard variables.

Example:

```
void DataEE_Read(int32 addr, int8 * ram, int bytes) {
   int i;
   for(i=0;i<bytes;i++,ram++,addr++)
     *ram=read_eeprom(addr);
}

void DataEE_Write(int32 addr, int8 * ram, int bytes) {
   int i;
   for(i=0;i<bytes;i++,ram++,addr++)
     write_eeprom(addr,*ram);
}

addressmod (DataEE,DataEE_read,DataEE_write,5,0xff);
      // would define a region called DataEE between
      // 0x5 and 0xff in the chip data EEprom.

void main (void)
{
  int DataEE test;
  int x,y;
  x=12;
  test=x;  // writes x to the Data EEPROM
  y=test;  // Reads the Data EEPROM
}
```

Note: If the area is defined in RAM then read and write functions are not required, the variables assigned in the memory region defined by the addressmod can be treated as a regular variable in all valid expressions. Any structure or data type can be used with an addressmod. Pointers can also be made to an addressmod data type. The #type directive can be used to make this memory region as default for variable allocations.

The syntax is :

```
#type default=addressmodname        // all the variable declarations
that
                                    // follow will use this memory
region
#type default=                      // goes back to the default mode
```

For example:

```
Type default=emi                    //emi is the addressmod name
defined
char buffer[8192];
#include <memoryhog.h>
#type default=
```

Using Program Memory for Data

CCS C Compiler provides a few different ways to use program memory for data. The different ways are discussed below:

Constant Data:
The **const** qualifier will place the variables into program memory. If the keyword **const** is used before the identifier, the identifier is treated as a constant. Constants should be initialized and may not be changed at run-time. This is an easy way to create lookup tables.

The **rom** Qualifier puts data in program memory with 3 bytes per instruction space. The address used for ROM data is not a physical address but rather a true byte address. The & operator can be used on ROM variables however the address is logical not physical.

The syntax is:

```
const type id[cexpr] = {value}
```

For example:

Placing data into ROM

```
const int table[16]={0,1,2...15}
```

Placing a string into ROM

```
const char cstring[6]={"hello"}
```

Creating pointers to constants

```
const char *cptr;
cptr = string;
```

The #org preprocessor can be used to place the constant to specified address blocks.

For example:

The constant ID will be at 1C00.

```
#ORG 0x1C00, 0x1C0F
CONST CHAR ID[10]= {"123456789"};
```

Note: Some extra code will precede the 123456789.

The function **label_address** can be used to get the address of the constant. The constant variable can be accessed in the code. This is a great way of storing constant data in large programs. Variable length constant strings can be stored into program memory.

A special method allows the use of pointers to ROM. This method does not contain extra code at the start of the structure as does constant.

For example:

```
char rom commands[] = {"put|get|status|shutdown"};
```

The compiler allows a non-standard C feature to implement a constant array of variable length strings.

The syntax is:

```
const char id[n] [*] = { "string", "string" ...};
```

Where n is optional and id is the table identifier.

For example:

```
const char colors[] [*] = {"Red", "Green", "Blue"};
```

#ROM directive:

Another method is to use #rom to assign data to program memory.

The syntax is:

```
#rom address = {data, data, … , data}
```

For example:

Places 1,2,3,4 to ROM addresses starting at 0x1000

```
#rom 0x1000 = {1, 2, 3, 4}
```

Places null terminated string in ROM

```
#rom 0x1000={"hello"}
```

This method can only be used to initialize the program memory.

Built-in-Functions:

The compiler also provides built-in functions to place data in program memory, they are:

- `write_program_eeprom(address,data);`

- Writes **data** to program memory

- `write_program_memory(address, dataptr, count);`

- Writes **count** bytes of data from **dataptr** to **address** in program memory.

-

Please refer to the help of these functions to get more details on their usage and limitations regarding erase procedures. These functions can be used only on chips that allow writes to program memory. The compiler uses the flash memory erase and write routines to implement the functionality.

The data placed in program memory using the methods listed above can be read from width the following functions:

- `read_program_memory((address, dataptr, count)`

- Reads count bytes from program memory at address to RAM at dataptr.

These functions can be used only on chips that allow reads from program memory. The compiler uses the flash memory read routines to implement the functionality.

Named Registers

The CCS C Compiler supports the new syntax for filing a variable at the location of a processor register. This syntax is being proposed as a C extension for embedded use. The same functionality is provided with the non-standard **#byte**, **#word**, **#bit** and **#locate**.

The syntax is:

```
        register _name type id;
  Or
        register constant type id;
```

name is a valid SFR name with an underscore before it.

Examples:

```
        register _status int8 status_reg;
        register _T1IF int8 timer_interrupt;
        register 0x04 int16 file_select_register;
```

FUNCTION DEFINITION

Function Definition

The format of a function definition is as follows:

[qualifier] id	**(** [type-specifier id] **)**	**{** [stmt] **}**
Optional See Below	Zero or more comma separated. See Data Types	Zero or more Semi-colon separated. See Statements.

The qualifiers for a function are as follows:

- VOID
- type-specifier
- #separate
- #inline
- #int_..

When one of the above are used and the function has a prototype (forward declaration of the function before it is defined) you must include the qualifier on both the prototype and function definition.

A (non-standard) feature has been added to the compiler to help get around the problems created by the fact that pointers cannot be created to constant strings. A function that has one CHAR parameter will accept a constant string where it is called. The compiler will generate a loop that will call the function once for each character in the string.

Example:

```
void lcd_putc(char c ) {
...
}

lcd_putc ("Hi There.");
```

SEE ALSO:

Overloaded Functions
Reference Parameters
Default Parameters
Variable Parameters

Overloaded Functions

Overloaded functions allow the user to have multiple functions with the same name, but they must accept different parameters.

Here is an example of function overloading: Two functions have the same name but differ in the types of parameters. The compiler determines which data type is being passed as a parameter and calls the proper function.

This function finds the square root of a long integer variable.

```
long FindSquareRoot(long n){
}
```

This function finds the square root of a float variable.

```
        float FindSquareRoot(float n){
        }
```

FindSquareRoot is now called. If variable is of long type, it will call the first FindSquareRoot() example. If variable is of float type, it will call the second FindSquareRoot() example.

```
        result=FindSquareRoot(variable);
```

Reference Parameters

The compiler has limited support for reference parameters. This increases the readability of code and the efficiency of some inline procedures. The following two procedures are the same. The one with reference parameters will be implemented with greater efficiency when it is inline.

```
      funct_a(int*x,int*y){
         /*Traditional*/
         if(*x!=5)
            *y=*x+3;
      }

      funct_a(&a,&b);



      funct_b(int&x,int&y){
         /*Reference params*/
         if(x!=5)
            y=x+3;
      }

      funct_b(a,b);
```

Default Parameters

Default parameters allows a function to have default values if nothing is passed to it when called.

```
        int mygetc(char *c, int n=100){
        }
```

This function waits n milliseconds for a character over RS232. If a character is received, it saves it to the pointer c and returns TRUE. If there was a timeout it returns FALSE.

```
        //gets a char, waits 100ms for timeout
        mygetc(&c);
        //gets a char, waits 200ms for a timeout
        mygetc(&c, 200);
```

Variable Argument Lists

The compiler supports a variable number of parameters. This works like the ANSI requirements except that it does not require at least one fixed parameter as ANSI does. The function can be passed any number of variables and any data types. The access functions are VA_START, VA_ARG, and VA_END. To view the number of arguments passed, the NARGS function can be used.

```
/*
stdarg.h holds the macros and va_list data type needed for variable number of parameters.
*/
#include <stdarg.h>
```

A function with variable number of parameters requires two things. First, it requires the ellipsis (...), which must be the last parameter of the function. The ellipsis represents the variable argument list. Second, it requires one more variable before the ellipsis (...). Usually you will use this variable as a method for determining how many variables have been pushed onto the ellipsis.

Here is a function that calculates and returns the sum of all variables:

```
int Sum(int count, ...)
{
   //a pointer to the argument list
   va_list al;
   int x, sum=0;
   //start the argument list
   //count is the first variable before the ellipsis
   va_start(al, count);
   while(count--) {
      //get an int from the list
      x = var_arg(al, int);
      sum += x;
   }
   //stop using the list
   va_end(al);
   return(sum);
}
```

Some examples of using this new function:

```
x=Sum(5, 10, 20, 30, 40, 50);
y=Sum(3, a, b, c);
```

FUNCTIONAL OVERVIEW

I2C

I2C™ is a popular two-wire communication protocol developed by Phillips. Many PIC microcontrollers support hardware-based I2C™. CCS offers support for the hardware-based I2C™ and a software-based master I2C™ device. (For more information on the hardware-based I2C module, please consult the datasheet for you target device; not all PICs support I2C™.)

Relevant Functions:	
i2c_start()	Issues a start command when in the I2C master mode.
i2c_write(data)	Sends a single byte over the I2C interface.
i2c_read()	Reads a byte over the I2C interface.
i2c_stop()	Issues a stop command when in the I2C master mode.
i2c_poll()	Returns a TRUE if the hardware has received a byte in the buffer.
Relevant Preprocessor:	
#USE I2C	Configures the compiler to support I2C™ to your specifications.
Relevant Interrupts:	
#INT_SSP	I2C or SPI activity
#INT_BUSCOL	Bus Collision
#INT_I2C	I2C Interrupt (Only on 14000)
#INT_BUSCOL2	Bus Collision (Only supported on some PIC18's)
#INT_SSP2	I2C or SPI activity (Only supported on some PIC18's)
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() Parameters:	
I2C_SLAVE	Returns a 1 if the device has I2C slave H/W
I2C_MASTER	Returns a 1 if the device has a I2C master H/W
Example Code:	
#define Device_SDA PIN_C3	// Pin defines
#define Device_SLC PIN_C4	
#use i2c(master, sda=Device_SDA, scl=Device_SCL)	// Configure Device as Master
..	
..	
BYTE data;	// Data to be transmitted
i2c_start();	// Issues a start command when in the I2C master mode.
i2c_write(data);	// Sends a single byte over the I2C interface.
i2c_stop();	// Issues a stop command when in the I2C master mode.

ADC

These options let the user configure and use the analog to digital converter module. They are only available on devices with the ADC hardware. The options for the functions and directives vary depending on the chip and are listed in the device header file. On some devices there are two independent ADC modules, for these chips the second module is configured using secondary ADC setup functions (Ex. setup_ADC2).

Relevant Functions:	
setup_adc(mode)	Sets up the a/d mode like off, the adc clock etc.
setup_adc_ports(value)	Sets the available adc pins to be analog or digital.
set_adc_channel(channel)	Specifies the channel to be use for the a/d call.
read_adc(mode)	Starts the conversion and reads the value. The mode can also control the functionality.
adc_done()	Returns 1 if the ADC module has finished its conversion.
Relevant Preprocessor:	
#DEVICE ADC=xx	Configures the read_adc return size. For example, using a PIC with a 10 bit A/D you can use 8 or 10 for xx- 8 will return the most significant byte, 10 will return the full A/D reading of 10 bits.
Relevant Interrupts:	
INT_AD	Interrupt fires when a/d conversion is complete
INT_ADOF	Interrupt fires when a/d conversion has timed out
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
ADC_CHANNELS	Number of A/D channels
ADC_RESOLUTION	Number of bits returned by read_adc
Example Code:	
#DEVICE ADC=10	
...	
long value;	
...	
setup_adc(ADC_CLOCK_INTERNAL);	//enables the a/d module //and sets the clock to internal adc clock
setup_adc_ports(ALL_ANALOG);	//sets all the adc pins to analog
set_adc_channel(0);	//the next read_adc call will read channel 0
delay_us(10);	//a small delay is required after setting the channel
	//and before read
value=read_adc();	//starts the conversion and reads the result
	//and store it in value
read_adc(ADC_START_ONLY);	//only starts the conversion
value=read_adc(ADC_READ_ONLY);	//reads the result of the last conversion and store it in //value. Assuming

	the device hat a 10bit ADC module, //value will range between 0-3FF. If #DEVICE ADC=8 had //been used instead the result will yield 0-FF. If #DEVICE //ADC=16 had been used instead the result will yield 0-//FFC0

Analog Comparator

These functions set up the analog comparator module. Only available in some devices.

Relevant Functions:	
setup_comparator(mode)	Enables and sets the analog comparator module. The options vary depending on the chip. Refer to the header file for details.
Relevant Preprocessor:	
None	
Relevant Interrupts:	
INT_COMP	Interrupt fires on comparator detect. Some chips have more than one comparator unit, and thus, more interrupts.
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() Parameters:	
Returns 1 if the device has a comparator	COMP
Example Code:	
setup_comparator(A4_A5_NC_NC);	
if(C1OUT)	
output_low(PIN_D0);	
else	
output_high(PIN_D1);	

CAN Bus

These functions allow easy access to the Controller Area Network (CAN) features included with the MCP2515 CAN interface chip and the PIC18 MCU. These functions will only work with the MCP2515 CAN interface chip and PIC microcontroller units containing either a CAN or an ECAN module. Some functions are only available for the ECAN module and are specified by the work ECAN at the end of the description. The listed interrupts are no available to the MCP2515 interface chip.

Relevant Functions:	
can_init(void);	Initializes the CAN module and clears all the filters and masks so thathat all messages can be received from any ID.
can_set_baud(void);	Initializes the baud rate of the CAN bus to125kHz, if using a 20 MHz clock and the default CAN-BRG defines, it is called inside the can_init()

	function so there is no need to call it.
can_set_mode (CAN_OP_MODE mode);	Allows the mode of the CAN module to be changed to configuration mode, listen mode, loop back mode, disabled mode, or normal mode.
can_set_functional_mode (CAN_FUN_OP_MODE mode);	Allows the functional mode of ECAN modules to be changed to legacy mode, enhanced legacy mode, or first in firstout (fifo) mode. ECAN
can_set_id(int* addr, int32 id, int1 ext);	Can be used to set the filter and mask ID's to the value specified by addr. It is also used to set the ID of the message to be sent.
can_get_id(int * addr, int1 ext);	Returns the ID of a received message.
can_putd (int32 id, int * data, int len, int priority, int1 ext, int1 rtr);	Constructs a CAN packet using the given arguments and places it in one of the available transmit buffers.
can_getd (int32 & id, int * data, int & len, struct rx_stat & stat);	Retrieves a received message from one of the CAN buffers and stores the relevant data in the referenced function parameters.
can_enable_rtr(PROG_BUFFER b);	Enables the automatic response feature which automatically sends a user created packet when a specified ID is received. ECAN
can_disable_rtr(PROG_BUFFER b);	Disables the automatic response feature. ECAN
can_load_rtr (PROG_BUFFER b, int * data, int len);	Creates and loads the packet that will automatically transmitted when the triggering ID is received. ECAN
can_enable_filter(long filter);	Enables one of the extra filters included in the ECAN module. ECAN
can_disable_filter(long filter);	Disables one of the extra filters included in the ECAN module. ECAN
can_associate_filter_to_buffer (CAN_FILTER_ASSOCIATION_BUFFERS buffer,CAN_FILTER_ASSOCIATION filter);	Used to associate a filter to a specific buffer. This allows only specific buffers to be filtered and is available in the ECAN module. ECAN
can_associate_filter_to_mask (CAN_MASK_FILTER_ASSOCIATE mask, CAN_FILTER_ASSOCIATION filter);	Used to associate a mask to a specific buffer. This allows only specific buffer to have this mask applied. This feature is available in the ECAN module. ECAN
can_fifo_getd(int32 & id,int * data, int &len,struct rx_stat & stat);	Retrieves the next buffer in the fifo buffer. Only available in the ECON module while operating in fifo mode. ECAN
Relevant Preprocessor:	
None	
Relevant Interrupts:	
#int_canirx	This interrupt is triggered when an invalid packet is received on the CAN.

#int_canwake	This interrupt is triggered when the PIC is woken up by activity on the CAN.
#int_canerr	This interrupt is triggered when there is an error in the CAN module.
#int_cantx0	This interrupt is triggered when transmission from buffer 0 has completed.
#int_cantx1	This interrupt is triggered when transmission from buffer 1 has completed.
#int_cantx2	This interrupt is triggered when transmission from buffer 2 has completed.
#int_canrx0	This interrupt is triggered when a message is received in buffer 0.
#int_canrx1	This interrupt is triggered when a message is received in buffer 1.
Relevant Include Files:	
can-mcp2510.c	Drivers for the MCP2510 and MCP2515 interface chips
can-18xxx8.c	Drivers for the built in CAN module
can-18F4580.c	Drivers for the build in ECAN module
Relevant getenv() Parameters:	
none	
Example Code:	
can_init();	// initializes the CAN bus
can_putd(0x300,data,8,3,TRUE,FALSE);	// places a message on the CAN buss with
	// ID = 0x300 and eight bytes of data pointed to by
	// “data”, the TRUE creates an extended ID, the
	// FALSE creates
can_getd(ID,data,len,stat);	// retrieves a message from the CAN bus storing the
	// ID in the ID variable, the data at the array pointed to by
	// “data', the number of data bytes in len, and statistics
	// about the data in the stat structure.

CCP

These options lets to configure and use the CCP module. There might be multiple CCP modules for a device. These functions are only available on devices with CCP hardware. They operate in 3 modes: capture, compare and PWM. The source in capture/compare mode can be timer1 or timer3 and in PWM can be timer2 or timer4. The options available are different for different devices and are listed in the device header file. In capture mode the value of the timer is copied to the CCP_X register when the input pin event occurs. In compare mode it will trigger an action when timer and CCP_x values are equal and in PWM mode it will generate a square wave.

Relevant Functions:	
setup_ccp1(mode)	Sets the mode to capture, compare or PWM. For capture
set_pwm1_duty(value)	The value is written to the pwm1 to set the duty.
Relevant Preprocessor:	
None	
Relevant Interrupts :	

INT_CCP1	Interrupt fires when capture or compare on CCP1

Relevant Include Files:

None, all functions built-in

Relevant getenv() parameters:

CCP1	Returns 1 if the device has CCP1

Example Code:

```
#int_ccp1
void isr()
{
    rise = CCP_1;                    //CCP_1 is the time the pulse went high
    fall = CCP_2;                    //CCP_2 is the time the pulse went low
    pulse_width = fall - rise;       //pulse width
}
..
setup_ccp1(CCP_CAPTURE_RE);          // Configure CCP1 to capture rise
setup_ccp2(CCP_CAPTURE_FE);          // Configure CCP2 to capture fall
setup_timer_1(T1_INTERNAL);          // Start timer 1
```

Some chips also have fuses which allows to multiplex the ccp/pwm on different pins. So check the fuses to see which pin is set by default. Also fuses to enable/disable pwm outputs.

Code Profile

Profile a program while it is running. Unlike in-circuit debugging, this tool grabs information while the program is running and provides statistics, logging and tracing of it's execution. This is accomplished by using a simple communication method between the processor and the ICD with minimal side-effects to the timing and execution of the program. Another benefit of code profile versus in-circuit debugging is that a program written with profile support enabled will run correctly even if there is no ICD connected.

In order to use Code Profiling, several functions and pre-processor statements need to be included in the project being compiled and profiled. Doing this adds the proper code profile run-time support on the microcontroller.

See the help file in the Code Profile tool for more help
and usage examples.

Relevant Functions:	
profileout()	Send a user specified message or variable to be displayed or logged by the code profile tool.
Relevant Pre-Processor:	
#use profile()	Global configuration of the code profile run-time on the microcontroller.

#profile	Dynamically enable/disable specific elements of the profiler.
Relevant Interrupts:	The profiler can be configured to use a microcontroller's internal timer for more accurate timing of events over the clock on the PC. This timer is configured using the #profile pre-processor command.
Relevant Include Files:	None – all the functions are built into the compiler.
Relevant getenv():	None
Example Code:	(see below)

```
#include <18F4520.h>
#use delay(crystal=10MHz, clock=40MHz)
#profile functions, parameters
void main(void)
{
   int adc;
   setup_adc(ADC_CLOCK_INTERNAL);
   set_adc_channel(0);

   for(;;)
   {
      adc = read_adc();
      profileout(adc);
      delay_ms(250);
   }
}
```

Configuration Memory

On all PIC18 Family of chips, the configuration memory is readable and writable. This functionality is not available on the PIC16 Family of devices..

Relevant Functions:	
write_configuration_memory (ramaddress, count)	Writes count bytes, no erase needed
or	
write_configuration_memory (offset,ramaddress, count)	Writes count bytes, no erase needed starting at byte address offset
read_configuration_memory (ramaddress,count)	Read count bytes of configuration memory

Relevant Preprocessor:

None

Relevant Include Files:

None, all functions built-in

Relevant getenv() parameters:	
None	

Example Code:	
For PIC18f452	
int16 data=0xc32;	
...	
write_configuration_memory(data, 2);	//writes 2 bytes to the configuration memory

DAC

These options let the user configure and use the digital to analog converter module. They are only available on devices with the DAC hardware. The options for the functions and directives vary depending on the chip and are listed in the device header file.

Relevant Functions:	
setup_dac(divisor)	Sets up the DAC e.g. Reference voltages
dac_write(value)	Writes the 8-bit value to the DAC module
	Sets up the d/a mode e.g. Right enable, clock divisor
	Writes the 16-bit value to the specified channel
Relevant Preprocessor:	
	#USE DELAY(clock=20M, Aux: crystal=6M, clock=3M)
Relevant Interrupts:	None
Relevant Include Files:	None, all functions built-in
Relevant getenv() parameters:	None

Example Code	int8 i=0
	setup_dac(DAC_VSS_VDD);
	while(TRUE){
	itt;
	dac_write(i);
	}

Data Eeprom

The data eeprom memory is readable and writable in some chips. These options lets the user read and write to the data eeprom memory. These functions are only available in flash chips.

Relevant Functions:	
(8 bit or 16 bit depending on the device)	
read_eeprom(address)	Reads the data EEPROM memory location
write_eeprom(address, value)	Erases and writes value to data EEPROM location address.
	Reads N bytes of data EEPROM starting at memory location address. The maximum return size is int64.
	Reads from EEPROM to fill variable starting at address
	Reads N bytes, starting at address, to pointer
	Writes value to EEPROM address
	Writes N bytes to address from pointer
Relevant Preprocessor:	
#ROM address={list}	Can also be used to put data EEPROM memory data into the hex file.
write_eeprom = noint	Allows interrupts to occur while the write_eeprom() operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.
Relevant Interrupts:	
INT_EEPROM	Interrupt fires when EEPROM write is complete
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
DATA_EEPROM	Size of data EEPROM memory.
Example Code:	

For 18F452
#rom 0xf00000={1,2,3,4,5}
	//inserts this data into the hex file. The data eeprom address
	//differs for different family of chips. Please refer to the
	//programming specs to find the right value for the device

write_eeprom(0x0,0x12);	//writes 0x12 to data eeprom location 0
value=read_eeprom(0x0);	//reads data eeprom location 0x0 returns 0x12
#ROM 0x007FFC00={1,2,3,4,5}	// Inserts this data into the hex file
	// The data EEPROM address differs between PICs // Please refer to the device editor for device specific values.
write_eeprom(0x10, 0x1337);	// Writes 0x1337 to data EEPROM location 10.
value=read_eeprom(0x0);	// Reads data EEPROM location 10 returns 0x1337.

Data Signal Modulator

The Data Signal Modulator (DSM) allows the user to mix a digital data stream (the "modulator signal") with a carrier signal to produce a modulated output. Both the carrier and the modulator signals are supplied to the DSM module, either internally from the output of a peripheral, or externally through an input pin. The modulated output signal is generated by performing a logical AND operation of both the carrier and modulator signals and then it is provided to the MDOUT pin. Using this method, the DSM can generate the following types of key modulation schemes:

- Frequency Shift Keying (FSK)
- Phase Shift Keying (PSK)
- On-Off Keying (OOK)

Relevant Functions:	***(8 bit or 16 bit depending on the device)***
setup_dsm(mode,source,carrier)	Configures the DSM module and selects the source signal and carrier signals.
setup_dsm(TRUE)	Enables the DSM module.
setup_dsm(FALSE)	Disables the DSM module.
Relevant Preprocessor:	None
Relevant Interrupts:	None
Relevant Include Files:	None, all functions built-in
Relevant getenv() parameters:	None
Example Code:	
setup_dsm(DSM_ENABLED |	//Enables DSM module with the output enabled and selects UART1
DSM_OUTPUT_ENABLED,	//as the source signal and VSS as the high carrier signal and OC1's
DSM_SOURCE_UART1,	//PWM output as the low carrier signal.
DSM_CARRIER_HIGH_VSS |	
DSM_CARRIER_LOW_OC1);	

if(input(PIN_B0))
  setup_dsm(FALSE);
	Disable DSM module

else
  setup_dsm(TRUE);
	Enable DSM module

External Memory

Some PIC18 devices have the external memory functionality where the external memory can be mapped to external memory devices like (Flash, EPROM or RAM). These functions are available only on devices that support external memory bus.

General Purpose I/O

These options let the user configure and use the I/O pins on the device. These functions will affect the pins that are listed in the device header file.

Relevant Functions:	
output_high(pin)	Sets the given pin to high state.
output_low(pin)	Sets the given pin to the ground state.
output_float(pin)	Sets the specified pin to the input mode. This will allow the pin to float high to represent a high on an open collector type of connection.
output_x(value)	Outputs an entire byte to the port.
output_bit(pin,value)	Outputs the specified value (0,1) to the specified I/O pin.
input(pin)	The function returns the state of the indicated pin.
input_state(pin)	This function reads the level of a pin without changing the direction of the pin as INPUT() does.
set_tris_x(value)	Sets the value of the I/O port direction register. A '1' is an input and '0' is for output.
input_change_x( )	This function reads the levels of the pins on the port, and compares them to the last time they were read to see if there was a change, 1 if there was, 0 if there wasn't.
Relevant Preprocessor:	
#USE STANDARD_IO(port)	This compiler will use this directive be default and it will automatically inserts code for the direction register whenever an I/O function like output_high() or input() is used.
#USE FAST_IO(*port*)	This directive will configure the I/O port to use the fast method of performing I/O. The user will be responsible for setting the port direction register using the set_tris_x() function.
#USE FIXED_IO (*port_outputs=;in,pin?*)	This directive set particular pins to be used an input or output, and the compiler will perform this setup every time this pin is used.
Relevant Interrupts:	
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
PIN:pb	Returns a 1 if bit b on port p is on this part
Example Code:	
`#use fast_io(b)`	
`...`	
`Int8 Tris_value= 0x0F;`	
`int1 Pin_value;`	

```
...
set_tris_b(Tris_value);          //Sets B0:B3 as  input and B4:B7 as output
output_high(PIN_B7);             //Set the pin B7 to High
If(input(PIN_B0)){               //Read the value on pin B0, set B7 to low if pin B0 is high
output_high(PIN_B7);}
```

Internal LCD

Some families of PIC microcontrollers can drive a glass segment LCD directly, without the need of an LCD controller. For example, the PIC16C92X, PIC16F91X, and PIC16F193X series of chips have an internal LCD driver module.

Relevant Functions:	
setup_lcd (mode, prescale, [segments])	Configures the LCD Driver Module to use the specified mode, timer prescaler, and segments. For more information on valid modes and settings, see the setup_lcd( ) manual page and the *.h header file for the PIC micro-controller being used.
lcd_symbol (symbol, segment_b7 ... segment_b0)	The specified symbol is placed on the desired segments, where segment_b7 to segment_b0 represent SEGXX pins on the PIC micro-controller. For example, if bit 0 of symbol is set, then segment_b0 is set, and if segment_b0 is 15, then SEG15 would be set.
lcd_load(ptr, offset, length)	Writes **length** bytes of data from **pointer** directly to the LCD segment memory, starting with **offset**.
lcd_contrast (contrast)	Passing a value of 0 – 7 will change the contrast of the LCD segments, 0 being the minimum, 7 being the maximum.
Relevant Preprocessor:	
None	
Relevant Interrupts:	
#int_lcd	LCD frame is complete, all pixels displayed
Relevant Inlcude Files:	None, all functions built-in to the compiler.
Relevant getenv() Parameters:	
LCD	Returns TRUE if the device has an Internal LCD Driver Module.
Example Program:	
// How each segment of the LCD is set (on or off) for the ASCII digits 0 to 9.	
byte CONST DIGIT_MAP[10] = {0xFC, 0x60, 0xDA, 0xF2, 0x66, 0xB6, 0xBE, 0xE0, 0xFE, 0xE6};	
// Define the segment information for the first digit of the LCD	
#define DIGIT1 COM1+20, COM1+18, COM2+18, COM3+20, COM2+28, COM1+28, COM2+20, COM3+18	
// Displays the digits 0 to 9 on the first digit of the LCD.	

```
for(i = 0; i <= 9; i++) {
        lcd_symbol( DIGIT_MAP[i], DIGIT1 );
        delay_ms( 1000 );
}
```

Internal Oscillator

Many chips have internal oscillator. There are different ways to configure the internal oscillator. Some chips have a constant 4 Mhz factory calibrated internal oscillator. The value is stored in some location (mostly the highest program memory) and the compiler moves it to the osccal register on startup. The programmers save and restore this value but if this is lost they need to be programmed before the oscillator is functioning properly. Some chips have factory calibrated internal oscillator that offers software selectable frequency range(from 31Kz to 8 Mhz) and they have a default value and can be switched to a higher/lower value in software. They are also software tunable. Some chips also provide the PLL option for the internal oscillator.

Relevant Functions:	
setup_oscillator(mode, finetune)	Sets the value of the internal oscillator and also tunes it. The options vary depending on the chip and are listed in the device header files.
Relevant Preprocessor:	
None	
Relevant Interrupts:	
INT_OSC_FAIL or INT_OSCF	Interrupt fires when the system oscillator fails and the processor switches to the internal oscillator.
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
None	
Example Code:	
For PIC18F8722	
setup_oscillator(OSC_32MHZ);	//sets the internal oscillator to 32MHz (PLL enabled)

If the internal oscillator fuse option are specified in the #fuses and a valid clock is specified in the #use delay(clock=xxx) directive the compiler automatically sets up the oscillator. The #use delay statements should be used to tell the compiler about the oscillator speed.

Interrupts

The following functions allow for the control of the interrupt subsystem of the microcontroller. With these functions, interrupts can be enabled, disabled, and cleared. With the preprocessor directives, a default function can be called for any interrupt that does not have an associated ISR, and a global function can replace the compiler generated interrupt dispatcher.

Relevant Functions:	
disable_interrupts()	Disables the specified interrupt.

enable_interrupts()	Enables the specified interrupt.
ext_int_edge()	Enables the edge on which the edge interrupt should trigger. This can be either rising or falling edge.
clear_interrupt()	This function will clear the specified interrupt flag. This can be used if a global isr is used, or to prevent an interrupt from being serviced.
interrupt_active()	This function checks the interrupt flag of specified interrupt and returns true if flag is set.
interrupt_enabled()	This function checks the interrupt enable flag of the specified interrupt and returns TRUE if set.
Relevant Preprocessor:	
#DEVICE HIGH_INTS=	This directive tells the compiler to generate code for high priority interrupts.
#INT_XXX fast	This directive tells the compiler that the specified interrupt should be treated as a high priority interrupt.
Relevant Interrupts:	
#int_default	This directive specifies that the following function should be called if an interrupt is triggered but no routine is associated with that interrupt.
#int_global	This directive specifies that the following function should be called whenever an interrupt is triggered. This function will replace the compiler generated interrupt dispatcher.
#int_xxx	This directive specifies that the following function should be called whenever the xxx interrupt is triggered. If the compiler generated interrupt dispatcher is used, the compiler will take care of clearing the interrupt flag bits.
Relevant Include Files: **none, all functions built in.**	
Relevant getenv() Parameters: **none**	
Example Code:	
#int_timer0	
void timer0interrupt()	// #int_timer associates the following function with the
	// interrupt service routine that should be called
enable_interrupts(TIMER0);	// enables the timer0 interrupt
disable_interrtups(TIMER0);	// disables the timer0 interrupt
clear_interrupt(TIMER0);	// clears the timer0 interrupt flag

Low Voltage Detect

These functions configure the high/low voltage detect module. Functions available on the chips that have the low voltage detect hardware.

Relevant Functions:	
setup_low_volt_detect(mode)	Sets the voltage trigger levels and also the mode (below or above in case of the high/low voltage detect module). The options vary depending on the chip and are listed in the device header files.
Relevant Preprocessor:	
None	
Relevant Interrupts :	
INT_LOWVOLT	Interrupt fires on low voltage detect
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
None	
Example Code:	
For PIC18F8722	
setup_low_volt_detect	
(LVD_36|LVD_TRIGGER_ABOVE);	//sets the trigger level as 3.6 volts and
	// trigger direction as above. The interrupt
	//if enabled is fired when the voltage is
	//above 3.6 volts.

PMP/EPMP

The Parallel Master Port (PMP)/Enhanced Parallel Master Port (EPMP) is a parallel 8-bit/16-bit I/O module specifically designed to communicate with a wide variety of parallel devices. Key features of the PMP module are:

· 8 or 16 Data lines
· Up to 16 or 32 Programmable Address Lines
· Up to 2 Chip Select Lines
· Programmable Strobe option
· Address Auto-Increment/Auto-Decrement
· Programmable Address/Data Multiplexing
· Programmable Polarity on Control Signals
· Legacy Parallel Slave(PSP) Support
· Enhanced Parallel Slave Port Support
· Programmable Wait States

Relevant Functions:	
	This will setup the PMP/EPMP module for various mode and specifies which address lines to be used.

setup_psp (options,address_mask)	This will setup the PSP module for various mode and specifies which address lines to be used.
setup_pmp_csx(options,[offset])	Sets up the Chip Select X Configuration, Mode and Base Address registers
setup_psp_es(options)	Sets up the Chip Select X Configuration and Mode registers
	Write the data byte to the next buffer location.
	This will write a byte of data to the next buffer location or will write a byte to the specified buffer location.
	Reads a byte of data.
	psp_read() will read a byte of data from the next buffer location and psp_read (address) will read the buffer location address.
	Configures the address register of the PMP module with the destination address during Master mode operation.
	This will return the status of the output buffer underflow bit.
	This will return the status of the input buffers.
psp_input_full()	This will return the status of the input buffers.
	This will return the status of the output buffers.
psp_output_full()	This will return the status of the output buffers.
Relevant Preprocessor:	
None	
Relevant Interrupts :	
#INT_PMP	Interrupt on read or write strobe
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
None	
Example Code:	
setup_pmp(PAR_ENABLE |	Sets up Master mode with address lines PMA0:PMA7
PAR_MASTER_MODE_1 |	
PAR_STOP_IN_IDLE,0x00FF);	
If (pmp_output_full ( ))	
{	
pmp_write(next_byte);	
}	

Power PWM

These options lets the user configure the Pulse Width Modulation (PWM) pins. They are only available on devices equipped with PWM. The options for these functions vary depending on the chip and are listed in the device header file.

Relevant Functions:	
setup_power_pwm(config)	Sets up the PWM clock, period, dead time etc.
setup_power_pwm_pins(module x)	Configure the pins of the PWM to be in
	Complimentary, ON or OFF mode.
set_power_pwmx_duty(duty)	Stores the value of the duty cycle in the PDCXL/H register. This duty cycle value is the time for which the PWM is in active state.
set_power_pwm_override(pwm,override,value)	This function determines whether the OVDCONS or the PDC registers determine the PWM output .
Relevant Preprocessor:	
None	
Relevant Interrupts:	
#INT_PWMTB	PWM Timebase Interrupt (Only available on PIC18XX31)
Relevant getenv() Parameters:	
None	
Example Code:	

```
....
long duty_cycle, period;
...
        // Configures PWM  pins to be ON,OFF or in Complimentary mode.
setup_power_pwm_pins(PWM_COMPLEMENTARY ,PWM_OFF, PWM_OFF, PWM_OFF);

        //Sets up PWM clock , postscale and period. Here period is used to set the
        //PWM Frequency as follows:
        //Frequency = Fosc / (4 * (period+1) *postscale)
setup_power_pwm(PWM_CLOCK_DIV_4|PWM_FREE_RUN,1,0,period,0,1,0);

set_power_pwm0_duty(duty_cycle));    // Sets the duty cycle of the PWM 0,1 in
                                     //Complementary mode
```

Program Eeprom

The Flash program memory is readable and writable in some chips and is just readable in some. These options lets the user read and write to the Flash program memory. These functions are only available in flash chips.

Relevant Functions:	
read_program_eeprom(addres	Reads the program memory location (16 bit or 32 bit depending on the

s)	device).
write_program_eeprom(address, value)	Writes value to program memory location address.
erase_program_eeprom(address)	Erases FLASH_ERASE_SIZE bytes in program memory.
write_program_memory(address,dataptr,count)	Writes count bytes to program memory from dataptr to address. When address is a mutiple of FLASH_ERASE_SIZE an erase is also performed.
read_program_memory(address,dataptr,count)	Read count bytes from program memory at address to dataptr.
Relevant Preprocessor:	
#ROM address={list}	Can be used to put program memory data into the hex file.
#DEVICE(WRITE_EEPROM=ASYNC)	Can be used with #DEVICE to prevent the write function from hanging. When this is used make sure the eeprom is not written both inside and outside the ISR.
Relevant Interrupts:	
INT_EEPROM	Interrupt fires when eeprom write is complete.
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters	
PROGRAM_MEMORY	Size of program memory
READ_PROGRAM	Returns 1 if program memory can be read
FLASH_WRITE_SIZE	Smallest number of bytes written in flash
FLASH_ERASE_SIZE	Smallest number of bytes erased in flash
Example Code:	
For 18F452 where the write size is 8 bytes and erase size is 64 bytes	
#rom 0xa00={1,2,3,4,5}	//inserts this data into the hex file.
erase_program_eeprom(0x1000);	//erases 64 bytes strting at 0x1000
write_program_eeprom(0x1000,0x1234);	//writes 0x1234 to 0x1000
value=read_program_eeprom(0x1000);	//reads 0x1000 returns 0x1234
write_program_memory(0x1000,data,8);	//erases 64 bytes starting at 0x1000 as 0x1000 is a multiple
	//of 64 and writes 8 bytes from data to 0x1000
read_program_memory(0x1000,value,8);	//reads 8 bytes to value from 0x1000
erase_program_eeprom(0x1000);	//erases 64 bytes starting at 0x1000
write_program_memory(0x1010,data,8);	//writes 8 bytes from data to 0x1000

read_program_memory(0x1000,value,8);	//reads 8 bytes to value from 0x1000
For chips where getenv("FLASH_ERASE_SIZE") > getenv("FLASH_WRITE_SIZE")	
WRITE_PROGRAM_EEPROM -	Writes 2 bytes,does not erase (use ERASE_PROGRAM_EEPROM)
WRITE_PROGRAM_MEMORY -	Writes any number of bytes,will erase a block whenever the first (lowest) byte in a block is written to. If the first address is not the start of a block that block is not erased.
ERASE_PROGRAM_EEPROM -	Will erase a block. The lowest address bits are not used.
For chips where getenv("FLASH_ERASE_SIZE") = getenv("FLASH_WRITE_SIZE")	
WRITE_PROGRAM_EEPROM -	Writes 2 bytes, no erase is needed.
WRITE_PROGRAM_MEMORY -	Writes any number of bytes, bytes outside the range of the write block are not changed. No erase is needed.
ERASE_PROGRAM_EEPROM -	Not available.

PSP

These options let to configure and use the Parallel Slave Port on the supported devices.

Relevant Functions:	
setup_psp(mode)	Enables/disables the psp port on the chip
psp_output_full()	Returns 1 if the output buffer is full(waiting to be read by the external bus)
psp_input_full()	Returns 1 if the input buffer is full(waiting to read by the cpu)
psp_overflow()	Returns 1 if a write occurred before the previously written byte was read
Relevant Preprocessor:	
None	
Relevant Interrupts :	
INT_PSP	Interrupt fires when PSP data is in
Relevant Include Files: **None, all functions built-in**	
Relevant getenv() parameters:	
PSP	Returns 1 if the device has PSP
Example Code:	
while(psp_output_full());	//waits till the output buffer is cleared
psp_data=command;	//writes to the port
while(!input_buffer_full());	//waits till input buffer is cleared
if (psp_overflow())	
error=true	//if there is an overflow set the error flag
else	
data=psp_data;	//if there is no overflow then read the port

QEI

The Quadrature Encoder Interface (QEI) module provides the interface to incremental encoders for obtaining mechanical positional data.

Relevant Functions:	
setup_qei(options, filter,maxcount)	Configures the QEI module.
qei_status( )	Returns the status of the QUI module.
qei_set_count(value)	Write a 16-bit value to the position counter.
qei_get_count( )	Reads the current 16-bit value of the position counter.
Relevant Preprocessor:	
None	
Relevant Interrupts :	
#INT_QEI	Interrupt on rollover or underflow of the position counter.
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
None	
Example Code:	
int16 Value;	
setup_qei(QEI_MODE_X2 |	Setup the QEI module
QEI_TIMER_INTERNAL,	
QEI_FILTER_DIV_2,QEI_FORWARD);	
Value = qei_get_count( );	Read the count.

RS232 I/O

These functions and directives can be used for setting up and using RS232 I/O functionality.

Relevant Functions:	

getc() or getch()
getchar() or fgetc()
	Gets a character on the receive pin(from the specified stream in case of fgetc, stdin by default). Use KBHIT to check if the character is available.

gets() or fgets()	Gets a string on the receive pin(from the specified stream in case of fgets, STDIN by default). Use getc to receive each character until return is encountered.
putc() or putchar() or fputc()	Puts a character over the transmit pin(on the specified stream in the case of fputc, stdout by default)
puts() or fputs()	Puts a string over the transmit pin(on the specified stream in the case of fputc, stdout by default). Uses putc to send each character.
printf() or fprintf()	Prints the formatted string(on the specified stream in the case of fprintf, stdout by default). Refer to the printf help for details on format string.
kbhit()	Return true when a character is received in the buffer in case of hardware RS232 or when the first bit is sent on the RCV pin in case of software RS232. Useful for polling without waiting in getc.
setup_uart(baud,[stream])	
or	
setup_uart_speed(baud,[stream])	Used to change the baud rate of the hardware UART at run-time. Specifying stream is optional. Refer to the help for more advanced options.
assert(condition)	Checks the condition and if false prints the file name and line to STDERR. Will not generate code if #DEFINE NODEBUG is used.
perror(message)	Prints the message and the last system error to STDERR.
putc_send() or fputc_send()	When using transmit buffer, used to transmit data from buffer. See function description for more detail on when needed.
rcv_buffer_bytes()	When using receive buffer, returns the number of bytes in buffer that still need to be retrieved.
tx_buffer_bytes()	When using transmit buffer, returns the number of bytes in buffer that still need to be sent.
tx_buffer_full()	When using transmit buffer, returns TRUE if transmit buffer is full.
receive_buffer_full()	When using receive buffer, returns TRUE if receive buffer is full.
#useRS232	Configures the compiler to support RS232 to specifications.
Relevant Interrupts:	
INT_RDA	Interrupt fires when the receive data available
INT_TBE	Interrupt fires when the transmit data empty

Some chips have more than one hardware uart, and hence more interrupts.

Relevant Include Files:

None, all functions built-in

Relevant getenv() parameters:

UART	Returns the number of UARTs on this PIC
AUART	Returns true if this UART is an advanced UART
UART_RX	Returns the receive pin for the first UART on this PIC (see PIN_XX)
UART_TX	Returns the transmit pin for the first UART on this PIC
UART2_RX	Returns the receive pin for the second UART on this PIC
UART2_TX	TX – Returns the transmit pin for the second UART on this PIC

Example Code:

```
/* configure and enable uart, use first hardware UART on PIC */
  #use rs232(uart1, baud=9600)

 /* print a string */
  printf("enter a character");

  /* get a character */
 if (kbhit())                    //check if a character has been received
   c = getc();                   //read character from UART
```

RTOS

These functions control the operation of the CCS Real Time Operating System (RTOS). This operating system is cooperatively multitasking and allows for tasks to be scheduled to run at specified time intervals. Because the RTOS does not use interrupts, the user must be careful to make use of the rtos_yield() function in every task so that no one task is allowed to run forever.

Relevant Functions:

rtos_run()	Begins the operation of the RTOS. All task management tasks are implemented by this function.
rtos_terminate()	This function terminates the operation of the RTOS and returns operation to the original program. Works as a return from the rtos_run()function.
rtos_enable(task)	Enables one of the RTOS tasks. Once a task is enabled, the rtos_run() function will call the task when its time occurs. The parameter to this function is the name of task to be enabled.
rtos_disable(task)	Disables one of the RTOS tasks. Once a task is disabled, the rtos_run() function will not call this task until it is enabled using rtos_enable(). The parameter to this function is the name of the task to be disabled.

rtos_msg_poll()	Returns true if there is data in the task's message queue.
rtos_msg_read()	Returns the next byte of data contained in the task's message queue.
rtos_msg_send(task,byte)	Sends a byte of data to the specified task. The data is placed in the receiving task's message queue.
rtos_yield()	Called with in one of the RTOS tasks and returns control of the program to the rtos_run() function. All tasks should call this function when finished.
rtos_signal(sem)	Increments a semaphore which is used to broadcast the availability of a limited resource.
rtos_wait(sem)	Waits for the resource associated with the semaphore to become available and then decrements to semaphore to claim the resource.
rtos_await(expre)	Will wait for the given expression to evaluate to true before allowing the task to continue.
rtos_overrun(task)	Will return true if the given task over ran its alloted time.
rtos_stats(task,stat)	Returns the specified statistic about the specified task. The statistics include the minimum and maximum times for the task to run and the total time the task has spent running.
Relevant Preprocessor:	
#USE RTOS(options)	This directive is used to specify several different RTOS attributes including the timer to use, the minor cycle time and whether or not statistics should be enabled.
#TASK(options)	This directive tells the compiler that the following function is to be an RTOS task.
#TASK	specifies the rate at which the task should be called, the maximum time the task shall be allowed to run, and how large it's queue should be
Relevant Interrupts:	
none	
Relevant Include Files:	
none all functions are built in	
Relevant getenv() Parameters:	
none	
Example Code:	
#USE RTOS(timer=0,minor_cycle=20ms)	// RTOS will use timer zero, minor cycle will be 20ms
...	
int sem;	
...	
#TASK(rate=1s,max=20ms,queue=5)	// Task will run at a rate of once per second

void task_name();	// with a maximum running time of 20ms and
	// a 5 byte queue
rtos_run();	// begins the RTOS
rtos_terminate();	// ends the RTOS
rtos_enable(task_name);	// enables the previously declared task.
rtos_disable(task_name);	// disables the previously declared task
rtos_msg_send(task_name,5);	// places the value 5 in task_names queue.
rtos_yield();	// yields control to the RTOS
rtos_sigal(sem);	// signals that the resource represented by sem is available.
For more information on the CCS RTOS please	

SPI

SPI™ is a fluid standard for 3 or 4 wire, full duplex communications named by Motorola. Most PIC devices support most common SPI™ modes. CCS provides a support library for taking advantage of both hardware and software based SPI™ functionality. For software support, see #USE SPI.

Relevant Functions:	

setup_spi(mode)
setup_spi2(mode)
setup_spi3 (mode)
setup_spi4 (mode)
	Configure the hardware SPI to the specified mode. The mode configures setup_spi2(mode) thing such as master or slave mode, clock speed and clock/data trigger configuration.

Note: for devices with dual SPI interfaces a second function, setup_spi2(), is provided to configure the second interface.	
spi_data_is_in()	Returns TRUE if the SPI receive buffer has a byte of data.
spi_data_is_in2()	

spi_write(value)
spi_write2(value)
	Transmits the value over the SPI interface. This will cause the data to be clocked out on the SDO pin.

spi_read(value)
spi_read2(value)
	Performs an SPI transaction, where the value is clocked out on the SDO pin and data clocked in on the SDI pin is returned. If you just want to clock in data then you can use spi_read() without a parameter**.**

Relevant Preprocessor:	
None	
Relevant Interrupts:	
#int_ssp **#int_ssp2**	Transaction (read or write) has completed on the indicated peripheral.
Relevant getenv() Parameters:	
SPI	Returns TRUE if the device has an SPI peripheral

Example Code:	
//configure the device to be a master, data transmitted on H-to-L clock transition	
setup_spi(SPI_MASTER | SPI_H_TO_L | SPI_CLK_DIV_16);	
spi_write(0x80);	//write 0x80 to SPI device
value=spi_read();	//read a value from the SPI device
value=spi_read(0x80);	//write 0x80 to SPI device the same time you are reading a value.

Timer0

These options lets the user configure and use timer0. It is available on all devices and is always enabled. The clock/counter is 8-bit on pic16s and 8 or 16 bit on pic18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:	
setup_timer_0(mode)	Sets the source, prescale etc for timer0
set_timer0(value) or set_rtcc(value)	Initializes the timer0 clock/counter. Value may be a 8 bit or 16 bit depending on the device.
value=get_timer0	Returns the value of the timer0 clock/counter
Relevant Preprocessor:	None
Relevant Interrupts :	
INT_TIMER0 or INT_RTCC	Interrupt fires when timer0 overflows
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
TIMER0	Returns 1 if the device has timer0
Example Code:	
For PIC18F452	
setup_timer_0(RTCC_INTERNAL |RTCC_DIV_2|RTCC_8_BIT);	//sets the internal clock as source //and prescale 2. At 20Mhz timer0
	//will increment every 0.4us in this
	//setup and overflows every
	//102.4us
set_timer0(0);	//this sets timer0 register to 0
time=get_timer0();	//this will read the timer0 register
	//value

Timer1

These options lets the user configure and use timer1. The clock/counter is 16-bit on pic16s and pic18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:	
setup_timer_1(mode)	Disables or sets the source and prescale for timer1
set_timer1(value)	Initializes the timer1 clock/counter
value=get_timer1	Returns the value of the timer1 clock/counter
Relevant Preprocessor:	
None	
Relevant Interrupts:	
INT_TIMER1	Interrupt fires when timer1 overflows
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
TIMER1	Returns 1 if the device has timer1
Example Code:	
For PIC18F452	
setup_timer_1(T1_DISABLED);	//disables timer1
or	
setup_timer_1(T1_INTERNAL|T1_DIV_BY_8);	//sets the internal clock as source
	//and prescale as 8. At 20Mhz timer1 will increment
	//every 1.6us in this setup and overflows every
	//104.896ms
set_timer1(0);	//this sets timer1 register to 0
time=get_timer1();	//this will read the timer1 register value

Timer2

These options lets the user configure and use timer2. The clock/counter is 8-bit on pic16s and pic18s. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:	
setup_timer_2 (mode,period,postscale)	Disables or sets the prescale, period and a postscale for timer2
set_timer2(value)	Initializes the timer2 clock/counter
value=get_timer2	Returns the value of the timer2 clock/counter

Relevant Preprocessor:	
None	
Relevant Interrupts:	
INT_TIMER2	Interrupt fires when timer2 overflows
Relevant Include Files:	
None, all functions built-in	
Relevant getenv() parameters:	
TIMER2	Returns 1 if the device has timer2
Example Code:	
For PIC18F452	
setup_timer_2(T2_DISABLED);	//disables timer2
or	
setup_timer_2(T2_DIV_BY_4,0xc0,2);	//sets the prescale as 4, period as 0xc0 and //postscales as 2.
	//At 20Mhz timer2 will increment every .8us in this
	//setup overflows every 154.4us and interrupt every 308.2us
set_timer2(0);	//this sets timer2 register to 0
time=get_timer2();	//this will read the timer1 register value

Timer3

Timer3 is very similar to timer1. So please refer to the Timer1 section for more details.

Timer4

Timer4 is very similar to Timer2. So please refer to the Timer2 section for more details.

Timer5

These options lets the user configure and use timer5. The clock/counter is 16-bit and is available only on 18Fxx31 devices. It counts up and also provides interrupt on overflow. The options available differ and are listed in the device header file.

Relevant Functions:	
setup_timer_5(mode)	Disables or sets the source and prescale for imer5
set_timer5(value)	Initializes the timer5 clock/counter
value=get_timer5	Returns the value of the timer51 clock/counter

Relevant Preprocessor:	
None	
Relevant Interrupts :	
INT_TIMER5	Interrupt fires when timer5 overflows
Relevant Include Files:	None, all functions built-in
Relevant getenv() parameters:	
TIMER5	Returns 1 if the device has timer5
Example Code:	
For PIC18F4431	
setup_timer_5(T5_DISABLED)	//disables timer5
or	
setup_timer_5(T5_INTERNAL|T5_DIV_BY_1);	//sets the internal clock as source and //prescale as 1.
	//At 20Mhz timer5 will increment every .2us in this
	//setup and overflows every 13.1072ms
set_timer5(0);	//this sets timer5 register to 0
time=get_timer5();	//this will read the timer5 register value

TimerA

These options lets the user configure and use timerA. It is available on devices with Timer A hardware. The clock/counter is 8 bit. It counts up and also provides interrupt on overflow. The options available are listed in the device's header file.

Relevant Functions:	
setup_timer_A(mode)	Disable or sets the source and prescale for timerA
set_timerA(value)	Initializes the timerA clock/counter
value=get_timerA()	Returns the value of the timerA clock/counter
Relevant Preprocessor:	
None	
Relevant Interrupts :	
INT_TIMERA	Interrupt fires when timerA overflows
Relevant Include Files:	None, all functions built-in
Relevant getenv() parameters:	
TIMERA	Returns 1 if the device has timerA
Example Code:	

setup_timer_A(TA_OFF);	//disable timerA
or	
setup_timer_A	//sets the internal clock as source
(TA_INTERNAL | TA_DIV_8);	//and prescale as 8. At 20MHz timerA will increment
	//every 1.6us in this setup and overflows every
	//409.6us
set_timerA(0);	//this sets timerA register to 0
time=get_timerA();	//this will read the timerA register value

TimerB

These options lets the user configure and use timerB. It is available on devices with TimerB hardware. The clock/counter is 8 bit. It counts up and also provides interrupt on overflow. The options available are listed in the device's header file.

Relevant Functions:	
setup_timer_B(mode)	Disable or sets the source and prescale for timerB
set_timerB(value)	Initializes the timerB clock/counter
value=get_timerB()	Returns the value of the timerB clock/counter
Relevant Preprocessor:	
None	
Relevant Interrupts :	
INT_TIMERB	Interrupt fires when timerB overflows
Relevant Include Files:	None, all functions built-in
Relevant getenv() parameters:	
TIMERB	Returns 1 if the device has timerB
Example Code:	
setup_timer_B(TB_OFF);	//disable timerB
or	
setup_timer_B	//sets the internal clock as source
(TB_INTERNAL | TB_DIV_8);	//and prescale as 8. At 20MHz timerB will increment
	//every 1.6us in this setup and overflows every
	//409.6us
set_timerB(0);	//this sets timerB register to 0
time=get_timerB();	//this will read the timerB register value

USB

Universal Serial Bus, or USB, is used as a method for peripheral devices to connect to and talk to a personal computer. CCS provides libraries for interfacing a PIC to PC using USB by using a PIC with an internal USB peripheral (like the PIC16C765 or the PIC18F4550 family) or by using any PIC with an external USB peripheral (the National USBN9603 family).

Relevant Functions:	
usb_init()	Initializes the USB hardware. Will then wait in an infinite loop for the USB peripheral to be connected to bus (but that doesn't mean it has been enumerated by the PC). Will enable and use the USB interrupt.
usb_init_cs()	The same as usb_init(), but does not wait for the device to be connected to the bus. This is useful if your device is not bus powered and can operate without a USB connection.
usb_task()	If you use connection sense, and the usb_init_cs() for initialization, then you must periodically call this function to keep an eye on the connection sense pin. When the PIC is connected to the BUS, this function will then perpare the USB peripheral. When the PIC is disconnected from the BUS, it will reset the USB stack and peripheral. Will enable and use the USB interrupt.
Note: In your application you must define USB_CON_SENSE_PIN to the connection sense pin.	
usb_detach()	Removes the PIC from the bus. Will be called automatically by usb_task() if connection is lost, but can be called manually by the user.
usb_attach()	Attaches the PIC to the bus. Will be called automatically by usb_task() if connection is made, but can be called manually by the user.
usb_attached()	If using connection sense pin (USB_CON_SENSE_PIN), returns TRUE if that pin is high. Else will always return TRUE.
usb_enumerated()	Returns TRUE if the device has been enumerated by the PC. If the device has been enumerated by the PC, that means it is in normal operation mode and you can send/receive packets.
usb_put_packet (endpoint, data, len, tgl)	Places the packet of data into the specified endpoint buffer. Returns TRUE if success, FALSE if the buffer is still full with the last packet.
usb_puts (endpoint, data, len, timeout)	Sends the following data to the specified endpoint. usb_puts() differs from usb_put_packet() in that it will send multi packet messages if the data will not fit into one packet.
usb_kbhit(endpoint)	Returns TRUE if the specified endpoint has data in it's receive buffer
usb_get_packet (endpoint, ptr, max)	Reads up to max bytes from the specified endpoint buffer and saves it to the pointer ptr. Returns the number of bytes saved to ptr.
usb_gets(endpoint, ptr, max, timeout)	Reads a message from the specified endpoint. The difference usb_get_packet() and usb_gets() is that usb_gets() will wait until a full message has received, which a message may contain more than one

	packet. Returns the number of bytes received.
Relevant CDC Functions:	
A CDC USB device will emulate an RS-232 device, and will appear on your PC as a COM port. The follow functions provide you this virtual RS-232/serial interface	
Note: When using the CDC library, you can use the same functions above, but do not use the packet related function such as usb_kbhit(), usb_get_packet(), etc.	
usb_cdc_kbhit()	The same as kbhit(), returns TRUE if there is 1 or more character in the receive buffer.
usb_cdc_getc()	The same as getc(), reads and returns a character from the receive buffer. If there is no data in the receive buffer it will wait indefinitely until there a character has been received.
usb_cdc_putc(c)	The same as putc(), sends a character. It actually puts a character into the transmit buffer, and if the transmit buffer is full will wait indefinitely until there is space for the character.
usb_cdc_putc_fast(c)	The same as usb_cdc_putc(), but will not wait indefinitely until there is space for the character in the transmit buffer. In that situation the character is lost.
usb_cdc_puts(*str)	Sends a character string (null terminated) to the USB CDC port. Will return FALSE if the buffer is busy, TRUE if buffer is string was put into buffer for sending. Entire string must fit into endpoint, if string is longer than endpoint buffer then excess characters will be ignored.
usb_cdc_putready()	Returns TRUE if there is space in the transmit buffer for another character.
Relevant Preporcessor:	
None	
Relevant Interrupts:	
#int_usb	A USB event has happened, and requires application intervention. The USB library that CCS provides handles this interrupt automatically.
Relevant Include files:	
pic_usb.h	Hardware layer driver for the PIC16C765 family PICmicro controllers with an internal USB peripheral.
pic18_usb.h	Hardware layer driver for the PIC18F4550 family PICmicro controllers with an internal USB peripheral.
usbn960x.h	Hardware layer driver for the National USBN9603/USBN9604 external USB peripheral. You can use this external peripheral to add USB to any microcontroller.
usb.h	Common definitions and prototypes used by the USB driver

usb.c	The USB stack, which handles the USB interrupt and USB Setup Requests on Endpoint 0.
usb_cdc.h	A driver that takes the previous include files to make a CDC USB device, which emulates an RS232 legacy device and shows up as a COM port in the MS Windows device manager.
Relevant getenv() Parameters:	
USB	Returns TRUE if the PICmicro controller has an integrated internal USB peripheral.
Example Code:	
Due to the complexity of USB example code will not fit here. But you can find the following examples installed with your CCS C Compiler:	
ex_usb_hid.c	A simple HID device
ex_usb_mouse.c	A HID Mouse, when connected to your PC the mouse cursor will go in circles.
ex_usb_kbmouse.c	An example of how to create a USB device with multiple interfaces by creating a keyboard and mouse in one device.
ex_usb_kbmouse2.c	An example of how to use multiple HID report Ids to transmit more than one type of HID packet, as demonstrated by a keyboard and mouse on one device.
ex_usb_scope.c	A vendor-specific class using bulk transfers is demonstrated.
ex_usb_serial.c	The CDC virtual RS232 library is demonstrated with this RS232 < - > USB example.
ex_usb_serial2.c	Another CDC virtual RS232 library example, this time a port of the ex_intee.c example to use USB instead of RS232.

Voltage Reference

These functions configure the votlage reference module. These are available only in the supported chips.

Relevant Functions:	
setup_vref(mode | value)	Enables and sets up the internal voltage reference value. Constants are defined in the device's .h file.
Relevant Preprocesser: **none**	
Relevant Interrupts: **none**	
Relevant Include Files: **none, all functions built-in**	

Relevant getenv() parameters:	
VREF	Returns 1 if the device has VREF
Example code:	
for PIC12F675	

```
#INT_COMP //comparator interrupt
handler
void isr() {
   safe_conditions = FALSE;
   printf("WARNING!!!! Voltage level
is above 3.6V. \r\n");
}

setup_comparator(A1_VR_OUT_ON
_A2)//sets 2 comparators(A1 and VR
and A2 as output)
{
   setup_vref(VREF_HIGH |
15);//sets 3.6(vdd * value/32 + vdd/4)
if vdd is 5.0V
   enable_interrupts(INT_COMP); //
enable the comparator interrupt
   enable_interrupts(GLOBAL);
//enable global interrupts
}
```

WDT or Watch Dog Timer

Different chips provide different options to enable/disable or configure the WDT.

Relevant Functions:	
setup_wdt()	Enables/disables the wdt or sets the prescalar.
restart_wdt()	Restarts the wdt, if wdt is enables this must be periodically called to prevent a timeout reset.

For PCB/PCM chips it is enabled/disabled using WDT or NOWDT fuses whereas on PCH device it is done using the setup_wdt function.

The timeout time for PCB/PCM chips are set using the setup_wdt function and on PCH using fuses like WDT16, WDT256 etc.

RESTART_WDT when specified in #USE DELAY, #USE I2C and #USE RS232 statements like this #USE DELAY(clock=20000000, restart_wdt) will cause the wdt to restart if it times out during the delay or I2C_READ or GETC.

Relevant Preprocessor:	
#FUSES WDT/NOWDT	Enabled/Disables wdt in PCB/PCM devices
#FUSES WDT16	Sets ups the timeout time in PCH devices
Relevant Interrupts:	
None	

Relevant Include Files:

None, all functions built-in

Relevant getenv() parameters:

None

Example Code:

For PIC16F877

```
#fuses wdt
 setup_wdt(WDT_2304MS);
  while(true){
     restart_wdt();
     perform_activity();
      }
```

For PIC18F452

```
#fuse WDT1
setup_wdt(WDT_ON);
while(true){
     restart_wdt();
     perform_activity();
  }
```

Some of the PCB chips are share the WDT prescalar bits with timer0 so the WDT prescalar constants can be used with setup_counters or setup_timer0 or setup_wdt functions.

interrupt_enabled()

This function checks the interrupt enabled flag for the specified interrupt and returns TRUE if set.

Syntax	**interrupt_enabled(interrupt);**
Parameters	interrupt- constant specifying the interrupt
Returns	Boolean value
Function	The function checks the interrupt enable flag of the specified interrupt and returns TRUE when set.
Availability	Devices with interrupts
Requires	Interrupt constants defined in the device's .h file.

Examples	if(interrupt_enabled(INT_RDA))
	    disable_interrupt(INT_RDA);

Example Files	None
Also see	DISABLE_INTERRUPTS(), , Interrupts Overview, CLEAR_INTERRUPT(), ENABLE_INTERRUPTS(),,INTERRUPT_ACTIVE()

Stream I/O

Syntax: **#include <ios.h> is required to use any of the ios identifiers.**

Output:

output:

stream << variable_or_constant_or_manipulator ;

____

one or more repeats

stream may be the name specified in the #use RS232 stream= option
or for the default stream use cout.

stream may also be the name of a char array. In this case the data is
written to the array with a 0 terminator.

stream may also be the name of a function that accepts a single char
parameter. In this case the function is called for each character to be
output.

variables/constants: May be any integer, char, float or fixed type. Char
arrays are
output as strings and all other types are output as an address of the
variable.

manipulators:

hex -Hex format numbers
dec- Decimal format numbers (default)
setprecision(x) -Set number of places after the decimal point
setw(x) -Set total number of characters output for numbers
boolalpha- Output int1 as true and false
noboolalpha -Output int1 as 1 and 0 (default)
fixed Floats- in decimal format (default)
scientific Floats- use E notation
iosdefault- All manipulators to default settings
endl -Output CR/LF
ends- Outputs a null ('\000')

Examples:

```
cout << "Value is " << hex << data << endl;
cout << "Price is $" << setw(4) << setprecision(2) << cost << endl;
lcdputc << '\f' << setw(3) << count << "    " << min << "    " << max;
string1 << setprecision(1) << sum / count;
string2 << x << ',' << y;
```

Input:

stream >> variable_or_constant_or_manipulator ;

____

one or more repeats

stream may be the name specified in the #use RS232 stream= option
or for the default stream use cin.

stream may also be the name of a char array. In this case the data is
read from the array up to the 0 terminator.

stream may also be the name of a function that returns a single char and has
no parameters. In this case the function is called for each character to be input.
Make sure the function returns a \r to terminate the input statement.

variables/constants: May be any integer, char, float or fixed type. Char arrays are
input as strings. Floats may use the E format.
Reading of each item terminates with any character not valid for the type. Usually
items are separated by spaces. The termination character is discarded. At the end
of any stream input statement characters are read until a return (\r) is read. No
termination character is read for a single char input.

manipulators:
hex -Hex format numbers
dec- Decimal format numbers (default)
noecho- Suppress echoing
strspace- Allow spaces to be input into strings
nostrspace- Spaces terminate string entry (default)
iosdefault -All manipulators to default settings

Examples:

```
cout << "Enter number: ";
cin >> value;
cout << "Enter title: ";
cin >> strspace >> title;
cin >> data[i].recordid >> data[i].xpos >> data[i].ypos >> data[i].sample ;
string1 >> data;
lcdputc << "\fEnter count";
lcdputc << keypadgetc >> count;     // read from keypad, echo to lcd
                                           // This syntax only works with
                                           // user defined functions.
```

PREPROCESSOR

PRE-PROCESSOR DIRECTORY

Pre-processor directives all begin with a # and are followed by a specific command. Syntax is dependent on the command. Many commands do not allow other syntactical elements on the remainder of the line. A table of commands and a description is listed on the previous page.

Several of the pre-processor directives are extensions to standard C. C provides a pre-processor directive that compilers will accept and ignore or act upon the following data. This implementation will allow any pre-processor directives to begin with #PRAGMA. To be compatible with other compilers, this may be used before non-standard features.

Examples:
Both of the following are valid

```
#INLINE
#PRAGMA INLINE
```

__address__

A predefined symbol __address__ may be used to indicate a type that must hold a program memory address.

For example:

```
       ___address__ testa = 0x1000  //will allocate 16 bits for test a and
                                    //initialize to 0x1000
```

_attribute_x

Syntax:	**__attribute__x**

Elements:	x is the attribute you want to apply. Valid values for x are as follows:
	
	((packed))
	By default each element in a struct or union are padded to be evenly spaced by the size of 'int'. This is to prevent an address fault when accessing an element of struct. See the following example:
	struct
	{
	    int8 a;
	    int16 b;
	  } test;
	
	On architectures where 'int' is 16bit (such as dsPIC or PIC24 PICmicrocontrollers), 'test' would take 4 bytes even though it is comprised of3 bytes. By applying the 'packed' attribute to this struct then it would take 3 bytes as originally intended:
	struct __attribute__((packed))
	{
	    int8 a;
	    int16 b;
	  } test;
	
	Care should be taken by the user when accessing individual elements of a packed struct – creating a pointer to 'b' in 'test' and attempting to dereference that pointer would cause an address fault. Any attempts to read/write 'b' should be done in context of 'test' so the compiler knows it is packed:
	test.b = 5;
	
	((aligned(y))
	By default the compiler will alocate a variable in the first free memory location. The aligned attribute will force the compiler to allocate a location for the specified variable at a location that is modulus of the y parameter. For example:
	  int8 array[256] __attribute__((aligned(0x1000)));
	This will tell the compiler to try to place 'array' at either 0x0, 0x1000, 0x2000, 0x3000, 0x4000, etc.

Purpose	To alter some specifics as to how the compiler operates

Examples:	struct __attribute__((packed))
	{
	  int8 a;
	  int8 b;
	} test;
	int8 array[256] __attribute__((aligned(0x1000)));

Example Files:	None

#asm #endasm #asm asis

Syntax:	**#ASM or #ASM ASIS code #ENDASM**
Elements:	code is a list of assembly language instructions
Examples:	see below

```
int find_parity(int data){

   int count;
   #asm
   MOV #0x08, W0
   MOV W0, count
   CLR W0
   loop:
   XOR.B data,W0
   RRC data,W0
   DEC count,F
   BRA NZ, loop
   MOV #0x01,W0
   ADD count,F
   MOV count, W0
   MOV W0. _RETURN_
   #endasm
}
```

Example Files:	FFT.c
Also See:	None

12 Bit and 14 Bit	
ADDWF f,d	ANDWF f,d
CLRF f	CLRW
COMF f,d	DECF f,d
DECFSZ f,d	INCF f,d
INCFSZ f,d	IORWF f,d
MOVF f,d	MOVPHW
MOVPLW	MOVWF f
NOP	RLF f,d
RRF f,d	SUBWF f,d
SWAPF f,d	XORWF f,d

BCF f,b	BSF f,b
BTFSC f,b	BTFSS f,b
ANDLW k	CALL k
CLRWDT	GOTO k
IORLW k	MOVLW k
RETLW k	SLEEP
XORLW	OPTION
TRIS k	
	14 Bit
	ADDLW k
	SUBLW k
	RETFIE
	RETURN

f	**may be a constant (file number) or a simple variable**
d	may be a constant (0 or 1) or W or F
f,b	may be a file (as above) and a constant (0-7) or it may be just a bit variable reference.
k	may be a constant expression

Note that all expressions and comments are in C like syntax.

PIC 18					
ADDWF	f,d	ADDWFC	f,d	ANDWF	f,d
CLRF	f	COMF	f,d	CPFSEQ	f
CPFSGT	f	CPFSLT	f	DECF	f,d
DECFSZ	f,d	DCFSNZ	f,d	INCF	f,d
INFSNZ	f,d	IORWF	f,d	MOVF	f,d
MOVFF	fs,d	MOVWF	f	MULWF	f
NEGF	f	RLCF	f,d	RLNCF	f,d
RRCF	f,d	RRNCF	f,d	SETF	f
SUBFWB	f,d	SUBWF	f,d	SUBWFB	f,d
SWAPF	f,d	TSTFSZ	f	XORWF	f,d
BCF	f,b	BSF	f,b	BTFSC	f,b
BTFSS	f,b	BTG	f,d	BC	n
BN	n	BNC	n	BNN	n
BNOV	n	BNZ	n	BOV	n
BRA	n	BZ	n	CALL	n,s
CLRWDT	-	DAW	-	GOTO	n
NOP	-	NOP	-	POP	-
PUSH	-	RCALL	n	RESET	-
RETFIE	s	RETLW	k	RETURN	s
SLEEP	-	ADDLW	k	ANDLW	k
IORLW	k	LFSR	f,k	MOVLB	k
MOVLW	k	MULLW	k	RETLW	k
SUBLW	k	XORLW	k	TBLRD	*
TBLRD	*+	TBLRD	*-	TBLRD	+*
TBLWT	*	TBLWT	*+	TBLWT	*-
TBLWT	+*				

The compiler will set the access bit depending on the value of the file register.

If there is just a variable identifier in the #asm block then the compiler inserts an & before it. And if it is an expression it must be a valid C expression that evaluates to a constant (no & here). In C an un-subscripted array name is a pointer and a constant (no need for &).

#bit

Syntax:	**#BIT *id = x.y***
Elements:	***id*** is a valid C identifier, ***x*** is a constant or a C variable, ***y*** is a constant 0-7
Purpose:	A new C variable (one bit) is created and is placed in memory at byte x and bit y. This is useful to gain access in C directly to a bit in the processors special function register map. It may also be used to easily access a bit of a standard C variable.

Examples:	`#bit T0IF = 0x b.2`
	`...`
	`T1IF = 0; // Clear Timer 0 interrupt flag`
	
	`int result;`
	`#bit result_odd = result.0`
	`...`
	`if (result_odd)`

Example Files:	ex_glint.c
Also See:	#BYTE, #RESERVE, #LOCATE, #WORD

__buildcount__

Only defined if Options>Project Options>Global Defines has global defines enabled.

This id resolves to a number representing the number of successful builds of the project.

#build

Syntax:	**#BUILD(*segment* = *address*)**
	#BUILD(*segment* = *address*, *segment* = *address*)
	#BUILD(*segment* = *start*:*end*)
	#BUILD(*segment* = *start*: *end*, *segment* = *start*: *end*)
	#BUILD(*nosleep*)

Elements:	***segment*** is one of the following memory segments which may be assigned a location: MEMORY, RESET, or INTERRUPT ***address*** is a ROM location memory address. ***Start*** and ***end*** are used to specify a range in memory to be used.

	start is the first ROM location and ***end*** is the last ROM location to be used. ***nosleep*** is used to prevent the compiler from inserting a sleep at the end of main() ***Bootload*** produces a bootloader-friendly hex file (in order, full block size). **NOSLEEP_LOCK** is used instead of A sleep at the end of a main A infinite loop.
Purpose:	PIC18XXX devices with external ROM or PIC18XXX devices with no internal ROM can direct the compiler to utilize the ROM. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

Examples:	`#build(memory=0x20000:0x2FFFF)      //Assigns memory space`
	`#build(reset=0x200,interrupt=0x208) //Assigns start`
	`                                    //location`
	`                                    //of reset and`
	`                                    //interrupt`
	`                                    //vectors`
	`#build(reset=0x200:0x207, interrupt=0x208:0x2ff)`
	`                                    //Assign limited space`
	`                                    //for reset and`
	`                                    //interrupt vectors.`
	`#build(memory=0x20000:0x2FFFF)      //Assigns memory space`

Example Files:	None
Also See:	#LOCATE, #RESERVE, #ROM, #ORG

#byte

Syntax:	**#byte *id* = *x***
Elements:	***id*** is a valid C identifier, ***x*** is a C variable or a constant
Purpose:	If the id is already known as a C variable then this will locate the variable at address x. In this case the variable type does not change from the original definition. If the id is not known a new C variable is created and placed at address x with the type int (8 bit) Warning: In both cases memory at x is not exclusive to this variable. Other variables may be located at the same location. In fact when x is a variable, then id and x share the same memory location.

Examples:	`#byte  status = 3`
	`#byte  b_port = 6`
	
	`struct  {`
	`  short int r_w;`
	`  short int c_d;`
	`    int unused : 2;`
	`  int data    : 4 ; } a _port;`

	`#byte a_port = 5`
	`...`
	`a_port.c_d = 1;`

Example Files:	ex_glint.c
Also See:	#bit, #locate, #reserve, #word, Named Registers, Type Specifiers, Type Qualifiers, Enumerated Types, Structures & Unions, Typedef

#case

Syntax:	**#CASE**
Elements:	None
Purpose:	Will cause the compiler to be case sensitive. By default the compiler is case insensitive. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit. Warning: Not all the CCS example programs, headers and drivers have been tested with case sensitivity turned on.
Examples:	see below
Example Files:	ex_cust.c
Also See:	None

```
#case

int STATUS;

void func() {
int status;
...
STATUS = status; // Copy local status to
                 //global
}
```

date

Syntax:	**__DATE__**
Elements:	None
Purpose:	This pre-processor identifier is replaced at compile time with the date of the compile in the form: "31-JAN-03"

Examples:	`printf("Software was compiled on ");`
	`printf(__DATE__);`

Example	None

Files:	
Also See:	None

#define

Syntax:	**#define *id* text** **or** **#define *id*(*x*,*y*...) text**
Elements:	***id*** is a preprocessor identifier, text is any text, ***x***,***y*** is a list of local preprocessor identifiers, and in this form there may be one or more identifiers separated by commas.
Purpose:	Used to provide a simple string replacement of the ID with the given text from this point of the program and on. In the second form (a C macro) the local identifiers are matched up with similar identifiers in the text and they are replaced with text passed to the macro where it is used. If the text contains a string of the form #idx then the result upon evaluation will be the parameter id concatenated with the string x. If the text contains a string of the form #idx#idy then parameter idx is concatenated with parameter idy forming a new identifier. Within the define text two special operators are supported: #x is the stringize operator resulting in "x" x##y is the concatination operator resulting in xy The varadic macro syntax is supported where the last parameter is specified as ... and the local identifier used is __va_args__. In this case, all remaining arguments are combined with the commas.

Examples:

```
#define  BITS  8
a=a+BITS;   //same as   a=a+8;


#define hi(x)  (x<<4)
a=hi(a);    //same as   a=(a<<4);

#define isequal(a,b)   (primary_##a[b]==backup_##a[b])
            // usage iseaqual(names,5)  is the same as
            // (primary_names[5]==backup_names[5])

#define str(s)  #s
#define part(device)  #include str(device##.h)
            // usage part(16F887) is the same as
            // #include "16F887.h"

#define DBG(...)      fprintf(debug,__VA_ARGS__)
```

Example Files: ex_stwt.c, ex_macro.c

Also See:	#UNDEF, #IFDEF, #IFNDEF

definedinc

Syntax:	**value = definedinc(** ***variable*** **);**
Parameters:	***variable*** is the name of the variable, function, or type to be checked.
Returns:	A C status for the type of ***id*** entered as follows: 0 – not known 1 – typedef or enum 2 – struct or union type 3 – typemod qualifier 4 – defined function 5 – function prototype 6 – compiler built-in function 7 – local variable 8 – global variable
Function:	This function checks the type of the variable or function being passed in and returns a specific C status based on the type.
Availability:	All devices
Requires:	None.
Examples:	int x, y = 0; y = definedinc(x); // y will return 7 – x is a local variable
Example Files:	None
Also See:	None

#device

Syntax:	**#DEVICE** ***chip options*** **#DEVICE** ***Compilation mode selection***
Elements:	***Chip Options-*** ***chip*** is the name of a specific processor (like: PIC16C74), To get a current list of supported devices: START | RUN | CCSC +Q ***Options*** are qualifiers to the standard operation of the device. Valid options are:

***=5**	**Use 5 bit pointers (for all parts)**
***=8**	Use 8 bit pointers (14 and 16 bit parts)
***=16**	Use 16 bit pointers (for 14 bit parts)
ADC=x	Where x is the number of bits read_adc() should return
ICD=TRUE	Generates code compatible with Microchips ICD debugging hardware.
ICD=n	For chips with multiple ICSP ports specify the port number being used. The default is 1.
WRITE_EEPROM=ASYNC	Prevents WRITE_EEPROM from hanging while writing is taking place. When used, do not write to EEPROM from both ISR and outside ISR.
WRITE_EEPROM = NOINT	Allows interrupts to occur while the write_eeprom() operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.
HIGH_INTS=TRUE	Use this option for high/low priority interrupts on the PIC® 18.
%f=.	No 0 before a decimal pint on %f numbers less than 1.
OVERLOAD=KEYWORD	Overloading of functions is now supported. Requires the use of the keyword for overloading.
OVERLOAD=AUTO	Default mode for overloading.
PASS_STRINGS=IN_RAM	A new way to pass constant strings to a function by first copying the string to RAM and then passing a pointer to RAM to the function.
CONST=READ_ONLY	Uses the ANSI keyword CONST definition, making CONST variables read only, rather than located in program memory.
CONST=ROM	Uses the CCS compiler traditional keyword CONST definition, making CONST variables located in program memory.
NESTED_INTERRUPTS=TRUE	Enables interrupt nesting for PIC24, dsPIC30, and dsPIC33 devices. Allows higher priority interrupts to interrupt lower priority interrupts.
NORETFIE	ISR functions (preceeded by a #int_xxx) will use a RETURN opcode instead of the RETFIE opcode. This is not a commonly used option; used rarely in cases where the user is writing their own ISR handler.
NO_DIGITAL_INIT	Normally the compiler sets all I/O pins to digital and turns off the comparator. This option prevents that action.

Both chip and options are optional, so multiple #DEVICE lines may be used to fully define the device. Be warned that a #DEVICE with a chip identifier, will clear all previous #DEVICE and #FUSE settings.

Compilation mode selection-

The #DEVICE directive supports compilation mode selection. The valid keywords are CCS2, CCS3, CCS4 and ANSI. The default mode is CCS4. For the CCS4 and ANSI mode, the compiler uses the default fuse settings NOLVP, PUT for chips with these fuses. The NOWDT fuse is default if no call is made to restart_wdt().

CCS4	**This is the default compilation mode. The pointer size in this mode for PCM and PCH is set to *=16 if the part has RAM over 0FF.**
ANSI	Default data type is SIGNED all other modes default is UNSIGNED. Compilation is case sensitive, all other modes are case insensitive. Pointer size is set to *=16 if the part has RAM over 0FF.
CCS2 CCS3	var16 = NegConst8 is compiled as: var16 = NegConst8 & 0xff (no sign extension) Pointer size is set to *=8 for PCM and PCH and *=5 for PCB . The overload

		keyword is required.

	CCS2 only	The default #DEVICE ADC is set to the resolution of the part, all other modes default to 8.
		onebit = eightbits is compiled as onebit = (eightbits != 0)
		All other modes compile as: onebit = (eightbits & 1)

Purpose:	***Chip Options*** -Defines the target processor. Every program must have exactly one #DEVICE with a chip. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit. ***Compilation mode selection*** - The compilation mode selection allows existing code to be compiled without encountering errors created by compiler compliance. As CCS discovers discrepancies in the way expressions are evaluated according to ANSI, the change will generally be made only to the ANSI mode and the next major CCS release.

Examples:	***Chip Options-***
	`#device PIC16C74`
	`#device PIC16C67 *=16`
	`#device *=16  ICD=TRUE`
	`#device PIC16F877 *=16 ADC=10`
	`#device %f=.`
	`printf("%f",.5); //will print .5, without the directive it will print 0.5`
	
	Compilation mode selection-
	`#device CCS2    // This will set the ADC to the resolution of the part`

Example Files:	ex_mxram.c , ex_icd.c , 16c74.h ,
Also See:	read_adc()

## _device_

Syntax:	**__DEVICE__**
Elements:	None
Purpose:	This pre-processor identifier is defined by the compiler with the base number of the current device (from a #DEVICE). The base number is usually the number after the C in the part number. For example the PIC16C622 has a base number of 622.

Examples:	`#if __device__==71`
	`SETUP_ADC_PORTS( ALL_DIGITAL );`
	`#endif`

Example Files:	None
Also See:	#DEVICE

#if expr #else #elif #endif

Syntax:	**#if *expr*** ***code*** **#elif expr //Optional, any number may be used** ***code*** **#else //Optional** ***code*** **#endif**
Elements:	***expr*** is an expression with constants, standard operators and/or preprocessor identifiers. ***Code*** is any standard c source code.
Purpose:	The pre-processor evaluates the constant expression and if it is non-zero will process the lines up to the optional #ELSE or the #ENDIF. Note: you may NOT use C variables in the #IF. Only preprocessor identifiers created via #define can be used. The preprocessor expression DEFINED(id) may be used to return 1 if the id is defined and 0 if it is not. == and != operators now accept a constant string as both operands. This allows for compile time comparisons and can be used with GETENV() when it returns a string result.

Examples:	`#if MAX_VALUE > 255`
	 `  long value;`
	 `#else`
	 `  int value;`
	 `#endif`
	 `#if getenv("DEVICE")=="PIC16F877"`
	 `  //do something special for the PIC16F877`
	 `#endif`

Example Files:	ex_extee.c
Also See:	#IFDEF, #IFNDEF, getenv()

#error

Syntax:	**#ERROR *text*** **#ERROR / warning *text*** **#ERROR / information *text***
Elements:	***text*** is optional and may be any text
Purpose:	Forces the compiler to generate an error at the location this directive appears in the file. The text may include macros that will be expanded for the display. This may be used to see the macro expansion. The command may also be used to alert the user to an invalid compile time situation.

Examples:	`#if  BUFFER_SIZE>16`
	`#error  Buffer size is too large`
	`#endif`
	`#error   Macro test:  min(x,y)`

Example Files:	ex_psp.c
Also See:	#WARNING

#export (options)

Syntax:	**#EXPORT (options)**
Elements:	***FILE=filname*** The filename which will be generated upon compile. If not given, the filname will be the name of the file you are compiling, with a .o or .hex extension (depending on output format). ***ONLY=symbol+symbol+.....+symbol*** Only the listed symbols will be visible to modules that import or link this relocatable object file. If neither ONLY or EXCEPT is used, all symbols are exported. ***EXCEPT=symbol+symbol+.....+symbol*** All symbols except the listed symbols will be visible to modules that import or link this relocatable object file. If neither ONLY or EXCEPT is used, all symbols are exported. ***RELOCATABLE*** CCS relocatable object file format. Must be imported or linked before loading into a PIC. This is the default format when the #EXPORT is used. ***HEX*** Intel HEX file format. Ready to be loaded into a PIC. This is the default format when no #EXPORT is used. ***RANGE=start:stop*** Only addresses in this range are included in the hex file. ***OFFSET=address*** Hex file address starts at this address (0 by default) ***ODD*** Only odd bytes place in hex file. ***EVEN*** Only even bytes placed in hex file.
Purpose:	This directive will tell the compiler to either generate a relocatable object file or a stand-alone HEX binary. A relocatable object file must be linked into your application, while a stand-alone HEX binary can be programmed directly into the PIC. The command line compiler and the PCW IDE Project Manager can also be used to compile/link/build

	modules and/or projects. Multiple #EXPORT directives may be used to generate multiple hex files. this may be used for 8722 like devices with external memory.

Examples:	`#EXPORT(RELOCATABLE, ONLY=TimerTask)`
	`void TimerFunc1(void) { /* some code */ }`
	`void TimerFunc2(void) { /* some code */ }`
	`void TimerFunc3(void) { /* some code */ }`
	`void TimerTask(void)`
	`{`
	`    TimerFunc1();`
	`    TimerFunc2();`
	`    TimerFunc3();`
	`}`
	`/*`
	`This source will be compiled into a relocatable object, but the object this is being linked to can only see TimerTask()`
	`*/`

Example Files:	None
See Also:	#IMPORT, #MODULE, Invoking the Command Line Compiler, Multiple Compilation Unit

__file__

Syntax:	**__FILE__**
Elements:	None
Purpose:	The pre-processor identifier is replaced at compile time with the file path and the filename of the file being compiled.

Examples:	`if(index>MAX_ENTRIES)`
	`   printf("Too many entries, source file: "`
	`       __FILE__ " at line " __LINE__ "\r\n");`

Example Files:	assert.h
Also See:	__ line __

__filename__

Syntax:	**__FILENAME__**
Elements:	None

Purpose:	The pre-processor identifier is replaced at compile time with the filename of the file being compiled.

Examples:	`if(index>MAX_ENTRIES)`
	`   printf("Too many entries, source file: "`
	`       __FILENAME__ " at line " __LINE__ "\r\n");`

Example Files:	None
Also See:	__line__

#fill_rom

Syntax:	**#fill_rom *value***
Elements:	***value*** is a constant 16-bit value
Purpose:	This directive specifies the data to be used to fill unused ROM locations. When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.
Examples:	`#fill_rom 0x36`
Example Files:	None
Also See:	#ROM

#fuses

Syntax:	**#FUSES *options***
Elements:	***options*** vary depending on the device. A list of all valid options has been put at the top of each devices .h file in a comment for reference. The PCW device edit utility can modify a particular devices fuses. The PCW pull down menu VIEW | Valid fuses will show all fuses with their descriptions. Some common options are: • LP, XT, HS, RC • WDT, NOWDT • PROTECT, NOPROTECT • PUT, NOPUT (Power Up Timer) • BROWNOUT, NOBROWNOUT
Purpose:	This directive defines what fuses should be set in the part when it is programmed. This directive does not affect the compilation; however, the information is put in the output files. If the fuses need to be in Parallax format, add a PAR option. SWAP has the special function of swapping (from the Microchip standard) the high and low BYTES of non-program data in the Hex file. This is required for some device programmers.

Some fuses are set by the compiler based on other compiler directives. For example, the oscillator fuses are set up by the #USE delay directive. The debug, No debug and ICSPN Fuses are set by the #DEVICE ICD=directive.

Some processors allow different levels for certain fuses. To access these levels, assign a value to the fuse. For example, on the 18F452, the fuse PROTECT=6 would place the value 6 into CONFIG5L, protecting code blocks 0 and 3.

When linking multiple compilation units be aware this directive applies to the final object file. Later files in the import list may reverse settings in previous files.

To eliminate all fuses in the output files use:

#FUSES none

To manually set the fuses in the output files use:

#FUSES 1 = 0xC200 // sets config word 1 to 0xC200

Examples:	`#fuses  HS,NOWDT`
Example Files:	ex_sqw.c
Also See:	None

#hexcomment

Syntax:	**#HEXCOMMENT text comment for the top of the hex file** **#HEXCOMMENT\ text comment for the end of the hex file**
Elements:	None
Purpose:	Puts a comment in the hex file Some programmers (MPLAB in particular) do not like comments at the top of the hex file.
Examples:	`#HEXCOMMENT Version 3.1 – requires 20MHz crystal`
Example Files:	None
Also See:	None

#id

Syntax:	**#ID *number 16*** **#ID *number*, *number*, *number*, *number*** **#ID *"filename"*** **#ID *CHECKSUM***
Elements:	***Number 16*** is a 16 bit number, ***number*** is a 4 bit number, filename is any valid PC filename and ***checksum*** is a keyword.
Purpose:	This directive defines the ID word to be programmed into the part. This directive does not affect the compilation but the information is put in the output file. The first syntax will take a 16 -bit number and put one nibble in each of the four ID words in the traditional manner. The second syntax specifies the exact value to be used in each of the four ID words . When a filename is specified the ID is read from the file. The format must be simple text with a CR/LF at the end. The keyword CHECKSUM indicates the device checksum should be saved as the ID.

Examples:	`#id  0x1234`
	`#id  "serial.num"`
	`#id  CHECKSUM`

Example Files:	ex_cust.c
Also See:	None

#ignore_warnings

Syntax:	**#ignore_warnings ALL** **#IGNORE_WARNINGS NONE** **#IGNORE_WARNINGS *warnings***
Elements:	***warnings*** is one or more warning numbers separated by commas
Purpose:	This function will suppress warning messages from the compiler. ALL indicates no warning will be generated. NONE indicates all warnings will be generated. If numbers are listed then those warnings are suppressed.

Examples:	`#ignore_warnings 203`
	`while(TRUE) {`
	`#ignore_warnings NONE`

Example Files:	None
Also See:	Warning messages

#import (options)

Syntax:	**#IMPORT (options)**
Elements:	***FILE=filname*** The filename of the object you want to link with this compilation. ***ONLY=symbol+symbol+.....+symbol*** Only the listed symbols will imported from the specified relocatable object file. If neither ONLY or EXCEPT is used, all symbols are imported. **EXCEPT=symbol+symbol+.....+symbol** The listed symbols will not be imported from the specified relocatable object file. If neither ONLY or EXCEPT is used, all symbols are imported. ***RELOCATABLE*** CCS relocatable object file format. This is the default format when the #IMPORT is used. ***COFF*** COFF file format from MPASM, C18 or C30. ***HEX*** Imported data is straight hex data. ***RANGE=start:stop*** Only addresses in this range are read from the hex file. ***LOCATION=id*** The identifier is made a constant with the start address of the imported data. ***SIZE=id*** The identifier is made a constant with the size of the imported data.
Purpose:	This directive will tell the compiler to include (link) a relocatable object with this unit during compilation. Normally all global symbols from the specified file will be linked, but the EXCEPT and ONLY options can prevent certain symbols from being linked. The command line compiler and the PCW IDE Project Manager can also be used to compile/link/build modules and/or projects.

Examples:	`#IMPORT(FILE=timer.o, ONLY=TimerTask)`
	`void main(void)`
	`{`
	`    while(TRUE)`
	`        TimerTask();`
	`}`
	`/*`
	`timer.o is linked with this compilation, but only TimerTask() is visible in scope from this object.`
	`*/`

Example	None

Files:	
See Also:	#EXPORT, #MODULE, Invoking the Command Line Compiler, Multiple Compilation Unit

#include

Syntax:	**#INCLUDE <*filename*>** **or** **#INCLUDE "*filename*"**
Elements:	***filename*** is a valid PC filename. It may include normal drive and path information. A file with the extension ".encrypted" is a valid PC file. The standard compiler #INCLUDE directive will accept files with this extension and decrypt them as they are read. This allows include files to be distributed without releasing the source code.
Purpose:	Text from the specified file is used at this point of the compilation. If a full path is not specified the compiler will use the list of directories specified for the project to search for the file. If the filename is in "" then the directory with the main source file is searched first. If the filename is in <> then the directory with the main source file is searched last.

Examples:	`#include  <16C54.H>`
	
	`#include  <C:\INCLUDES\COMLIB\MYRS232.C>`

Example Files:	ex_sqw.c
Also See:	None

#inline

Syntax:	**#INLINE**
Elements:	None
Purpose:	Tells the compiler that the function immediately following the directive is to be implemented INLINE. This will cause a duplicate copy of the code to be placed everywhere the function is called. This is useful to save stack space and to increase speed. Without this directive the compiler will decide when it is best to make procedures INLINE.
Examples:	see below

```
#inline
swapbyte(int &a, int &b) {
   int t;
   t=a;
   a=b;
   b=t;
}
```

Example Files:	ex_cust.c
Also See:	#SEPARATE

#int_xxxx

Syntax:

#INT_AD	**Analog to digital conversion complete**
#INT_ADOF	Analog to digital conversion timeout
#INT_BUSCOL	Bus collision
#INT_BUSCOL2	Bus collision 2 detected
#INT_BUTTON	Pushbutton
#INT_CANERR	An error has occurred in the CAN module
#INT_CANIRX	An invalid message has occurred on the CAN bus
#INT_CANRX0	CAN Receive buffer 0 has received a new message
#INT_CANRX1	CAN Receive buffer 1 has received a new message
#INT_CANTX0	CAN Transmit buffer 0 has completed transmission
#INT_CANTX1	CAN Transmit buffer 0 has completed transmission
#INT_CANTX2	CAN Transmit buffer 0 has completed transmission
#INT_CANWAKE	Bus Activity wake-up has occurred on the CAN bus
#INT_CCP1	Capture or Compare on unit 1
#INT_CCP2	Capture or Compare on unit 2
#INT_CCP3	Capture or Compare on unit 3
#INT_CCP4	Capture or Compare on unit 4
#INT_CCP5	Capture or Compare on unit 5
#INT_COMP	Comparator detect
#INT_COMP0	Comparator 0 detect
#INT_COMP1	Comparator 1 detect
#INT_COMP2	Comparator 2 detect
#INT_CR	Cryptographic activity complete
#INT_EEPROM	Write complete
#INT_ETH	Ethernet module interrupt
#INT_EXT	External interrupt
#INT_EXT1	External interrupt #1
#INT_EXT2	External interrupt #2
#INT_EXT3	External interrupt #3
#INT_I2C	I2C interrupt (only on 14000)
#INT_IC1	Input Capture #1
#INT_IC2QEI	Input Capture 2 / QEI Interrupt

#IC3DR	Input Capture 3 / Direction Change Interrupt
#INT_LCD	LCD activity
#INT_LOWVOLT	Low voltage detected
#INT_LVD	Low voltage detected
#INT_OSC_FAIL	System oscillator failed
#INT_OSCF	System oscillator failed
#INT_PMP	Parallel Master Port interrupt
#INT_PSP	Parallel Slave Port data in
#INT_PWMTB	PWM Time Base
#INT_RA	Port A any change on A0_A5
#INT_RB	Port B any change on B4-B7
#INT_RC	Port C any change on C4-C7
#INT_RDA	RS232 receive data available
#INT_RDA0	RS232 receive data available in buffer 0
#INT_RDA1	RS232 receive data available in buffer 1
#INT_RDA2	RS232 receive data available in buffer 2
#INT_RTCC	Timer 0 (RTCC) overflow
#INT_SPP	Streaming Parallel Port Read/Write
#INT_SSP	SPI or I2C activity
#INT_SSP2	SPI or I2C activity for Port 2
#INT_TBE	RS232 transmit buffer empty
#INT_TBE0	RS232 transmit buffer 0 empty
#INT_TBE1	RS232 transmit buffer 1 empty
#INT_TBE2	RS232 transmit buffer 2 empty
#INT_TIMER0	Timer 0 (RTCC) overflow
#INT_TIMER1	Timer 1 overflow
#INT_TIMER2	Timer 2 overflow
#INT_TIMER3	Timer 3 overflow
#INT_TIMER4	Timer 4 overflow
#INT_TIMER5	Timer 5 overflow
#INT_ULPWU	Ultra-low power wake up interrupt
#INT_USB	Universal Serial Bus activity

Note many more #INT_ options are available on specific chips. Check the devices .h file for a full list for a given chip.

Elements: None

Purpose: These directives specify the following function is an interrupt function. Interrupt functions may not have any parameters. Not all directives may be used with all parts. See the devices .h file for all valid interrupts for the part or in PCW use the pull down VIEW | Valid Ints

The compiler will generate code to jump to the function when the interrupt is detected. It will generate code to save and restore the machine state, and will clear the interrupt flag. To prevent the flag from being cleared add NOCLEAR after the #INT_xxxx. The application program must call ENABLE_INTERRUPTS(INT_xxxx) to initially activate the interrupt along with the ENABLE_INTERRUPTS(GLOBAL) to enable interrupts.

The keywords HIGH and FAST may be used with the PCH compiler to mark an interrupt as high priority. A high-priority interrupt can interrupt another interrupt handler. An interrupt marked FAST is performed without saving or restoring any registers. You should do as little as possible and save any registers that need to be saved on your own. Interrupts marked HIGH can be used normally. See #DEVICE for information on building with high-priority interrupts.

A summary of the different kinds of PIC18 interrupts:

#INT_xxxx
    Normal (low priority) interrupt. Compiler saves/restores key registers.
    This interrupt will not interrupt any interrupt in progress.

#INT_xxxx FAST
    High priority interrupt. Compiler DOES NOT save/restore key registers.
    This interrupt will interrupt any normal interrupt in progress.
    Only one is allowed in a program.

#INT_xxxx HIGH
    High priority interrupt. Compiler saves/restores key registers.
    This interrupt will interrupt any normal interrupt in progress.

#INT_xxxx NOCLEAR
    The compiler will not clear the interrupt.

The user code in the function should call clear_interrput( ) to
    clear the interrupt in this case.

#INT_GLOBAL
    Compiler generates no interrupt code. User function is located
    at address 8 for user interrupt handling.

Some interrupts shown in the devices header file are only for the enable/disable interrupts. For example, INT_RB3 may be used in enable/interrupts to enable pin B3. However, the interrupt handler is #INT_RB.

Similarly INT_EXT_L2H sets the interrupt edge to falling and the handler is #INT_EXT.

Examples:

```
#int_ad
adc_handler() {
   adc_active=FALSE;
}

#int_rtcc noclear
isr() {
        ...
}
```

Example Files: See ex_sisr.c and ex_stwt.c for full example programs.

Also See: enable_interrupts(), disable_interrupts(), #INT_DEFAULT, #INT_GLOBAL, #PRIORITY

#INT_DEFAULT

Syntax:	**#INT_DEFAULT**
Elements:	None
Purpose:	The following function will be called if the PIC® triggers an interrupt and none of the interrupt flags are set. If an interrupt is flagged, but is not the one triggered, the #INT_DEFAULT function will get called.

Examples:	`#int_default`
	`default_isr() {`
	`   printf("Unexplained interrupt\r\n");`
	`}`

Example Files:	None
Also See:	#INT_xxxx, #INT_global

#int_global

Syntax:	**#INT_GLOBAL**
Elements:	None
Purpose:	This directive causes the following function to replace the compiler interrupt dispatcher. The function is normally not required and should be used with great caution. When used, the compiler does not generate start-up code or clean-up code, and does not save the registers.

Examples:	`#int_global`
	`isr() {      // Will be located at location 4 for PIC16 chips.`
	`   #asm`
	`   bsf   isr_flag`
	`   retfie`
	`   #endasm`
	`}`

Example Files:	ex_glint.c
Also See:	#INT_xxxx

__line__

Syntax:	**__line__**
Elements:	None

Purpose: The pre-processor identifier is replaced at compile time with line number of the file being compiled.

Examples:

```
if(index>MAX_ENTRIES)
   printf("Too many entries, source file: "
     __FILE__" at line " __LINE__ "\r\n");
```

Example Files: assert.h

Also See: __file__

#list

Syntax: **#LIST**

Elements: None

Purpose: #LIST begins inserting or resumes inserting source lines into the .LST file after a #NOLIST.

Examples:

```
#NOLIST    // Don't clutter up the list file
#include <cdriver.h>
#LIST
```

Example Files: 16c74.h

Also See: #NOLIST

#line

Syntax: **#LINE number file name**

Elements: Number is non-negative decimal integer. File name is optional.

Purpose: The C pre-processor informs the C Compiler of the location in your source code. This code is simply used to change the value of _LINE_ and _FILE_ variables.

Examples:

```
1. void main(){
   #line 10    // specifies the line number that
               // should be reported for
               // the following line of input

2. #line 7 "hello.c"
               // line number in the source file
               // hello.c and it sets the
               // line 7 as current line
               // and hello.c as current file
```

Example Files:	None
Also See:	None

#locate

Syntax:	**#LOCATE *id=x***
Elements:	***id*** is a C variable, ***x*** is a constant memory address
Purpose:	#LOCATE allocates a C variable to a specified address. If the C variable was not previously defined, it will be defined as an INT8. A special form of this directive may be used to locate all A functions local variables starting at a fixed location. Use: #LOCATE Auto = address This directive will place the indirected C variable at the requested address.

Examples:	`// This will locate the float variable at 50-53`
	`// and C will not use this memory for other`
	`// variables automatically located.`
	`float x;`
	`#locate x=0x 50`

Example Files:	ex_glint.c
Also See:	#byte, #bit, #reserve, #word, Named Registers, Type Specifiers, Type Qualifiers, Enumerated Types, Structures & Unions, Typedef

#module

Syntax:	**#MODULE**
Elements:	None
Purpose:	All global symbols created from the #MODULE to the end of the file will only be visible within that same block of code (and files #INCLUDE within that block). This may be used to limit the scope of global variables and functions within include files. This directive also applies to pre-processor #defines. Note: The extern and static data qualifiers can also be used to denote scope of variables and functions as in the standard C methodology. #MODULE does add some benefits in that pre-processor #DEFINE can be given scope, which cannot normally be done in standard C methodology.
Examples:	`int GetCount(void);`

	`void SetCount(int newCount);`
	`#MODULE`
	`int g_count;`
	`#define G_COUNT_MAX  100`
	`int GetCount(void) {return(g_count);}`
	`void SetCount(int newCount) {`
	`  if (newCount>G_COUNT_MAX)`
	`     newCount=G_COUNT_MAX;`
	`  g_count=newCount;`
	`}`
	`/*`
	`the functions GetCount() and SetCount() have global scope, but the variable g_count and the #define G_COUNT_MAX only has scope to this file.`
	`*/`

Example Files:	None
See Also:	#EXPORT, Invoking the Command Line Compiler, Multiple Compilation Unit

#nolist

Syntax:	**#NOLIST**
Elements:	None
Purpose:	Stops inserting source lines into the .LST file (until a #LIST)

Examples:	`#NOLIST    // Don't clutter up the list file`
	`#include <cdriver.h>`
	`#LIST`

Example Files:	16c74.h
Also See:	#LIST

#ocs

Syntax:	**#OCS x**
Elements:	x is the clock's speed and can be 1 Hz to 100 MHz.
Purpose:	Used instead of the #use delay(clock = x)

Examples:	`#include <18F4520.h>`
	`#device ICD=TRUE`
	`#OCS 20 MHz`
	`#use rs232(debugger)`

	`void main(){`
	`      -------;`
	`            }`

Example Files:	None
Also See:	#USE DELAY

#opt

Syntax:	**#OPT *n***
Elements:	All Devices: ***n*** is the optimization level 1-11 or by using the word "compress" for PIC18 and Enhanced PIC16 families.
Purpose:	The optimization level is set with this directive. This setting applies to the entire program and may appear anywhere in the file. The PCW default is 9 for normal. When Compress is specified the optimization is set to an extreme level that causes a very tight rom image, the code is optimized for space, not speed. Debugging with this level my be more difficult.
Examples:	`#opt 5`
Example Files:	None
Also See:	None

#org

Syntax:	**#ORG *start*, *end*** **or** **#ORG *segment*** **or** **#ORG *start*, *end* { }** **or** **#ORG *start*, *end* *auto=0*** **#ORG *start*,*end* *DEFAULT*** **or** **#ORG *DEFAULT***
Elements:	***start*** is the first ROM location (word address) to use, ***end*** is the last ROM location, ***segment*** is the start ROM location from a previous #ORG
Purpose:	This directive will fix the following function, constant or ROM declaration into a specific ROM area. End may be omitted if a segment was previously defined if you only want to add another function to the segment. Follow the ORG with a { } to only reserve the area with nothing inserted by the compiler. The RAM for a ORG'd function may be reset to low memory so the local variables and scratch

variables are placed in low memory. This should only be used if the ORG'd function will not return to the caller. The RAM used will overlap the RAM of the main program. Add a AUTO=0 at the end of the #ORG line.

If the keyword DEFAULT is used then this address range is used for all functions user and compiler generated from this point in the file until a #ORG DEFAULT is encountered (no address range). If a compiler function is called from the generated code while DEFAULT is in effect the compiler generates a new version of the function within the specified address range.

#ORG may be used to locate data in ROM. Because CONSTANT are implemented as functions the #ORG should proceed the CONSTANT and needs a start and end address. For a ROM declaration only the start address should be specified.

When linking multiple compilation units be aware this directive applies to the final object file. It is an error if any #ORG overlaps between files unless the #ORG matches exactly.

Examples:

```
#ORG 0x1E00, 0x1FFF
MyFunc() {
//This function located at 1E00
}

#ORG 0x1E00
Anotherfunc(){
// This will be somewhere 1E00-1F00
}

#ORG 0x800, 0x820 {}
//Nothing will be at 800-820

#ORG 0x1B80
ROM int32 seridl_N0=12345;

#ORG 0x1C00, 0x1C0F
CHAR CONST ID[10}= {"123456789"};
//This ID will be at 1C00
//Note some extra code will
//proceed the 123456789

#ORG 0x1F00, 0x1FF0
Void loader (){
.
.
.
}
```

Example Files: loader.c

Also See: #ROM

#pin_select

Syntax: **#PIN_SELECT function=pin_xx**

Elements: *function* is the Microchip defined pin function name, such as: U1RX (UART1 receive), INT1 (external interrupt 1), T2CK (timer 2 clock), IC1 (input capture 1), OC1 (output capture 1).

INT1	**External Interrupt 1**
INT2	External Interrupt 2
INT3	External Interrupt 3
T0CK	Timer0 External Clock
T3CK	Timer3 External Clock
CCP1	Input Capture 1
CCP2	Input Capture 2
T1G	Timer1 Gate Input
T3G	Timer3 Gate Input
U2RX	EUSART2 Asynchronous Receive/Synchronous Receive (also named: RX2)
U2CK	EUSART2 Asynchronous Clock Input
SDI2	SPI2 Data Input
SCK2IN	SPI2 Clock Input
SS2IN	SPI2 Slave Select Input
FLT0	PWM Fault Input
T0CKI	Timer0 External Clock Input
T3CKI	Timer3 External Clock Input
RX2	EUSART2 Asynchronous Transmit/Asynchronous Clock Output (also named: TX2)
NULL	NULL
C1OUT	Comparator 1 Output
C2OUT	Comparator 2 Output
U2TX	EUSART2 Asynchronous Transmit/ Asynchronous Clock Output (also named: TX2)
U2DT	EUSART2 Synchronous Transmit (also named: DT2)
SDO2	SPI2 Data Output
SCK2OUT	SPIC2 Clock Output
SS2OUT	SPI2 Slave Select Output
ULPOUT	Ultra Low-Power Wake-Up Event
P1A	ECCP1 Compare or PWM Output Channel A
P1B	ECCP1 Enhanced PWM Output, Channel B
P1C	ECCP1 Enhanced PWM Output, Channel C
P1D	ECCP1 Enhanced PWM Output, Channel D
P2A	ECCP2 Compare or PWM Output Channel A
P2B	ECCP2 Enhanced PWM Output, Channel B
P2C	ECCP2 Enhanced PWM Output, Channel C
P2D	ECCP1 Enhanced PWM Output, Channel D
TX2	EUSART2 Asynchronous Transmit/Asynchronous Clock Output (also named: TX2)
DT2	EUSART2 Synchronous Transmit (also named: U2DT)
SCK2	SPI2 Clock Output
SSDMA	SPI DMA Slave Select

pin_xx is the CCS provided pin definition. For example: PIN_C7, PIN_B0, PIN_D3, etc.

Purpose: When using PPS chips a #PIN_SELECT must be appear before these peripherals can be used or referenced.

Examples:

```
#pin_select U1TX=PIN_C6
#pin_select U1RX=PIN_C7
#pin_select INT1=PIN_B0
```

Example Files:	None
Also See:	pin_select()

__pcb__

Syntax:	**__PCB__**
Elements:	None
Purpose:	The PCB compiler defines this pre-processor identifier. It may be used to determine if the PCB compiler is doing the compilation.

Examples:	`#ifdef __pcb__`
	`#device PIC16c54`
	`#endif`

Example Files:	ex_sqw.c
Also See:	__PCM__, __PCH__

__pcm__

Syntax:	**__PCM__**
Elements:	None
Purpose:	The PCM compiler defines this pre-processor identifier. It may be used to determine if the PCM compiler is doing the compilation.

Examples:	`#ifdef __pcm__`
	`#device PIC16c71`
	`#endif`

Example Files:	ex_sqw.c
Also See:	__PCB__, __PCH__

__pch__

Syntax:	**__PCH__**
Elements:	None
Purpose:	The PCH compiler defines this pre-processor identifier. It may be used to determine if the PCH compiler is doing the compilation.

Examples:	`#ifdef _ _ PCH _ _`
	`#device PIC18C452`
	`#endif`

Example Files:	ex_sqw.c
Also See:	__PCB__, __PCM__

#pragma

Syntax:	**#PRAGMA** *cmd*
Elements:	***cmd*** is any valid preprocessor directive.
Purpose:	This directive is used to maintain compatibility between C compilers. This compiler will accept this directive before any other pre-processor command. In no case does this compiler require this directive.
Examples:	`#pragma device  PIC16C54`
Example Files:	ex_cust.c
Also See:	None

#priority

Syntax:	**#PRIORITY** *ints*
Elements:	***ints*** is a list of one or more interrupts separated by commas. ***export*** makes the functions generated from this directive available to other compilation units within the link.
Purpose:	The priority directive may be used to set the interrupt priority. The highest priority items are first in the list. If an interrupt is active it is never interrupted. If two interrupts occur at around the same time then the higher one in this list will be serviced first. When linking multiple compilation units be aware only

	the one in the last compilation unit is used.
Examples:	`#priority rtcc,rb`
Example Files:	None
Also See:	#INT_xxxx

#profile

Syntax: **#profile options**

Elements: ***options*** may be one of the following:

functions	**Profiles the start/end of functions and all profileout() messages.**
functions, parameters	Profiles the start/end of functions, parameters sent to functions, and all profileout() messages.
profileout	Only profile profilout() messages.
paths	Profiles every branch in the code.
off	Disable all code profiling.
on	Re-enables the code profiling that was previously disabled with a #profile off command. This will use the last options before disabled with the off command.

Purpose: Large programs on the microcontroller may generate lots of profile data, which may make it difficult to debug or follow. By using #profile the user can dynamically control which points of the program are being profiled, and limit data to what is relevant to the user.

Examples:

```
#profile off
void BigFunction(void)
{
    // BigFunction code goes here.
    // Since #profile off was called above,
    // no profiling will happen even for other
    // functions called by BigFunction().
}
#profile on
```

Example Files: ex_profile.c

Also See: #use profile(), profileout(), Code Profile overview

#reserve

Syntax:	**#RESERVE** *address* **or** **#RESERVE** *address*, *address*, *address* **or** **#RESERVE** *start*:*end*
Elements:	***address*** is a RAM address, ***start*** is the first address and ***end*** is the last address
Purpose:	This directive allows RAM locations to be reserved from use by the compiler. #RESERVE must appear after the #DEVICE otherwise it will have no effect. When linking multiple compilation units be aware this directive applies to the final object file.

Examples:	`#DEVICE PIC16C74`
	`#RESERVE    0x60:0X6f`

Example Files:	ex_cust.c
Also See:	#ORG

#rom

Syntax:	**#ROM** *address* **= {***list***}**
	#ROM type *address* **= {***list***}**

Elements:	***address*** is a ROM word address, ***list*** is a list of words separated by commas
Purpose:	Allows the insertion of data into the .HEX file. In particular, this may be used to program the '84 data EEPROM, as shown in the following example. Note that if the #ROM address is inside the program memory space, the directive creates a segment for the data, resulting in an error if a #ORG is over the same area. The #ROM data will also be counted as used program memory space. The type option indicates the type of each item, the default is 16 bits. Using char as the type treats each item as 7 bits packing 2 chars into every pcm 14-bit word. When linking multiple compilation units be aware this directive applies to the final object file. Some special forms of this directive may be used for verifying program memory: #ROM address = checksum This will put a value at address such that the entire program memory will sum to 0x1248 #ROM address = crc16 This will put a value at address that is a crc16 of all the program memory except the specified address

	#ROM address = crc8 This will put a value at address that is a crc16 of all the program memory except the specified address

Examples:	`#rom  getnev ("EEPROM_ADDRESS")={1,2,3,4,5,6,7,8}`
	`#rom int8 0x1000={"(c)CCS, 2010"}`

Example Files:	None
Also See:	#ORG

#separate

Syntax:	**#SEPARATE**
Elements:	None
Purpose:	Tells the compiler that the procedure IMMEDIATELY following the directive is to be implemented SEPARATELY. This is useful to prevent the compiler from automatically making a procedure INLINE. This will save ROM space but it does use more stack space. The compiler will make all procedures marked SEPARATE, separate, as requested, even if there is not enough stack space to execute.
Examples:	(see below)
Example Files:	ex_cust.c
Also See:	#INLINE

```
#separate
swapbyte (int *a, int *b) {
int t;
   t=*a;
   *a=*b;
   *b=t;
}
```

#serialize

Syntax:	**#SERIALIZE(***id=xxx*, *next="x"* **|** *file="filename.txt"* **" |** *listfile="filename.txt"*, *"prompt="text"*, *log="filename.txt"***) -** **or** **#SERIALIZE(***dataee=x*, *binary=x*, *next="x"* **|** *file="filename.txt"* **|** *listfile="filename.txt"*, *prompt="text"*, *log="filename.txt"***)**
Elements:	***id=xxx*** - Specify a C CONST identifier, may be int8, int16, int32 or char array Use in place of id parameter, when storing serial number to EEPROM: ***dataee=x*** - The address x is the start address in the data EEPROM.

	binary=x - The integer x is the number of bytes to be written to address specified. -or- ***string=x*** - The integer x is the number of bytes to be written to address specified. ***unicode=n -*** If n is a 0, the string format is normal unicode. For n>0 n indicates the string number in a USB descriptor. Use only one of the next three options: ***file="filename.txt"*** - The file x is used to read the initial serial number from, and this file is updated by the ICD programmer. It is assumed this is a one line file with the serial number. The programmer will increment the serial number. ***listfile="filename.txt"*** - The file x is used to read the initial serial number from, and this file is updated by the ICD programmer. It is assumed this is a file one serial number per line. The programmer will read the first line then delete that line from the file. ***next="x"*** - The serial number X is used for the first load, then the hex file is updated to increment x by one. Other optional parameters: ***prompt="text"*** - If specified the user will be prompted for a serial number on each load. If used with one of the above three options then the default value the user may use is picked according to the above rules. ***log=xxx*** - A file may optionally be specified to keep a log of the date, time, hex file name and serial number each time the part is programmed. If no id=xxx is specified then this may be used as a simple log of all loads of the hex file.
Purpose:	Assists in making serial numbers easier to implement when working with CCS ICD units. Comments are inserted into the hex file that the ICD software interprets.

Examples:	`//Prompt user for serial number to be placed`
	`//at address of serialNumA`
	`//Default serial number = 200int8int8 const serialNumA=100;`
	`#serialize(id=serialNumA,next="200",prompt="Enter the serial number")`
	
	`//Adds serial number log in seriallog.txt`
	`#serialize(id=serialNumA,next="200",prompt="Enter the serial number", log="seriallog.txt")`
	
	`//Retrieves serial number from serials.txt`
	`#serialize(id=serialNumA,listfile="serials.txt")`
	
	`//Place serial number at EEPROM address 0, reserving 1 byte`
	`#serialize(dataee=0,binary=1,next="45",prompt="Put in Serial number")`
	
	`//Place string serial number at EEPROM address 0, reserving 2 bytes`
	`#serialize(dataee=0, string=2,next="AB",prompt="Put in Serial number")`

Example Files:	None
Also See:	None

#task

(The RTOS is only included with the PCW, PCWH, and PCWHD software packages.)

Each RTOS task is specified as a function that has no parameters and no return. The #TASK directive is needed just before each RTOS task to enable the compiler to tell which functions are RTOS tasks. An RTOS task cannot be called directly like a regular function can.

Syntax:	**#TASK** *(options)*
Elements:	***options*** are separated by comma and may be: rate=time Where time is a number followed by s, ms, us, or ns. This specifies how often the task will execute. max=time Where time is a number followed by s, ms, us, or ns. This specifies the budgeted time for this task. queue=bytes Specifies how many bytes to allocate for this task's incoming messages. The default value is 0. enabled=value Specifies whether a task is enabled or disabled by rtos_run( ). True for enabled, false for disabled. The default value is enabled.
Purpose:	This directive tells the compiler that the following function is an RTOS task. The rate option is used to specify how often the task should execute. This must be a multiple of the minor_cycle option if one is specified in the #USE RTOS directive. The max option is used to specify how much processor time a task will use in one execution of the task. The time specified in max must be equal to or less than the time specified in the minor_cycle option of the #USE RTOS directive before the project will compile successfully. The compiler does not have a way to enforce this limit on processor time, so a programmer must be careful with how much processor time a task uses for execution. This option does not need to be specified. The queue option is used to specify the number of bytes to be reserved for the task to receive messages from other tasks or functions. The default queue value is 0.
Examples:	`#task(rate=1s, max=20ms, queue=5)`
Also See:	#USE RTOS

__time__

Syntax:	**__TIME__**
Elements:	None

Purpose:	This pre-processor identifier is replaced at compile time with the time of the compile in the form: "hh:mm:ss"

Examples:	`printf("Software was compiled on ");`
	`printf(__TIME__);`

Example Files:	None
Also See:	None

#type

Syntax:	**#TYPE** *standard-type***=***size* **#TYPE** *default=area* **#TYPE** unsigned **#TYPE** signed
Elements:	***standard-type*** is one of the C keywords short, int, long, or default ***size*** is 1,8,16, or 32 ***area*** is a memory region defined before the #TYPE using the addressmod directive
Purpose:	By default the compiler treats SHORT as one bit , INT as 8 bits, and LONG as 16 bits. The traditional C convention is to have INT defined as the most efficient size for the target processor. This is why it is 8 bits on the PIC ® . In order to help with code compatibility a #TYPE directive may be used to allow these types to be changed. #TYPE can redefine these keywords. Note that the commas are optional. Since #TYPE may render some sizes inaccessible (like a one bit int in the above) four keywords representing the four ints may always be used: INT1, INT8, INT16, and INT32. Be warned CCS example programs and include files may not work right if you use #TYPE in your program. This directive may also be used to change the default RAM area used for variable storage. This is done by specifying default=area where area is a addressmod address space. When linking multiple compilation units be aware this directive only applies to the current compilation unit. The #TYPE directive allows the keywords UNSIGNED and SIGNED to set the default data type.
Examples:	see below

```
#TYPE   SHORT= 8 , INT= 16 , LONG= 32

#TYPE default=area

addressmod (user_ram_block, 0x100, 0x1FF);

#type default=user_ram_block  // all variable declarations
                              // in this area will be in
                              // 0x100-0x1FF
```

```
#type default=                // restores memory allocation
                              // back to normal

#TYPE SIGNED

...
void main()
{
int variable1;  // variable1 can only take values from -128 to 127
...
...
}
```

Example Files:	ex_cust.c
Also See:	None

#undef

Syntax:	**#UNDEF** *id*
Elements:	***id*** is a pre-processor id defined via #DEFINE
Purpose:	The specified pre-processor ID will no longer have meaning to the pre-processor.

Examples:	`#if MAXSIZE<100`
	`#undef MAXSIZE`
	`#define MAXSIZE 100`
	`#endif`

Example Files:	None
Also See:	#DEFINE

_unicode

Syntax:	**__unicode(constant-string)**
Elements:	Unicode format string
Purpose	This macro will convert a standard ASCII string to a Unicode format string by inserting a \000 after each character and removing the normal C string terminator. For example: _unicode("ABCD")

will return: "A\00B\000C\000D" (8 bytes total with the terminator)

Since the normal C terminator is not used for these strings you need to do one of the following for variable length strings:

string = _unicode(KEYWORD) "\000\000";
OR
string = _unicode(KEYWORD);
string_size = sizeof(_unicode(KEYWORD));

Examples:

```
#define USB_DESC_STRING_TYPE 3

#define USB_STRING(x)
(sizeof(_unicode(x))+2),USB_DESC_STRING_TYPE,_unicode(x)
#define USB_ENGLISH_STRING 4,USB_DESC_STRING_TYPE,0x09,0x04
                                         //Microsoft Defined for US-English

char const USB_STRING_DESC[]=[
   USB_ENGLISH_STRING,
   USB_STRING("CCS"),
   USB_STRING("CCS HID DEMO")
};
```

Example Files: usb_desc_hid.h

#use capture

Syntax: **#USE CAPTURE(options)**

Elements:

ICx/CCPx
Which CCP/Input Capture module to us.

INPUT = PIN_xx
Specifies which pin to use. Useful for device with remappable pins, this will cause compiler to automatically assign pin to peripheral.

TIMER=x
Specifies the timer to use with capture unit. If not specified default to timer 1 for PCM and PCH compilers and timer 3 for PCD compiler.

TICK=x
The tick time to setup the timer to. If not specified it will be set to fastest as possible or if same timer was already setup by a previous stream it will be set to that tick time. If using same timer as previous stream and different tick time an error will be generated.

FASTEST
Use instead of TICK=x to set tick time to fastest as possible.

	SLOWEST Use instead of TICK=x to set tick time to slowest as possible. **CAPTURE_RISING** Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING. **CAPTURE_FALLING** Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING. **CAPTURE_BOTH** PCD only. Specifies the edge that timer value is captured on. Defaults to CAPTURE_RISING. **PRE=x** Specifies number of rising edges before capture event occurs. Valid options are 1, 4 and 16, default to 1 if not specified. Options 4 and 16 are only valid when using CAPTURE_RISING, will generate an error is used with CAPTURE_FALLING or CAPTURE_BOTH. **ISR=x** **STREAM=id** Associates a stream identifier with the capture module. The identifier may be used in functions like get_capture_time(). **DEFINE=id** Creates a define named id which specifies the number of capture per second. Default define name if not specified is CAPTURES_PER_SECOND. Define name must start with an ASCII letter 'A' to 'Z', an ASCII letter 'a' to 'z' or an ASCII underscore ('_').
Purpose:	This directive tells the compiler to setup an input capture on the specified pin using the specified settings. The #USE DELAY directive must appear before this directive can be used. This directive enables use of built-in functions such as get_capture_time() and get_capture_event().
Examples:	#USE CAPTURE(INPUT=PIN_C2,CAPTURE_RISING,TIMER=1,FASTEST)
Example Files:	None.
Also See:	get_capture_time(), get_capture_event()

#use delay

Syntax:	**#USE DELAY (options))**
Elements:	Options may be any of the following separated by commas: ***clock=speed*** speed is a constant 1-100000000 (1 hz to 100 mhz). This number can contains commas. This number also supports the following denominations: M, MHZ, K, KHZ. This specifies the clock the CPU runs at. Depending on the PIC this is 2 or 4 times the instruction rate. This directive is not needed if the following type=speed is used and there is no frequency multiplication or division. ***type=speed*** type defines what kind of clock you are using, and the following values are valid: oscillator, osc (same as oscillator), crystal, xtal (same as crystal), internal, int (same as internal) or rc. The compiler will automatically set the oscillator configuration bits based upon your defined type. If you specified internal, the compiler will also automatically set the internal oscillator to the defined

	speed. Configuration fuses are modified when this option is used. Speed is the input frequency. ***restart_wdt*** will restart the watchdog timer on every delay_us() and delay_ms() use. ***clock_out*** when used with the internal or oscillator types this enables the clockout pin to output the clock. ***fast_start*** some chips allow the chip to begin execution using an internal clock until the primary clock is stable. ***lock*** some chips can prevent the oscillator type from being changed at run time by the software. ***USB or USB_FULL*** for devices with a built-in USB peripheral. When used with the ***type=speed*** option the compiler will set the correct configuration bits for the USB peripheral to operate at Full-Speed. ***USB_LOW*** for devices with a built-in USB peripheral. When used with the ***type=speed*** option the compiler will set the correct configuration bits for the USB peripheral to operate at Low-Speed. **PLL_WAIT** for devices with a PLL and a PLL Ready Status flag to test. When a PLL clock is specified it will cause the compiler to poll the ready PLL Ready Flag and only continue program execution when flag indicates that the PLL is ready. **ACT or ACT=type** for device with Active Clock Tuning, type can be either USB or SOSC. If only using ACT type will default to USB. ACT=USB causes the compiler to enable the active clock tuning and to tune the internal oscillator to the USB clock. ACT=SOSC causes the compiler to enable the active clock tuning and to tune the internal oscillator to the secondary clock at 32.768 kHz. ACT can only be used when the system clock is set to run from the internal oscillator.
Also See:	delay_ms(), delay_us()

#use dynamic_memory

Syntax:	**#USE DYNAMIC_MEMORY**
Elements:	***None***
Purpose:	This pre-processor directive instructs the compiler to create the _DYNAMIC_HEAD object. _DYNAMIC_HEAD is the location where the first free space is allocated.

Examples:	`#USE DYNAMIC_MEMORY`
	`void main ( ){`
	`             }`

Example Files:	ex_malloc.c
Also See:	None

#use fast_io

Syntax:	**#USE FAST_IO (***port***)**
Elements:	***port*** is A, B, C, D, E, F, G, H, J or ALL
Purpose:	Affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another #use xxxx_IO directive is encountered. The fast method of doing I/O will cause the compiler to perform I/O without programming of the direction register. The compiler's default operation is the opposite of this command, the direction I/O will be set/cleared on each I/O operation. The user must ensure the direction register is set correctly via set_tris_X(). When linking multiple compilation units be aware this directive only applies to the current compilation unit.
Examples:	`#use fast_io(A)`
Example Files:	ex_cust.c
Also See:	#USE FIXED_IO, #USE STANDARD_IO, set_tris_X() , General Purpose I/O

#use fixed_io

Syntax:	**#USE FIXED_IO (***port_outputs***=***pin***,** *pin***?)**
Elements:	***port*** is A-G, ***pin*** is one of the pin constants defined in the devices .h file.
Purpose:	This directive affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another #USE XXX_IO directive is encountered. The fixed method of doing I/O will cause the compiler to generate code to make an I/O pin either input or output every time it is used. The pins are programmed according to the information in this directive (not the operations actually performed). This saves a byte of RAM used in standard I/O. When linking multiple compilation units be aware this directive only applies to the current compilation unit.
Examples:	`#use fixed_io(a_outputs=PIN_A2, PIN_A3)`
Example Files:	None
Also See:	#USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

#use i2c

Syntax:	**#USE I2C (***options***)**

Elements:

Options are separated by commas and may be:

MASTER	**Sets to the master mode**
MULTI_MASTER	Set the multi_master mode
SLAVE	Set the slave mode
SCL=pin	Specifies the SCL pin (pin is a bit address)
SDA=pin	Specifies the SDA pin
ADDRESS=nn	Specifies the slave mode address
FAST	Use the fast I2C specification.
FAST=nnnnnn	Sets the speed to nnnnnn hz
SLOW	Use the slow I2C specification
RESTART_WDT	Restart the WDT while waiting in I2C_READ
FORCE_HW	Use hardware I2C functions.
FORCE_SW	Use software I2C functions.
NOFLOAT_HIGH	Does not allow signals to float high, signals are driven from low to high
SMBUS	Bus used is not I2C bus, but very similar
STREAM=id	Associates a stream identifier with this I2C port. The identifier may then be used in functions like i2c_read or i2c_write.
NO_STRETCH	Do not allow clock streaching
MASK=nn	Set an address mask for parts that support it
I2C1	Instead of SCL= and SDA= this sets the pins to the first module
I2C2	Instead of SCL= and SDA= this sets the pins to the second module
NOINIT	No initialization of the I2C peripheral is performed. Use I2C_INIT() to initialize peripheral at run time.

Only some chips allow the following:

DATA_HOLD	**No ACK is sent until I2C_READ is called for data bytes (slave only)**
ADDRESS_HOLD	No ACK is sent until I2C_read is called for the address byte (slave only)
SDA_HOLD	Min of 300ns holdtime on SDA a from SCL goes low

Purpose:

CCS offers support for the hardware-based I2C™ and a software-based master I2C™ device.(For more information on the hardware-based I2C module, please consult the datasheet for your target device; not all PICs support I2C™.

The I2C library contains functions to implement an I2C bus. The #USE I2C remains in effect for the I2C_START, I2C_STOP, I2C_READ, I2C_WRITE and I2C_POLL functions until another USE I2C is encountered. Software functions are generated unless the FORCE_HW is specified. The SLAVE mode should only be used with the built-in SSP. The functions created with this directive are exported when using multiple compilation units. To access the correct function use the stream identifier.

Examples:

```
#use I2C(master, sda=PIN_B0, scl=PIN_B1)

#use I2C(slave,sda=PIN_C4,scl=PIN_C3
                address=0xa0,FORCE_HW)

#use I2C(master, scl=PIN_B0, sda=PIN_B1, fast=450000)
//sets the target speed to 450 KBSP
```

Example Files:	ex_extee.c with 16c74.h
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, I2C Overview

#use profile()

Syntax: **#use profile(options)**

Elements: ***options*** may be any of the following, comma separated:

ICD	**Default – configures code profiler to use the ICD connection.**
TIMER1	Optional. If specified, the code profiler run-time on the microcontroller will use the Timer1 peripheral as a timestamp for all profile events. If not specified the code profiler tool will use the PC clock, which may not be accurate for fast events.
BAUD=x	Optional. If specified, will use a different baud rate between the microcontroller and the code profiler tool. This may be required on slow microcontrollers to attempt to use a slower baud rate.

Purpose: Tell the compiler to add the code profiler run-time in the microcontroller and configure the link and clock.

Examples: #profile(ICD, TIMER1, baud=9600)

Example Files: ex_profile.c

Also See: #profile(), profileout(), Code Profile overview

#use pwm()

Syntax: **#use pwm (options)**

Elements: ***options*** are separated by commas and may be:

PWMx or CCPx	**Selects the CCP to use, x being the module number to use.**
OUTPUT=PIN_xx	Selects the PWM pin to use, pin must be one of the CCP pins. If device has remappable pins compiler will assign specified pin to specified CCP module. If CCP module not specified it will assign remappable pin to

	first available module.
TIMER=x	Selects timer to use with PWM module, default if not specified is timer 2.
FREQUENCY=x	Sets the period of PWM based off specified value, should not be used if PERIOD is already specified. If frequency can't be achieved exactly compiler will generate a message specifying the exact frequency and period of PWM. If neither FREQUENCY or PERIOD is specified, the period defaults to maximum possible period with maximum resolution and compiler will generate a message specifying the frequency and period of PWM, or if using same timer as previous stream instead of setting to maximum possible it will be set to the same as previous stream. If using same timer as previous stream and frequency is different compiler will generate an error.
PERIOD=x	Sets the period of PWM, should not be used if FREQUENCY is already specified. If period can't be achieved exactly compiler will generate a message specifying the exact period and frequency of PWM. If neither PERIOD or FREQUENCY is specified, the period defaults to maximum possible period with maximum resolution and compiler will generate a message specifying the frequency and period of PWM, or if using same timer as previous stream instead of setting to maximum possible it will be set to the same as previous stream. If using same timer as previous stream and period is different compiler will generate an error.
BITS=x	Sets the resolution of the the duty cycle, if period or frequency is specified will adjust the period to meet set resolution and will generate an message specifying the frequency and duty of PWM. If period or frequency not specified will set period to maximum possible for specified resolution and compiler will generate a message specifying the frequency and period of PWM, unless using same timer as previous then it will generate an error if resolution is different then previous stream. If not specified then frequency, period or previous stream using same timer sets the resolution.
DUTY=x	Selects the duty percentage of PWM, default if not specified is 50%.
PWM_ON	Initialize the PWM in the ON state, default state if pwm_on or pwm_off is not specified.
PWM_OFF	Initalize the PWM in the OFF state.
STREAM=id	Associates a stream identifier with the PWM signal. The identifier may be used in functions like pwm_set_duty_percent().

Purpose: This directive tells the compiler to setup a PWM on the specified pin using the specified frequency, period, duty cycle and resolution. The #USE DELAY directive must appear before this directive can be used. This directive enables use of built-in functions such as set_pwm_duty_percent(), set_pwm_frequency(), set_pwm_period(), pwm_on() and pwm_off().

Examples: None

Also See:

#use rs232

Syntax: **#USE RS232 (*options*)**

Elements: ***Options*** are separated by commas and may be:

STREAM=id	**Associates a stream identifier with this RS232 port. The identifier may then be used in functions like fputc.**

BAUD=x	Set baud rate to x
XMIT=pin	Set transmit pin
RCV=pin	Set receive pin
FORCE_SW	Will generate software serial I/O routines even when the UART pins are specified.
BRGH1OK	Allow bad baud rates on chips that have baud rate problems.
ENABLE=pin	The specified pin will be high during transmit. This may be used to enable 485 transmit.
DEBUGGER	Indicates this stream is used to send/receive data through a CCS ICD unit. The default pin used is B3, use XMIT= and RCV= to change the pin used. Both should be the same pin.
RESTART_WDT	Will cause GETC() to clear the WDT as it waits for a character.
INVERT	Invert the polarity of the serial pins (normally not needed when level converter, such as the MAX232). May not be used with the internal UART.
PARITY=X	Where x is N, E, or O.
BITS =X	Where x is 5-9 (5-7 may not be used with the SCI).
FLOAT_HIGH	The line is not driven high. This is used for open collector outputs. Bit 6 in RS232_ERRORS is set if the pin is not high at the end of the bit time.
ERRORS	Used to cause the compiler to keep receive errors in the variable RS232_ERRORS and to reset errors when they occur.
SAMPLE_EARLY	A getc() normally samples data in the middle of a bit time. This option causes the sample to be at the start of a bit time. May not be used with the UART.
RETURN=pin	For FLOAT_HIGH and MULTI_MASTER this is the pin used to read the signal back. The default for FLOAT_HIGH is the XMIT pin and for MULTI_MASTER the RCV pin.
MULTI_MASTER	Uses the RETURN pin to determine if another master on the bus is transmitting at the same time. If a collision is detected bit 6 is set in RS232_ERRORS and all future PUTC's are ignored until bit 6 is cleared. The signal is checked at the start and end of a bit time. May not be used with the UART.
LONG_DATA	Makes getc() return an int16 and putc accept an int16. This is for 9 bit data formats.
DISABLE_INTS	Will cause interrupts to be disabled when the routines get or put a character. This prevents character distortion for software implemented I/O and prevents interaction between I/O in interrupt handlers and the main program when using the UART.
STOP=X	To set the number of stop bits (default is 1). This works for both UART and non-UART ports.

TIMEOUT=X	To set the time getc() waits for a byte in milliseconds. If no character comes in within this time the RS232_ERRORS is set to 0 as well as the return value form getc(). This works for both UART and non-UART ports.
SYNC_SLAVE	Makes the RS232 line a synchronous slave, making the receive pin a clock in, and the data pin the data in/out.
SYNC_MASTER	Makes the RS232 line a synchronous master, making the receive pin a clock out, and the data pin the data in/out.
SYNC_MATER_CONT	Makes the RS232 line a synchronous master mode in continuous receive mode. The receive pin is set as a clock out, and the data pin is set as the data in/out.
UART1	Sets the XMIT= and RCV= to the chips first hardware UART.
UART2	Sets the XMIT= and RCV= to the chips second hardware UART.
NOINIT	No initialization of the UART peripheral is performed. Useful for dynamic control of the UART baudrate or initializing the peripheral manually at a later point in the program's run time. If this option is used, then setup_uart( ) needs to be used to initialize the peripheral. Using a serial routine (such as getc( ) or putc( )) before the UART is initialized will cause undefined behavior.
ICD	Indicates this stream is used to send/receive data through a CCS ICD unit. The default trasmit pin is the PIC's ICSPDAT/PGD pin and the default receive pin is the PIC's ICSPCLK/PGC pin. Use XMIT= and RCV= to change the pins used.
UART3	Sets the XMIT= and RCV= to the device's third hardware UART.
UART4	Sets the XMIT= and RCV= to the device's fourth hardware UART.
ICD	Indicates this stream uses the ICD in a special pass through mode to send/receive serial data to/from PC. The ICSP clock line is the PIC's receive pin, usually pin B6, and the ICSP data line is the PIC's transmit pin, usually pin B7.
MAX_ERROR=x	Specifies the max error percentage the compiler can set the RS232 baud rate from the specified baud before generating an error. Defaults to 3% if not specified.
Serial Buffer Options:	
RECEIVE_BUFFER=x	Size in bytes of UART circular receive buffer, default if not specified is zero. Uses an interrupt to receive data, supports RDA interrupt or external interrupts.
TRANSMIT_BUFFER=x	Size in bytes of UART circular transmit buffer, default if not specified is zero.
TXISR	If TRANSMIT_BUFFER is greater then zero specifies using TBE interrupt for transmitting data. Default is NOTXISR if TXISR or NOTXISR is not specified. TXISR option can only be used when using hardware UART.
NOTXISR	If TRANSMIT_BUFFER is greater then zero specifies to not use TBE interrupt for transmitting data. Default is NOTXISR if TXISR or NOTXISR is not specified and XMIT_BUFFER is greater then zero
Flow Control Options:	
RTS = PIN_xx	Pin to use for RTS flow control. When using FLOW_CONTROL_MODE this pin is driven to the active level when it is ready to receive more data. In SIMPLEX_MODE the pin is driven to the active level when it has data to transmit. FLOW_CONTROL_MODE can only be use when using RECEIVE_BUFFER
RTS_LEVEL=x	Specifies the active level of the RTS pin, HIGH is active high and LOW is active low. Defaults to LOW if not specified.
CTS = PIN_xx	Pin to use for CTS flow control. In both FLOW_CONTROL_MODE and SIMPLEX_MODE this pin is sampled to see if it clear to send

	data. If pin is at active level and there is data to send it will send next data byte.
CTS_LEVEL=x	Specifies the active level of the CTS pin, HIGH is active high and LOW is active low. Default to LOW if not specified
FLOW_CONTROL_MODE	Specifies how the RTS pin is used. For FLOW_CONTROL_MODE the RTS pin is driven to the active level when ready to receive data. Defaults to FLOW_CONTROL_MODE when neither FLOW_CONTROL_MODE or SIMPLEX_MODE is specified. If RTS pin isn't specified then this option is not used.
SIMPLEX_MODE	Specifies how the RTS pin is used. For SIMPLEX_MODE the RTS pin is driven to the active level when it has data to send. Defaults to FLOW_CONTROL_MODE when neither FLOW_CONTROL_MODE or SIMPLEX_MODE is specified. If RTS pin isn't specified then this option is not used.

Purpose: This directive tells the compiler the baud rate and pins used for serial I/O. This directive takes effect until another RS232 directive is encountered. The #USE DELAY directive must appear before this directive can be used. This directive enables use of built-in functions such as GETC, PUTC, and PRINTF. The functions created with this directive are exported when using multiple compilation units. To access the correct function use the stream identifier.

When using parts with built-in SCI and the SCI pins are specified, the SCI will be used. If a baud rate cannot be achieved within 3% of the desired value using the current clock rate, an error will be generated. The definition of the RS232_ERRORS is as follows:

No UART:

- Bit 7 is 9th bit for 9 bit data mode (get and put).
- Bit 6 set to one indicates a put failed in float high mode.

With a UART:

- Used only by get:
- Copy of RCSTA register except:
- Bit 0 is used to indicate a parity error.

Warning:
The PIC UART will shut down on overflow (3 characters received by the hardware with a GETC() call). The "ERRORS" option prevents the shutdown by detecting the condition and resetting the UART.

Examples:

```
#use rs232(baud=9600, xmit=PIN_A2,rcv=PIN_A3)
```

Example Files: ex_cust.c

Also See: getc(), putc(), printf(), setup_uart( ), RS2332 I/O overview

#use rtos

(The RTOS is only included with the PCW and PCWH packages.)

The CCS Real Time Operating System (RTOS) allows a PIC micro controller to run regularly scheduled tasks without the need for interrupts. This is accomplished by a function (RTOS_RUN()) that acts as a dispatcher. When a task is scheduled to run, the dispatch function gives control of the processor to that task. When the task is done executing or does not need the processor anymore, control of the processor is returned to the dispatch function which then will give control of the processor to the next task that is scheduled to execute at the appropriate time. This process is called cooperative multi-tasking.

Syntax: **#USE RTOS** (options)

Elements: options are separated by comma and may be:

timer=X	**Where x is 0-4 specifying the timer used by the RTOS.**
minor_cycle=time	Where time is a number followed by s, ms, us, ns. This is the longest time any task will run. Each task's execution rate must be a multiple of this time. The compiler can calculate this if it is not specified.
statistics	Maintain min, max, and total time used by each task.

Purpose: This directive tells the compiler which timer on the PIC to use for monitoring and when to grant control to a task. Changes to the specified timer's prescaler will effect the rate at which tasks are executed.

This directive can also be used to specify the longest time that a task will ever take to execute with the minor_cycle option. This simply forces all task execution rates to be a multiple of the minor_cycle before the project will compile successfully. If the this option is not specified the compiler will use a minor_cycle value that is the smallest possible factor of the execution rates of the RTOS tasks.

If the statistics option is specified then the compiler will keep track of the minimum processor time taken by one execution of each task, the maximum processor time taken by one execution of each task, and the total processor time used by each task.

When linking multiple compilation units, this directive must appear exactly the same in each compilation unit.

Examples:

```
#use rtos(timer=0, minor_cycle=20ms)
```

Also See: #TASK

#use spi

Syntax: **#USE SPI (*options*)**

Elements: ***Options*** are separated by commas and may be:

MASTER	**Set the device as the master. (default)**
SLAVE	Set the device as the slave.
BAUD=n	Target bits per second, default is as fast as possible.
CLOCK_HIGH=n	High time of clock in us (not needed if BAUD= is used). (default=0)
CLOCK_LOW=n	Low time of clock in us (not needed if BAUD= is used). (default=0)
DI=pin	Optional pin for incoming data.
DO=pin	Optional pin for outgoing data.
CLK=pin	Clock pin.
MODE=n	The mode to put the SPI bus.
ENABLE=pin	Optional pin to be active during data transfer.
LOAD=pin	Optional pin to be pulsed active after data is transferred.

DIAGNOSTIC=pin	Optional pin to the set high when data is sampled.
SAMPLE_RISE	Sample on rising edge.
SAMPLE_FALL	Sample on falling edge (default).
BITS=n	Max number of bits in a transfer. (default=32)
SAMPLE_COUNT=n	Number of samples to take (uses majority vote). (default=1
LOAD_ACTIVE=n	Active state for LOAD pin (0, 1).
ENABLE_ACTIVE=n	Active state for ENABLE pin (0, 1). (default=0)
IDLE=n	Inactive state for CLK pin (0, 1). (default=0)
ENABLE_DELAY=n	Time in us to delay after ENABLE is activated. (default=0)
DATA_HOLD=n	Time between data change and clock change
LSB_FIRST	LSB is sent first.
MSB_FIRST	MSB is sent first. (default)
STREAM=id	Specify a stream name for this protocol.
SPI1	Use the hardware pins for SPI Port 1
SPI2	Use the hardware pins for SPI Port 2
FORCE_HW	Use the pic hardware SPI.
NOINIT	Don't initialize the hardware SPI Port

Purpose: The SPI library contains functions to implement an SPI bus. After setting all of the proper parameters in #USE SPI, the spi_xfer() function can be used to both transfer and receive data on the SPI bus.

The SPI1 and SPI2 options will use the SPI hardware onboard the PIC. The most common pins present on hardware SPI are: DI, DO, and CLK. These pins don't need to be assigned values through the options; the compiler will automatically assign hardware-specific values to these pins. Consult your PIC's data sheet as to where the pins for hardware SPI are. If hardware SPI is not used, then software SPI will be used. Software SPI is much slower than hardware SPI, but software SPI can use any pins to transfer and receive data other than just the pins tied to the PIC's hardware SPI pins.

The MODE option is more or less a quick way to specify how the stream is going to sample data. MODE=0 sets IDLE=0 and SAMPLE_RISE. MODE=1 sets IDLE=0 and SAMPLE_FALL. MODE=2 sets IDLE=1 and SAMPLE_FALL. MODE=3 sets IDLE=1 and SAMPLE_RISE. There are only these 4 MODEs.

SPI cannot use the same pins for DI and DO. If needed, specify two streams: one to send data and another to receive data.

The pins must be specified with DI, DO, CLK or SPIx, all other options are defaulted as indicated above.

Examples:

```
#use spi(DI=PIN_B1, DO=PIN_B0, CLK=PIN_B2, ENABLE=PIN_B4, BITS=16)
// uses software SPI

#use spi(FORCE_HW, BITS=16, stream=SPI_STREAM)
// uses hardware SPI and gives this stream the name SPI_STREAM
```

Example Files: None

Also See: spi_xfer()

#use standard_io

Syntax: **#USE STANDARD_IO (*port*)**

Elements:	***port*** is A, B, C, D, E, F, G, H, J or ALL
Purpose:	This directive affects how the compiler will generate code for input and output instructions that follow. This directive takes effect until another #USE XXX_IO directive is encountered. The standard method of doing I/O will cause the compiler to generate code to make an I/O pin either input or output every time it is used. On the 5X processors this requires one byte of RAM for every port set to standard I/O. Standard_io is the default I/O method for all ports. When linking multiple compilation units be aware this directive only applies to the current compilation unit.
Examples:	`#use standard_io(A)`
Example Files:	ex_cust.c
Also See:	#USE FAST_IO, #USE FIXED_IO, General Purpose I/O

#use timer

Syntax:	**#USE TIMER (options)**
Elements:	**TIMER=x** Sets the timer to use as the tick timer. x is a valid timer that the PIC has. Default value is 1 for Timer 1. **TICK=xx** Sets the desired time for 1 tick. xx can be used with ns(nanoseconds), us (microseconds), ms (milliseconds), or s (seconds). If the desired tick time can't be achieved it will set the time to closest achievable time and will generate a warning specifying the exact tick time. The default value is 1us. **BITS=x** Sets the variable size used by the get_ticks() and set_ticks() functions for returning and setting the tick time. x can be 8 for 8 bits, 16 for 16 bits or 32 for 32bits. The default is 32 for 32 bits. **ISR** Uses the timer's interrupt to increment the upper bits of the tick timer. This mode requires the the global interrupt be enabled in the main program. **NOISR** The get_ticks() function increments the upper bits of the tick timer. This requires that the get_ticks() function be called more often then the timer's overflow rate. NOISR is the default mode of operation. **STREAM=id** Associates a stream identifier with the tick timer. The identifier may be used in functions like get_ticks(). **DEFINE=id**

	Creates a define named id which specifies the number of ticks that will occur in one second. Default define name if not specified is TICKS_PER_SECOND. Define name must start with an ASCII letter 'A' to 'Z', an ASCII letter 'a' to 'z' or an ASCII underscore ('_'). **COUNTER or COUNTER=x** Sets up specified timer as a counter instead of timer. x specifies the prescallar to setup counter with, default is1 if x is not specified specified. The function get_ticks() will return the current count and the function set_ticks() can be used to set count to a specific starting value or to clear counter.
Purpose:	This directive creates a tick timer using one of the PIC's timers. The tick timer is initialized to zero at program start. This directive also creates the define TICKS_PER_SECOND as a floating point number, which specifies that number of ticks that will occur in one second.
Examples:	(see code below)
Example Files:	None
Also See:	get_ticks(), set_ticks()

```
#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)

unsigned int16 tick_difference(unsigned int16 current, unsigned int16 previous) {
   return(current - previous);
}

void main(void) {
   unsigned int16 current_tick, previous_tick;
   current_tick = previous_tick = get_ticks();
   while(TRUE) {
      current_tick = get_ticks();
      if(tick_difference(current_tick, previous_tick) > 1000) {
         output_toggle(PIN_B0);
         previous_tick = current_tick;
      }
   }
}
```

#use touchpad

Syntax:	**#USE TOUCHPAD (options)**
Elements:	***RANGE=x*** Sets the oscillator charge/discharge current range. If x is L, current is nominally 0.1 microamps. If x is M, current is nominally 1.2 microamps. If x is H, current is nominally 18 microamps. Default value is H (18 microamps). ***THRESHOLD=x*** x is a number between 1-100 and represents the percent reduction in the nominal frequency that will generate a valid key press in software. Default value is 6%. ***SCANTIME=xxMS*** xx is the number of milliseconds used by the microprocessor to scan for one key press. If utilizing

	multiple touch pads, each pad will use xx milliseconds to scan for one key press. Default is 32ms. ***PIN=char*** If a valid key press is determined on "PIN", the software will return the character "char" in the function touchpad_getc(). (Example: PIN_B0='A') **SOURCETIME=xxus** (CTMU only) xx is thenumber of microseconds each pin is sampled for by ADC during each scan time period. Default is 10us.
Purpose:	This directive will tell the compiler to initialize and activate the Capacitive Sensing Module (CSM)or Charge Time Measurement Unit (CTMU) on the microcontroller. The compiler requires use of the TIMER0 and TIMER1 modules for CSM and Timer1 ADC modules for CTMU, and global interrupts must still be activated in the main program in order for the CSM or CTMU to begin normal operation. For most applications, a higher RANGE, lower THRESHOLD, and higher SCANTIME will result better key press detection. Multiple PIN's may be declared in "options", but they must be valid pins used by the CSM or CTMU. The user may also generate a TIMER0 ISR with TIMER0's interrupt occuring every SCANTIME milliseconds. In this case, the CSM's or CTMU's ISR will be executed first.
Examples:	see below
Example Files:	None
Also See:	touchpad_state( ), touchpad_getc( ), touchpad_hit( )

Examples:

```
#USE TOUCHPAD (THRESHOLD=5, PIN_D5='5', PIN_B0='C')
void main(void){
     char c;
     enable_interrupts(GLOBAL);

     while(1){
         c = TOUCHPAD_GETC();  //will wait until a pin is detected
     }                         //if PIN_B0 is pressed, c will have 'C'
}                              //if PIN_D5 is pressed, c will have '5'
```

#warning

Syntax:	**#WARNING** *text*
Elements:	***text*** is optional and may be any text
Purpose:	Forces the compiler to generate a warning at the location this directive appears in the file. The text may include macros that will be expanded for the display. This may be used to see the macro expansion. The command may also be used to alert the user to an invalid compile time situation. To prevent the warning from being counted as a warning, use this syntax: #warning/information text
Examples:	see below

```
#if  BUFFER_SIZE < 32
#warning  Buffer Overflow may occur
#endif
```

Example Files:	ex_psp.c
Also See:	#ERROR

#word

Syntax:	**#WORD** *id* **=** *x*
Elements:	***id*** is a valid C identifier, ***x*** is a C variable or a constant
Purpose:	If the id is already known as a C variable then this will locate the variable at address x. In this case the variable type does not change from the original definition. If the id is not known a new C variable is created and placed at address x with the type int16 Warning: In both cases memory at x is not exclusive to this variable. Other variables may be located at the same location. In fact when x is a variable, then id and x share the same memory location.

Examples:	`#word data = 0x0800`
	
	`struct  {`
	`  int lowerByte : 8;`
	`  int upperByte : 8;`
	`} control_word;`
	`#word control_word = 0x85`
	`...`
	`control_word.upperByte = 0x42;`

Example Files:	None
Also See:	#bit, #byte, #locate, #reserve, Named Registers, Type Specifiers, Type Qualifiers, Enumerated Types, Structures & Unions, Typedef

#zero_ram

Syntax:	**#ZERO_RAM**
Elements:	None
Purpose:	This directive zero's out all of the internal registers that may be used to hold variables before program execution begins.

Examples:	`#zero_ram`
	`void main() {`
	
	`}`

Example Files:	ex_cust.c
Also See:	None

BUILT-IN FUNCTIONS

BUILT-IN FUNCTIONS

The CCS compiler provides a lot of built-in functions to access and use the PIC microcontroller's peripherals. This makes it very easy for the users to configure and use the peripherals without going into in depth details of the registers associated with the functionality. The functions categorized by the peripherals associated with them are listed on the next page. Click on the function name to get a complete description and parameter and return value descriptions.

abs( )

Syntax:	**value = abs(*x*)**
Parameters:	***x*** is a signed 8, 16, or 32 bit int or a float
Returns:	Same type as the parameter.
Function:	Computes the absolute value of a number.
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`signed int target,actual;`
	`   ...`
	`error = abs(target-actual);`

Example Files:	None
Also See:	labs()

sin( ) cos( ) tan( ) asin( ) acos() atan() sinh() cosh() tanh() atan2()

Syntax:	**val = sin (*rad*)** **val = cos (*rad*)** **val = tan (*rad*)** **rad = asin (*val*)** **rad1 = acos (*val*)** **rad = atan (*val*)** **rad2=atan2(*val*, *val*)** **result=sinh(*value*)** **result=cosh(*value*)** **result=tanh(*value*)**
Parameters:	***rad*** is a float representing an angle in Radians -2pi to 2pi. ***val*** is a float with the range -1.0 to 1.0. ***Value*** is a float
Returns:	rad is a float representing an angle in Radians -pi/2 to pi/2 val is a float with the range -1.0 to 1.0. rad1 is a float representing an angle in Radians 0 to pi

	rad2 is a float representing an angle in Radians -pi to pi Result is a float
Function:	These functions perform basic Trigonometric functions.

sin	**returns the sine value of the parameter (measured in radians)**
cos	returns the cosine value of the parameter (measured in radians)
tan	returns the tangent value of the parameter (measured in radians)
asin	returns the arc sine value in the range [-pi/2,+pi/2] radians
acos	returns the arc cosine value in the range[0,pi] radians
atan	returns the arc tangent value in the range [-pi/2,+pi/2] radians
atan2	returns the arc tangent of y/x in the range [-pi,+pi] radians
sinh	returns the hyperbolic sine of x
cosh	returns the hyperbolic cosine of x
tanh	returns the hyperbolic tangent of x

Note on error handling:

If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function.

Domain error occurs in the following cases:
asin: when the argument not in the range[-1,+1]
acos: when the argument not in the range[-1,+1]
atan2: when both arguments are zero

Range error occur in the following cases:
cosh: when the argument is too large
sinh: when the argument is too large

Availability: All devices

Requires: #INCLUDE <math.h>

Examples:

```
float phase;
// Output one sine wave
for(phase=0; phase<2*3.141596; phase+=0.01)
   set_analog_voltage( sin(phase)+1 );
```

Example Files: ex_tank.c

Also See: log(), log10(), exp(), pow(), sqrt()

adc_done( )

Syntax: **value = adc_done();**

Parameters: None

channel is an optional parameter for specifying the channel to check if the conversion is done. If not specified will use channel specified in the last call to set_adc_channel(),

	read_adc() or adc_done(). Only available for dsPIC33EPxxGSxxx family.
Returns:	A short int. TRUE if the A/D converter is done with conversion, FALSE if it is still busy.
Function:	Can be polled to determine if the A/D has valid data.
Availability:	Only available on devices with built in analog to digital converters
Requires:	None

Examples:	`int16 value;`
	`setup_adc_ports(sAN0|sAN1, VSS_VDD);`
	`setup_adc(ADC_CLOCK_DIV_4|ADC_TAD_MUL_8);`
	`set_adc_channel(0);`
	`read_adc(ADC_START_ONLY);`
	
	`int1 done = adc_done();`
	`while(!done) {`
	`    done = adc_done();`
	`}`
	`value = read_adc(ADC_READ_ONLY);`
	`printf("A/C value = %LX\n\r", value);`
	`}`

Example Files:	None
Also See:	setup_adc(), set_adc_channel(), setup_adc_ports(), read_adc(), ADC Overview

assert( )

Syntax:	**assert (***condition***);**
Parameters:	***condition*** is any relational expression
Returns:	Nothing
Function:	This function tests the condition and if FALSE will generate an error message on STDERR (by default the first USE RS232 in the program). The error message will include the file and line of the assert(). No code is generated for the assert() if you #define NODEBUG. In this way you may include asserts in your code for testing and quickly eliminate them from the final program.
Availability:	All devices
Requires:	assert.h and #USE RS232
Examples:	`assert( number_of_entries<TABLE_SIZE );`

	`// If number_of_entries is >= TABLE_SIZE then`
	`// the following is output at the RS232:`
	`// Assertion failed, file myfile.c, line 56`

Example Files:	None
Also See:	#USE RS232, RS232 I/O Overview

atoe

Syntax:	**atoe(**string**);**
Parameters:	***string*** *is a pointer to a null terminated string of characters.*
Returns:	Result is a floating point number
Function:	Converts the string passed to the function into a floating point representation. If the result cannot be represented, the behavior is undefined. This function also handles E format numbers
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`char string [10];`
	`float32 x;`
	
	`strcpy (string, "12E3");`
	`x = atoe(string);`
	`// x is now 12000.00`

Example Files:	None
Also See:	atoi(), atol(), atoi32(), atof(), printf()

atof( )

Syntax:	**result = atof (***string***)**
Parameters:	***string*** is a pointer to a null terminated string of characters.
Returns:	Result is a floating point number
Function:	Converts the string passed to the function into a floating point representation. If the result cannot be represented, the behavior is undefined.

Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`char string [10];`
	`float x;`
	
	`strcpy (string, "123.456");`
	`x = atof(string);`
	`// x is now 123.456`

Example Files:	ex_tank.c
Also See:	atoi(), atol(), atoi32(), printf()

pin_select()

Syntax:	**pin_select(**peripheral_pin**,** pin**,** **[**unlock**],**[lock**])**
Parameters:	**periphera**l_pin – a constant string specifying which peripheral pin to map the specified pin to. Refer to #pin_select for all available strings. Using "NULL" for the peripheral_pin parameter will unassign the output peripheral pin that is currently assigned to the pin passed for the pin parameter. **pin** – the pin to map to the specified peripheral pin. Refer to device's header file for pin defines. If the peripheral_pin parameter is an input, passing FALSE for the pin parameter will unassign the pin that is currently assigned to that peripheral pin. **unlock** – optional parameter specifying whether to perform an unlock sequence before writing the RPINRx or RPORx register register determined by peripheral_pin and pin options. Default is TRUE if not specified. The unlock sequence must be performed to allow writes to the RPINRx and RPORx registers. This option allows calling pin_select() multiple times without performing an unlock sequence each time. **lock** – optional parameter specifying whether to perform a lock sequence after writing the RPINRx or RPORx registers. Default is TRUE if not specified. Although not necessary it is a good idea to lock the RPINRx and RPORx registers from writes after all pins have been mapped. This option allows calling pin_select() multiple times without performing a lock sequence each time.
Returns:	Nothing.
Availability:	On device with remappable peripheral pins.
Requires:	Pin defines in device's header file.

Examples:	pin_select("U2TX",PIN_B0);
	
	//Maps PIN_B0 to U2TX //peripheral pin, performs unlock //and lock sequences.
	
	pin_select("U2TX",PIN_B0,TRUE,FALSE);

	//Maps PIN_B0 to U2TX //peripheral pin and performs //unlock sequence.
	
	pin_select(“U2RX”,PIN_B1,FALSE,TRUE);
	
	//Maps PIN_B1 to U2RX //peripheral pin and performs lock //sequence.

Example Files:	None.
Also See:	#pin_select

atoi( )   atol( )   atoi32( )

Syntax:	**ivalue = atoi(***string***)** **or** **lvalue = atol(***string***)** **or** **i32value = atoi32(***string***)**
Parameters:	***string*** is a pointer to a null terminated string of characters.
Returns:	ivalue is an 8 bit int. lvalue is a 16 bit int. i32value is a 32 bit int.
Function:	Converts the string passed to the function into an int representation. Accepts both decimal and hexadecimal argument. If the result cannot be represented, the behavior is undefined.
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`char string[10];`
	`int x;`
	
	`strcpy(string,"123");`
	`x = atoi(string);`
	`// x is now 123`

Example Files:	input.c
Also See:	printf()

at_clear_interrupts( )

Syntax:	**at_clear_interrupts(**interrupts**);**

Parameters:	**interrupts** - an 8-bit constant specifying which AT interrupts to disable. The constants are defined in the device's header file as: · AT_PHASE_INTERRUPT · AT_MISSING_PULSE_INTERRUPT · AT_PERIOD_INTERRUPT · AT_CC3_INTERRUPT · AT_CC2_INTERRUPT · AT_CC1_INTERRUPT
Returns:	Nothing
Function:	To disable the Angular Timer interrupt flags. More than one interrupt can be cleared at a time by or'ing multiple constants together in a single call, or calling function multiple times for each interrupt to clear.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file
Examples:	see below
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

Examples:

```
#INT-AT1
void1_isr(void)
[
   if(at_interrupt_active(AT_PERIOD_INTERRUPT))
   [
      handle_period_interrupt();
      at_clear_interrupts(AT_PERIOD_INTERRUPT);
   ]
   if(at_interrupt(active(AT_PHASE_INTERRUPT);
   [
      handle_phase_interrupt();
      at_clear_interrupts(AT_PHASE_INTERRUPT);
   ]
]
```

at_disable_interrupts( )

Syntax:	**at_disable_interrupts(**interrupts**);**
Parameters:	**interrupts** - an 8-bit constant specifying which AT interrupts to disable. The constants are defined in the device's header file as:

	· AT_PHASE_INTERRUPT · AT_MISSING_PULSE_INTERRUPT · AT_PERIOD_INTERRUPT · AT_CC3_INTERRUPT · AT_CC2_INTERRUPT · AT_CC1_INTERRUPT
Returns:	Nothing
Function:	To disable the Angular Timer interrupts. More than one interrupt can be disabled at a time by or'ing multiple constants together in a single call, or calling function multiple times for eadch interrupt to be disabled.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file

Examples:	`at_disable_interrupts(AT_PHASE_INTERRUPT);`
	`at_disable_interrupts(AT_PERIOD_INTERRUPT|AT_CC1_INTERRUPT);`

Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_enable_interrupts( )

Syntax:	**at_enable_interrupts(**interrupts**);**
Parameters:	**interrupts** - an 8-bit constant specifying which AT interrupts to enable. The constants are defined in the device's header file as: · AT_PHASE_INTERRUPT · AT_MISSING_PULSE_INTERRUPT · AT_PERIOD_INTERRUPT · AT_CC3_INTERRUPT · AT_CC2_INTERRUPT · AT_CC1_INTERRUPT
Returns:	Nothing
Function:	To enable the Angular Timer interrupts. More than one interrupt can be enabled at a time by or'ing multiple constants together in a single call, or calling function multiple times for each interrupt to be enabled.

Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file

Examples:	`at_enable_interrupts(AT_PHASE_INTERRUPT);`
	`at_enable_interrupts(AT_PERIOD_INTERRUPT|AT_CC1_INTERRUPT);`

Example Files:	None
Also See:	setup_at(), at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point(), at_get_set_point_error(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status()

at_get_capture( )

Syntax:	**result=at_get_capture(**which**);;**
Parameters:	**which** - an 8-bit constant specifying which AT Capture/Compare module to get the capture time from, can be 1, 2 or 3.
Returns:	A 16-bit integer
Function:	To get one of the Angular Timer Capture/Compare modules capture time.
Availability:	All devices with an AT module.
Requires:	Nothing

Examples:	`result1=at_get_capture(1);`
	`result2=at_get_capture(2);`

Example Files:	None
Also See:	setup_at(), at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_status()

at_get_missing_pulse_delay( )

Syntax:	**result=at_get_missing_pulse_delay();**
Parameters:	None.
Returns:	A 16-bit integer
Function:	To setup the Angular Timer Missing Pulse Delay
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`result=at_get_missing_pulse_delay();`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_get_period( )

Syntax:	**result=at_get_period();**
Parameters:	None.
Returns:	A 16-bit integer. The MSB of the returned value specifies whether the period counter rolled over one or more times. 1 - counter rolled over at least once, 0 - value returned is valid.
Function:	To get Angular Timer Measured Period
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`result=at_get_period();`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_get_phase_counter( )

Syntax:	**result=at_get_phase_counter();**
Parameters:	None.
Returns:	A 16-bit integer.
Function:	To get the Angular Timer Phase Counter
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`result=at_get_phase_counter();`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_get_resolution( )

Syntax:	**result=at_get_resolution();**
Parameters:	None
Returns:	A 16-bit integer
Function:	To setup the Angular Timer Resolution
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`result=at_get_resolution();`

Example Files:	None
Also See:	at_set_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_get_set_point( )

Syntax:	**result=at_get_set_point();**
Parameters:	None
Returns:	A 16-bit integer
Function:	To get the Angular Timer Set Point
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`result=at_get_set_point();`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

.

at_get_set_point_error( )

Syntax:	**result=at_get_set_point_error();**
Parameters:	None
Returns:	A 16-bit integer
Function:	To get the Angular Timer Set Point Error, the error of the measured period value compared to the threshold setting.
Availability:	All devices with an AT module.

Requires:	Nothing
Examples:	`result=at_get_set_point_error();`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

.

at_get_status( )

Syntax:	**result=at_get_status();**
Parameters:	None
Returns:	An 8-bit integer. The possible results are defined in the device's header file as: · AT_STATUS_PERIOD_AND_PHASE_VALID · AT_STATUS_PERIOD_LESS_THEN_PREVIOUS
Function:	To get the status of the Angular Timer module.
Availability:	All devices with an AT module.
Requires:	Nothing

Examples:	`if((at_get_status()&AT_STATUS_PERIOD_AND_PHASE_VALID)==`
	`AT_STATUS_PERIOD_AND_PHASE_VALID`
	`[`
	`   Period=at_get_period();`
	`   Phase=at_get_phase();`
	`]`

Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), setup_at()

at_interrupt_active( )

Syntax:	**result=at_interrupt_active(**interrupt**);**
Parameters:	**interrupts** - an 8-bit constant specifying which AT interrupts to check if its flag is set. The constants are defined in the device's header file as: · AT_PHASE_INTERRUPT · AT_MISSING_PULSE_INTERRUPT · AT_PERIOD_INTERRUPT · AT_CC3_INTERRUPT · AT_CC2_INTERRUPT · AT_CC1_INTERRUPT
Returns:	TRUE if the specified AT interrupt's flag is set, interrupt is active, or FALSE if the flag is clear, interrupt is not active.
Function:	To check if the specified Angular Timer interrupt flag is set.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file
Examples:	see below
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

Examples:

```
#INT-AT1
void1_isr(void)
[
   if(at_interrupt_active(AT_PERIOD_INTERRUPT))
   [
      handle_period_interrupt();
      at_clear_interrupts(AT_PERIOD_INTERRUPT);
   ]
   if(at_interrupt(active(AT_PHASE_INTERRUPT);
   [
      handle_phase_interrupt();
      at_clear_interrupts(AT_PHASE_INTERRUPT);
   ]
]
```

at_set_compare_time( )

Syntax:	**at_set_compare_time(**which, compare_time**);**
Parameters:	**which** - an 8-bit constant specifying which AT Capture/Compare module to set the compare time for, can be 1, 2, or 3. **compare_time** - a 16-bit constant or variable specifying the value to trigger an interrupt/ouput pulse.
Returns:	Nothing
Function:	To set one of the Angular Timer Capture/Compare module's compare time.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file

Examples:	`at_set_compare_time(1,0x1FF);`
	`at_set_compare_time(3,compare_time);`

Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_get_capture(), at_get_status(), setup_at()

at_set_missing_pulse_delay( )

Syntax:	**at_set_missing_pulse_delay(pulse_delay);**
Parameters:	**pulse_delay** - a signed 16-bit constant or variable to set the missing pulse delay.
Returns:	Nothing
Function:	To setup the Angular Timer Missing Pulse Delay
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`at_set_missing_pulse_delay(pulse_delay);`

Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_set_resolution( )

Syntax:	**at_set_resolution(**resolution**);**
Parameters:	**resolution** - a 16-bit constant or variable to set the resolution.
Returns:	Nothing
Function:	To setup the Angular Timer Resolution
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`at_set_resolution(resolution);`
Example Files:	None
Also See:	at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

at_set_set_point( )

Syntax:	**at_set_set_point(**set_point**);**
Parameters:	**set_point** - a 16-bit constant or variable to set the set point. The set point determines the threshold setting that the period is compared against for error calculation.
Returns:	Nothing

Function:	To get the Angular Timer Set Point
Availability:	All devices with an AT module.
Requires:	Nothing
Examples:	`at_set_set_point(set_point);`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

.

at_setup_cc( )

Syntax:	**at_setup_cc(**which, settings**);**
Parameters:	**which** - an 8-bit constant specifying which AT Capture/Compare to setup, can be 1, 2 or 3. **settings** - a 16-bit constant specifying how to setup the specified AT Capture/Compare module. See the device's header file for all options. Some of the typical options include: · AT_CC_ENABLED · AT_CC_DISABLED · AT_CC_CAPTURE_MODE · AT_CC_COMPARE_MODE · AT_CAPTURE_FALLING_EDGE · AT_CAPTURE_RISING_EDGE
Returns:	Nothing
Function:	To setup one of the Angular Timer Capture/Compare modules to the specified settings.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's header file

Examples:	`at_setup_cc(1,AT_CC_ENABLED|AT_CC_CAPTURE_MODE|`
	`AT_CAPTURE_FALLING_EDGE|AT_CAPTURE_INPUT_ATCAP);`
	
	`at_setup_cc(2,AT_CC_ENABLED|AT_CC_CAPTURE_MODE|`
	`AT_CC_ACTIVE_HIGH);`

Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_set_compare_time(), at_get_capture(), at_get_status(), setup_at()

bit_clear( )

Syntax:	**bit_clear(***var*, *bit***)**
Parameters:	***var*** may be a any bit variable (any lvalue) ***bit*** is a number 0- 31 representing a bit number, 0 is the least significant bit.
Returns:	undefined
Function:	Simply clears the specified bit (0-7, 0-15 or 0-31) in the given variable. The least significant bit is 0. This function is the similar to: var &= ~(1<<bit);
Availability:	All devices
Requires:	Nothing

Examples:	`int x;`
	`x=5;`
	`bit_clear(x,2);`
	`// x is now 1`

Example Files:	ex_patg.c
Also See:	bit_set(), bit_test()

bit_set( )

Syntax:	**bit_set(***var*, *bit***)**
Parameters:	***var*** may be a 8,16 or 32 bit variable (any lvalue) ***bit*** is a number 0- 31 representing a bit number, 0 is the least significant bit.
Returns:	Undefined
Function:	Sets the specified bit (0-7, 0-15 or 0-31) in the given variable. The least significant bit is 0. This function is the similar to: var |= (1<<bit);

Availability:	All devices
Requires:	Nothing

Examples:	`int x;`
	`x=5;`
	`bit_set(x,3);`
	`// x is now 13`

Example Files:	ex_patg.c
Also See:	bit_clear(), bit_test()

bit_test( )

Syntax:	**value = bit_test (*var*, *bit*)**
Parameters:	***var*** may be a 8,16 or 32 bit variable (any lvalue) ***bit*** is a number 0- 31 representing a bit number, 0 is the least significant bit.
Returns:	0 or 1
Function:	Tests the specified bit (0-7,0-15 or 0-31) in the given variable. The least significant bit is 0. This function is much more efficient than, but otherwise similar to: ((var & (1<<bit)) != 0)
Availability:	All devices
Requires:	Nothing
Examples:	see below
Example Files:	ex_patg.c
Also See:	bit_clear(), bit_set()

```
if( bit_test(x,3) || !bit_test (x,1) ){
         //either bit 3 is 1 or bit 1 is 0
}


if(data!=0)
  for(i=31;!bit_test(data, i);i--) ;
// i now has the most significant bit in data
// that is set to a 1
```

brownout_enable( )

Syntax:	**brownout_enable (*value*)**
Parameters:	***value*** – TRUE or FALSE
Returns:	undefined
Function:	Enable or disable the software controlled brownout. Brownout will cause the PIC to reset if the power voltage goes below a specific set-point.
Availability:	This function is only available on PICs with a software controlled brownout. This may also require a specific configuration bit/fuse to be set for the brownout to be software controlled.
Requires:	Nothing
Examples:	`brownout_enable(TRUE);`
Example Files:	None
Also See:	restart_cause()

bsearch( )

Syntax:	**ip = bsearch (*&key, base, num, width, compare*)**
Parameters:	***key***: Object to search for ***base***: Pointer to array of search data ***num***: Number of elements in search data ***width***: Width of elements in search data ***compare***: Function that compares two elements in search data
Returns:	bsearch returns a pointer to an occurrence of key in the array pointed to by base. If key is not found, the function returns NULL. If the array is not in order or contains duplicate records with identical keys, the result is unpredictable.
Function:	Performs a binary search of a sorted array
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`int nums[5]={1,2,3,4,5};`
	`int compar(const void *arg1,const void *arg2);`
	
	`void main() {`

```
   int *ip, key;
   key = 3;
   ip = bsearch(&key, nums, 5, sizeof(int), compar);
}

int compar(const void *arg1,const void *arg2)  {
   if ( * (int *) arg1 < ( * (int *) arg2) return -1
   else if ( * (int *) arg1 == ( * (int *) arg2) return 0
   else return 1;
}
```

Example Files:	None
Also See:	qsort()

calloc( )

Syntax:	**ptr=calloc(*nmem*, *size*)**
Parameters:	***nmem*** is an integer representing the number of member objects **size** is the number of bytes to be allocated for each one of them.
Returns:	A pointer to the allocated memory, if any. Returns null otherwise.
Function:	The calloc function allocates space for an array of nmem objects whose size is specified by size. The space is initialized to all bits zero.
Availability:	All devices
Requires:	#INCLUDE <stdlibm.h>

Examples:	`int * iptr;`
	`iptr=calloc(5,10);`
	`// iptr will point to a block of memory of`
	`// 50 bytes all initialized to 0.`

Example Files:	None
Also See:	realloc(), free(), malloc()

ceil( )

Syntax:	**result = ceil (*value*)**
Parameters:	***value*** is a float

Returns:	A float
Function:	Computes the smallest integer value greater than the argument. CEIL(12.67) is 13.00.
Availability:	All devices
Requires:	#INCLUDE<math.h>

Examples:	`// Calculate cost based on weight rounded`
	`// up to the next pound`
	
	`cost = ceil( weight ) * DollarsPerPound;`

Example Files:	None
Also See:	floor()

clc1_setup_gate() clc2_setup_gate() clc3_setup_gate() clc4_setup_gate()

Syntax:	**clc1_setup_gate(gate, mode);**
	clc2_setup_gate(gate, mode);
	clc3_setup_gate(gate, mode);
	clc4_setup_gate(gate, mode);

Parameters:	**gate** – selects which data gate of the Configurable Logic Cell (CLC) module to setup, value can be 1 to 4. **mode** – the mode to setup the specified data gate of the CLC module into. The options are: CLC_GATE_AND CLC_GATE_NAND CLC_GATE_NOR CLC_GATE_OR CLC_GATE_CLEAR CLC_GATE_SET
Returns:	Undefined
Function:	Sets the logic function performed on the inputs for the specified data gate.
Availability:	On devices with a CLC module.
Retu rns:	Undefined.
Examples:	`clc1_setup_gate(1, CLC_GATE_AND);`

	`clc1_setup_gate(2, CLC_GATE_NAND);`
	`clc1_setup_gate(3, CLC_GATE_CLEAR);`
	`clc1_setup_gate(4, CLC_GATE_SET);`

Example Files:	None
Also See:	setup_clcx(), clcx_setup_input()

clc1_setup_input() clc2_setup_input() clc3_setup_input() clc4_setup_input()

Syntax:	**clc1_setup_input(**input**,** selection**);**
	clc2_setup_input(input**,** selection**);**
	clc3_setup_input(input**,** selection**);**
	clc4_setup_input(input**,** selection**);**

Parameters:	**input** – selects which input of the Configurable Logic Cell (CLC) module to setup, value can be 1 to 4. **selection** – the actual input for the specified input that is actually connected to the data gates of the CLC module. The options are: CLC_INPUT_0 CLC_INPUT_1 CLC_INPUT_2 CLC_INPUT_3 CLC_INPUT_4 CLC_INPUT_5 CLC_INPUT_6 CLC_INPUT_7
Returns:	Undefined.
Function:	Sets the input for the specified input number that is actually connected to all four data gates of the CLC module. Please refer to the table CLCx DATA INPUT SELECTION in the device's datasheet to determine which of the above selections corresponds to actual input pin or peripheral of the device.
Availability:	On devices with a CLC module.
Retu rns:	Undefined.

Examples:	`clc1_setup_input(1, CLC_INPUT_0);`
	`clc1_setup_input(2, CLC_INPUT_1);`
	`clc1_setup_input(3, CLC_INPUT_2);`
	`clc1_setup_input(4, CLC_INPUT_3);`

Example Files:	None

Also See:	setup_clcx(), clcx_setup_gate()

clear_interrupt( )

Syntax:	**clear_interrupt(***level***)**
Parameters:	**level** - a constant defined in the devices.h file
Returns:	undefined
Function:	Clears the interrupt flag for the given level. This function is designed for use with a specific interrupt, thus eliminating the GLOBAL level as a possible parameter. Some chips that have interrupt on change for individual pins allow the pin to be specified like INT_RA1.
Availability:	All devices
Requires:	Nothing
Examples:	`clear_interrupt(int_timer1);`
Example Files:	None

Also See:	enable_interrupts() , #INT , Interrupts Overview
	disable_interrupts(), interrupt_actvie()

clear_pwm1_interrupt( ) clear_pwm2_interrupt( ) clear_pwm3_interrupt( ) clear_pwm4_interrupt( ) clear_pwm5_interrupt( ) clear_pwm6_interrupt( )

Syntax:	**clear_pwm1_interrupt (***interrupt***)** **clear_pwm2_interrupt (***interrupt***)** **clear_pwm3_interrupt (***interrupt***)** **clear_pwm4_interrupt (***interrupt***)** **clear_pwm5_interrupt (***interrupt***)** **clear_pwm6_interrupt (***interrupt***)**
Parameters:	***interrupt*** - 8-bit constant or variable. Constants are defined in the device's header file as: • PWM_PERIOD_INTERRUPT • PWM_DUTY_INTERRUPT • PWM_PHASE_INTERRUPT • PWM_OFFSET_INTERRUPT

Returns:	undefined.
Function:	Clears one of the above PWM interrupts, multiple interrupts can be cleared by or'ing multiple options together.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`clear_pwm1_interrupt(PWM_PERIOD_INTERRUPT);`
	`clear_pwm1_interrupt(PWM_PERIOD_INTERRUPT | PWM_DUTY_INTERRUPT);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

cog_status( )

Syntax:	**value=cog_status();**
Parameters:	None
Returns:	value - the status of the COG module
Function:	To determine if a shutdown event occurred on the Complementary Output Generator (COG) module.
Availability:	All devices with a COG module.

Examples:	`if(cog_status()==COG_AUTO_SHUTDOWN)`
	`  cog_restart();`

Example Files:	None
Also See:	setup_cog(), set_cog_dead_band(), set_cog_blanking(), set_cog_phase(), cog_restart()

.

cog_restart( )

Syntax:	**cog_restart();**
Parameters:	None
Returns:	Nothing
Function:	To restart the Complementary Output Generator (COG) module after an auto-shutdown event occurs, when not using auto-restart option of module.
Availability:	All devices with a COG module.

Examples:	`if(cog_status()==COG_AUTO_SHUTDOWN)`
	`  cog_restart();`

Example Files:	None
Also See:	setup_cog(), set_cog_dead_band(), set_cog_blanking(), set_cog_phase(), cog_status()

crc_calc( ) crc_calc8( ) crc_calc16( )

Syntax:	**Result = crc_calc (**data,[width]**);**
	Result = crc_calc(ptr,len,[width]**);**
	Result = crc_calc8(data,[width]**);**
	Result = crc_calc8(ptr,len,[width]**);**
	Result = crc_calc16(data,[width]**);** **//same as crc_calc( )**
	Result = crc_calc16(ptr,len,[width]**);** **//same as crc_calc( )**

Parameters:	**data**- This is one double word, word or byte that needs to be processed when using crc_calc16( ), or crc_calc8( ) **ptr**- is a pointer to one or more double words, words or bytes of data **len**- number of double words, words or bytes to process for function calls crc_calc16( ), or crc_calc8( ) **width**- optional parameter used to specify the input data bit width to use with the functions crc_calc16( ), and crc_calc8( ) If not specified, it defaults to the width of the return value of the function, 8-bit for crc_calc8( ), 16-bit for crc_calc16( ) For devices with a 16-bit for CRC the input data bit width is the same as the return bit width, crc_calc16( ) and 8-bit crc_calc8( ).
Returns:	Returns the result of the final CRC calculation.
Function:	This will process one data double word, word or byte or **len** double words, words or bytes of

	data using the CRC engine.
Availability:	Only the devices with built in CRC module.
Requires:	Nothing

Examples:	`int16 data[8];`
	`Result = crc_calc(data,8);`

Example Files:	None
Also See:	setup_crc(); crc_init()

crc_init(mode)

Syntax:	**crc_init (*data*);**
Parameters:	***data*** - This will setup the initial value used by write CRC shift register. Most commonly, this register is set to 0x0000 for start of a new CRC calculation.
Returns:	undefined
Function:	Configures the CRCWDAT register with the initial value used for CRC calculations.
Availability:	Only the devices with built in CRC module.
Requires:	Nothing

Examples:	`crc_init (); // Starts the CRC accumulator out at 0`
	
	`crc_init(0xFEEE); // Starts the CRC accumulator out at 0xFEEE`

Example Files:	None
Also See:	setup_crc(), crc_calc(), crc_calc8()

cwg_status( )

Syntax:	**value = cwg_status( );**
Parameters:	None

Returns:	the status of the CWG module
Function:	To determine if a shutdown event occured causing the module to auto-shutdown
Availability:	On devices with a CWG module.

Examples:	`if(cwg_status( ) == CWG_AUTO_SHUTDOWN)`
	`  cwg_restart( );`

Example Files:	None
Also See:	setup_cwg( ), cwg_restart( )

cwg_restart( )

Syntax:	**cwg_restart( );**
Parameters:	None
Returns:	Nothing
Function:	To restart the CWG module after an auto-shutdown event occurs, when not using auto-raster option of module.
Availability:	On devices with a CWG module.

Examples:	`if(cwg_status( ) == CWG_AUTO_SHUTDOWN)`
	`  cwg_restart( );`

Example Files:	None
Also See:	setup_cwg( ), cwg_status( )

dac_write( )

Syntax:	**dac_write (**value**)**
Parameters:	**Value**: 8-bit integer value to be written to the DAC module
Returns:	undefined

Function:	This function will write a 8-bit integer to the specified DAC channel.
Availability:	Only available on devices with built in digital to analog converters.
Requires:	Nothing

Examples:	`int i = 0;`
	`setup_dac(DAC_VDD | DAC_OUTPUT);`
	`while(1){`
	`     i++;`
	`     dac_write(i);`
	`}`

Also See:	setup_dac( ), DAC Overview, see header file for device selected

delay_cycles( )

Syntax:	**delay_cycles (*count*)**
Parameters:	***count*** - a constant 1-255
Returns:	undefined
Function:	Creates code to perform a delay of the specified number of instruction clocks (1-255). An instruction clock is equal to four oscillator clocks. The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.
Availability:	All devices
Requires:	Nothing

Examples:	`delay_cycles( 1 ); // Same as a NOP`
	
	`delay_cycles(25); // At 20 mhz a 5us delay`

Example Files:	ex_cust.c
Also See:	delay_us(), delay_ms()

delay_ms( )

Syntax:	**delay_ms (*time*)**

Parameters:	***time*** - a variable 0-65535(int16) or a constant 0-65535 Note: Previous compiler versions ignored the upper byte of an int16, now the upper byte affects the time.
Returns:	undefined
Function:	This function will create code to perform a delay of the specified length. Time is specified in milliseconds. This function works by executing a precise number of instructions to cause the requested delay. It does not use any timers. If interrupts are enabled the time spent in an interrupt routine is not counted toward the time. The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.
Availability:	All devices
Requires:	#USE DELAY

Examples:	`#use delay (clock=20000000)`
	
	`delay_ms( 2 );`
	
	`void delay_seconds(int n) {`
	`  for (;n!=0; n- -)`
	`  delay_ms( 1000 );`
	`}`

Example Files:	ex_sqw.c
Also See:	delay_us(), delay_cycles(), #USE DELAY

delay_us( )

Syntax:	**delay_us (*time*)**
Parameters:	***time*** - a variable 0-65535(int16) or a constant 0-65535 Note: Previous compiler versions ignored the upper byte of an int16, now the upper byte affects the time.
Returns:	undefined
Function:	Creates code to perform a delay of the specified length. Time is specified in microseconds. Shorter delays will be INLINE code and longer delays and variable delays are calls to a function. This function works by executing a precise number of instructions to cause the requested delay. It does not use any timers. If interrupts are enabled the time

	spent in an interrupt routine is not counted toward the time. The delay time may be longer than requested if an interrupt is serviced during the delay. The time spent in the ISR does not count toward the delay time.
Availability:	All devices
Requires:	#USE DELAY

Examples:	`#use delay(clock=20000000)`
	
	`do {`
	`output_high(PIN_B0);`
	`delay_us(duty);`
	`output_low(PIN_B0);`
	`delay_us(period-duty);`
	`} while(TRUE);`

Example Files:	ex_sqw.c
Also See:	delay_ms(), delay_cycles(), #USE DELAY

disable_interrupts( )

Syntax:	**disable_interrupts (*level*)**
Parameters:	***level*** - a constant defined in the devices .h file
Returns:	undefined
Function:	Disables the interrupt at the given level. The GLOBAL level will not disable any of the specific interrupts but will prevent any of the specific interrupts, previously enabled to be active. Valid specific levels are the same as are used in #INT_xxx and are listed in the devices .h file. GLOBAL will also disable the peripheral interrupts on devices that have it. Note that it is not necessary to disable interrupts inside an interrupt service routine since interrupts are automatically disabled. Some chips that have interrupt on change for individual pins allow the pin to be specified like INT_RA1.
Availability:	Device with interrupts (PCM and PCH)
Requires:	Should have a #INT_xxxx, constants are defined in the devices .h file.

Examples:	`disable_interrupts(GLOBAL);  // all interrupts OFF`
	`disable_interrupts(INT_RDA); // RS232 OFF`
	
	`enable_interrupts(ADC_DONE);`
	`enable_interrupts(RB_CHANGE);`
	`   // these enable the interrupts`
	`   // but since the GLOBAL is disabled they`

```
   // are not activated until the following
   // statement:
enable_interrupts(GLOBAL);
```

Example Files:	ex_sisr.c, ex_stwt.c
Also See:	enable_interrupts(), clear_interrupt (), #INT_xxxx, Interrupts Overview, interrupt_active()

disable_pwm1_interrupt( ) disable_pwm2_interrupt( ) disable_pwm3_interrupt( ) disable_pwm4_interrupt( ) disable_pwm5_interrupt( ) disable_pwm6_interrupt( )

Syntax:	**disable_pwm1_interrupt (***interrupt***)** **disable_pwm2_interrupt (***interrupt***)** **disable_pwm3_interrupt (***interrupt***)** **disable_pwm4_interrupt (***interrupt***)** **disable_pwm5_interrupt (***interrupt***)** **disable_pwm6_interrupt (***interrupt***)**
Parameters:	***interrupt*** - 8-bit constant or variable. Constants are defined in the device's header file as: • PWM_PERIOD_INTERRUPT • PWM_DUTY_INTERRUPT • PWM_PHASE_INTERRUPT • PWM_OFFSET_INTERRUPT
Returns:	undefined.
Function:	Disables one of the above PWM interrupts, multiple interrupts can be disabled by or'ing multiple options together.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`disable_pwm1_interrupt(PWM_PERIOD_INTERRUPT);`
	`disable_pwm1_interrupt(PWM_PERIOD_INTERRUPT | PWM_DUTY_INTERRUPT);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(), enable_pwm_interrupt(), clear_pwm_interrupt(), pwm_interrupt_active()

div( ) ldiv( )

Syntax:	**idiv=div(***num*, *denom***)** **ldiv =ldiv(***lnum*, *ldenom***)**
Parameters:	***num*** and ***denom*** are signed integers. ***num*** is the numerator and ***denom*** is the denominator. ***lnum*** and ***ldenom*** are signed longs ***lnum*** is the numerator and ***ldenom*** is the denominator.
Returns:	idiv is a structure of type div_t and lidiv is a structure of type ldiv_t. The div function returns a structure of type div_t, comprising of both the quotient and the remainder. The ldiv function returns a structure of type ldiv_t, comprising of both the quotient and the remainder.
Function:	The div and ldiv function computes the quotient and remainder of the division of the numerator by the denominator. If the division is inexact, the resulting quotient is the integer or long of lesser magnitude that is the nearest to the algebraic quotient. If the result cannot be represented, the behavior is undefined; otherwise quot*denom(ldenom)+rem shall equal num(lnum).
Availability:	All devices.
Requires:	#INCLUDE <STDLIB.H>

Examples:	`div_t idiv;`
	`ldiv_t lidiv;`
	`idiv=div(3,2);`
	`//idiv will contain quot=1 and rem=1`
	
	`lidiv=ldiv(300,250);`
	`//lidiv will contain lidiv.quot=1 and lidiv.rem=50`

Example Files:	None
Also See:	None

enable_interrupts( )

Syntax:	**enable_interrupts (***level***)**
Parameters:	***level*** is a constant defined in the devices **.h* file.
Returns:	undefined.
Function:	This function enables the interrupt at the given level. An interrupt procedure should have been defined for the indicated interrupt. The GLOBAL level will not enable any of the specific interrupts, but will allow any of the specified interrupts previously enabled to become active. Some chips that have an interrupt

	on change for individual pins all the pin to be specified, such as INT_RA1. For interrupts that use edge detection to trigger, it can be setup in the enable_interrupts( ) function without making a separate call to the set_int_edge( ) function. Enabling interrupts does not clear the interrupt flag if there was a pending interrupt prior to the call. Use the clear_interrupt( ) function to clear pending interrupts before the call to enable_interrupts( ) to discard the prior interrupts.
Availability:	Devices with interrupts.
Requires:	Should have a #INT_XXXX to define the ISR, and constants are defined in the devices *.h* file.

Examples:	`enable_interrupts(GLOBAL);`
	`enable_interrupts(INT_TIMER0);`
	`enable_interrupts( INT_EXT_H2L );`

Example Files:	ex_sisr.c, ex_stwt.c
Also See:	disable interrupts(), clear_interrupt (), ext_int_edge( ), #INT_xxxx, Interrupts Overview, interrupt_active()

enable_pwm1_interrupt( ) enable_pwm2_interrupt( ) enable_pwm3_interrupt( ) enable_pwm4_interrupt( ) enable_pwm5_interrupt( ) enable_pwm6_interrupt( )

Syntax:	**enable_pwm1_interrupt (***interrupt***)** **enable_pwm2_interrupt (***interrupt***)** **enable_pwm3_interrupt (***interrupt***)** **enable_pwm4_interrupt (***interrupt***)** **enable_pwm5_interrupt (***interrupt***)** **enable_pwm6_interrupt (***interrupt***)**
Parameters:	***interrupt*** - 8-bit constant or variable. Constants are defined in the device's header file as: • PWM_PERIOD_INTERRUPT • PWM_DUTY_INTERRUPT • PWM_PHASE_INTERRUPT • PWM_OFFSET_INTERRUPT
Returns:	undefined.
Function:	Enables one of the above PWM interrupts, multiple interrupts can be enabled by or'ing multiple options together. For the interrupt to occur, the overall PWMx interrupt still needs to be enabled and an interrupt service routine still needs to be created.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`enable_pwm1_interrupt(PWM_PERIOD_INTERRUPT);`
	`enable_pwm1_interrupt(PWM_PERIOD_INTERRUPT | PWM_DUTY_INTERRUPT);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(), disable_pwm_interrupt(), clear_pwm_interrupt(), pwm_interrupt_active()

erase_eeprom( )

Syntax:	**erase_eeprom (address);**
Parameters:	address is 8 bits on PCB parts.
Returns:	undefined
Function:	This will erase a row of the EEPROM or Flash Data Memory.
Availability:	PCB devices with EEPROM like the 12F519
Requires:	Nothing
Examples:	`erase_eeprom(0);  // erase the first row of the EEPROM (8  bytes)`
Example Files:	None
Also See:	write program eeprom(), write program memory(), Program Eeprom Overview

erase_program_eeprom( )

Syntax:	**erase_program_eeprom (***address***);**
Parameters:	***address*** is 16 bits on PCM parts and 32 bits on PCH parts . The least significant bits may be ignored.
Returns:	undefined
Function:	Erases FLASH_ERASE_SIZE bytes to 0xFFFF in program memory. FLASH_ERASE_SIZE varies depending on the part. For example, if it is 64 bytes then the least significant 6 bits of address is ignored.

	See write_program_memory() for more information on program memory access.
Availability:	Only devices that allow writes to program memory.
Requires:	Nothing
Examples:	`for(i=0x1000;i<=0x1fff;i+=getenv("FLASH_ERASE_SIZE"))` `erase_program_memory(i);`
Example Files:	None
Also See:	write program eeprom(), write program memory(), Program Eeprom Overview

exp( )

Syntax:	**result = exp (*value*)**
Parameters:	***value*** is a float
Returns:	A float
Function:	Computes the exponential function of the argument. This is e to the power of value where e is the base of natural logarithms. exp(1) is 2.7182818. Note on error handling: If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function. Range error occur in the following case: • exp: when the argument is too large
Availability:	All devices
Requires:	#INCLUDE <math.h>

Examples:	`// Calculate x to the power of y`
	
	`x_power_y = exp( y * log(x) );`

Example Files:	None
Also See:	pow(), log(), log10()

ext_int_edge( )

Syntax:	**ext_int_edge (***source*, *edge***)**
Parameters:	***source*** is a constant 0,1 or 2 for the PIC18XXX and 0 otherwise. Source is optional and defaults to 0. ***edge*** is a constant H_TO_L or L_TO_H representing "high to low" and "low to high"
Returns:	undefined
Function:	Determines when the external interrupt is acted upon. The edge may be L_TO_H or H_TO_L to specify the rising or falling edge.
Availability:	Only devices with interrupts (PCM and PCH)
Requires:	Constants are in the devices .h file

Examples:	`ext_int_edge( 2, L_TO_H); // Set up PIC18 EXT2`
	`ext_int_edge( H_TO_L );   // Sets up EXT`

Example Files:	ex_wakup.c
Also See:	#INT_EXT , enable_interrupts() , disable_interrupts() , Interrupts Overview

fabs( )

Syntax:	**result=fabs (***value***)**
Parameters:	***value*** is a float
Returns:	result is a float
Function:	The fabs function computes the absolute value of a float
Availability:	All devices.
Requires:	#INCLUDE <math.h>

Examples:	`float result;`
	`result=fabs(-40.0)`
	`// result is 40.0`

Example Files:	None
Also See:	abs(), labs()

getc( ) getch( ) getchar( ) fgetc( )

Syntax:	**value = getc()** **value = fgetc(*stream*)** **value=getch()** **value=getchar()**
Parameters:	***stream*** is a stream identifier (a constant byte)
Returns:	An 8 bit character
Function:	This function waits for a character to come in over the RS232 RCV pin and returns the character. If you do not want to hang forever waiting for an incoming character use kbhit() to test for a character available. If a built-in USART is used the hardware can buffer 3 characters otherwise GETC must be active while the character is being received by the PIC®. If fgetc() is used then the specified stream is used where getc() defaults to STDIN (the last USE RS232).
Availability:	All devices
Requires:	#USE RS232
Examples:	see below
Example Files:	ex_stwt.c
Also See:	putc(), kbhit(), printf(), #USE RS232, input.c, RS232 I/O Overview

```
printf("Continue (Y,N)?");
do {
   answer=getch();
}while(answer!='Y' && answer!='N');


#use rs232(baud=9600,xmit=pin_c6,
              rcv=pin_c7,stream=HOSTPC)
#use rs232(baud=1200,xmit=pin_b1,
            rcv=pin_b0,stream=GPS)
#use rs232(baud=9600,xmit=pin_b3,
            stream=DEBUG)
...
while(TRUE) {
   c=fgetc(GPS);
   fputc(c,HOSTPC);
   if(c==13)
     fprintf(DEBUG,"Got a CR\r\n");
}
```

floor( )

Syntax:	**result = floor (*value*)**
Parameters:	***value*** is a float
Returns:	result is a float
Function:	Computes the greatest integer value not greater than the argument. Floor (12.67) is 12.00.
Availability:	All devices.
Requires:	#INCLUDE <math.h>

Examples:	`// Find the fractional part of a value`
	
	`frac = value - floor(value);`

Example Files:	None
Also See:	ceil()

fmod( )

Syntax:	**result= fmod (*val1*, *val2*)**
Parameters:	***val1*** is a float ***val2*** is a float
Returns:	result is a float
Function:	Returns the floating point remainder of val1/val2. Returns the value val1 - i*val2 for some integer “i” such that, if val2 is nonzero, the result has the same sign as val1 and magnitude less than the magnitude of val2.
Availability:	All devices.
Requires:	#INCLUDE <math.h>

Examples:	`float result;`
	`result=fmod(3,2);`
	`// result is 1`

Example Files:	None
Also See:	None

free( )

Syntax:	**free(*ptr*)**
Parameters:	***ptr*** is a pointer earlier returned by the calloc, malloc or realloc.
Returns:	No value
Function:	The free function causes the space pointed to by the ptr to be deallocated, that is made available for further allocation. If ptr is a null pointer, no action occurs. If the ptr does not match a pointer earlier returned by the calloc, malloc or realloc, or if the space has been deallocated by a call to free or realloc function, the behavior is undefined.
Availability:	All devices.
Requires:	#INCLUDE <stdlibm.h>

Examples:	`int * iptr;`
	`iptr=malloc(10);`
	`free(iptr)`
	`// iptr will be deallocated`

Example Files:	None
Also See:	realloc(), malloc(), calloc()

frexp( )

Syntax:	**result=frexp (*value*, &*exp*);**
Parameters:	***value*** is a float ***exp*** is a signed int.
Returns:	result is a float
Function:	The frexp function breaks a floating point number into a normalized fraction and an integral power of 2. It stores the integer in the signed int object exp. The result is in the interval [1/2 to1) or zero, such that value is result times 2 raised to power exp. If value is zero then both parts are zero.
Availability:	All devices.
Requires:	#INCLUDE <math.h>

Examples:	`float result;`
	`signed int exp;`
	`result=frexp(.5,&exp);`
	`//  result is .5 and exp is 0`

Example Files:	None
Also See:	ldexp(), exp(), log(), log10(), modf()

get_capture( )

Syntax:	**value = get_capture(*x*)**
Parameters:	***x*** defines which ccp module to read from.
Returns:	A 16-bit timer value.
Function:	This function obtains the last capture time from the indicated CCP module
Availability:	Only available on devices with Input Capture modules
Requires:	None
Examples:	
Example Files:	ex_ccpmp.c
Also See:	setup_ccpx( )

get_capture_event()

Syntax:	**result = get_capture_event([**stream**]);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE CAPTURE.
Returns:	TRUE if a capture event occurred, FALSE otherwise.
Function:	To determine if a capture event occurred.
Availability:	All devices.

Requires:	#USE CAPTURE

Examples:	#USE CAPTURE(INPUT=PIN_C2,CAPTURE_RISING,TIMER=1,FASTEST)
	if(get_capture_event())
	   result = get_capture_time();

Example Files:	None
Also See:	#use_capture, get_capture_time()

get_capture_time()

Syntax:	**result = get_capture_time([stream]);**
Parameters:	stream – optional parameter specifying the stream defined in #USE CAPTURE.
Returns:	An int16 value representing the last capture time.
Function:	To get the last capture time.
Availability:	All devices.
Requires:	#USE CAPTURE

Examples:	`#USE CAPTURE(INPUT=PIN_C2,CAPTURE_RISING,TIMER=1,FASTEST)`
	`result = get_capture_time();`

Example Files:	None
Also See:	#use_capture, get_capture_event()

get_capture32()

Syntax:	**result = get_capture32(**x,[wait]**);**
Parameters:	**x** is 1-16 and defines which input capture result buffer modules to read from. **wait** is an optional parameter specifying if the compiler should read the oldest result in the bugger or the next result to enter the buffer.
Returns:	A 32-bit timer value

Function:	If **wait** is true, the current capture values in the result buffer are cleared, and the next result to be sent to the buffer is returned. If **wait** is false, the default setting, the first value currently in the buffer is returned. However, the buffer will only hold four results while waiting for them to be read, so if get_capture32 is not being called for every capture event. When **wait** is false, the buffer will fill with old capture values and any new results will be lost.
Availability:	Only devices with a 32-bit Input Capture module
Requires:	Nothing

Examples:	`setup_timer2(TMR_INTERNAL | TMR_DIV_BY_1 | TMR_32_BIT);`
	`setup_capture(1,CAPTURE_FE | CAPTURE_TIMER2 | CAPTURE_32_BIT);`
	`while(TRUE) {`
	`   timerValue=get_capture32(1,TRUE);`
	`   printf("Capture 1 occurred at: %LU", timerValue);`
	`}`

Example Files:	None
Also See:	setup_capture(), setup_compare(), get_capture(), Input Capture Overview

get_hspwm_capture( )

Syntax:	**result=get_hspwm_capture(**unit**);**
Parameters:	**unit** - The High Speed PWM unit to set.
Returns:	Unsigned in16 value representing the capture PWM time base value.
Function:	Gets the captured PWM time base value from the leading edge detection on the current-limit input.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None
Examples:	`result=get_hspwm_capture(1);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(),

	setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

get_nco_accumulator( )

Syntax:	**value =get_nco_accumulator( );**
Parameters:	none
Returns:	current value of accumulator.
Availability:	On devices with a NCO module.
Examples:	`value = get_nco_accumulator( );`
Example Files:	None
Also See:	setup_nco( ), set_nco_inc_value( ), get_nco_inc_value( )

get_nco_inc_value( )

Syntax:	**value =get_nco_inc_value( );**
Parameters:	None
Returns:	- current value set in increment registers.
Availability:	On devices with a NCO module.
Examples:	`value = get_nco_inc_value( );`
Example Files:	None
Also See:	setup_nco( ), set_nco_inc_value( ), get_nco_accumulator( )

get_ticks( )

Syntax:	**value = get_ticks**([stream]**);**
Parameters:	**stream –** optional parameter specifying the stream defined in #USE TIMER.
Returns:	– a 8, 16 or 32 bit integer. (int8, int16 or int32)
Function:	Returns the current tick value of the tick timer. The size returned depends on the size of the tick timer.
Availability:	All devices.
Requires:	#USE TIMER(options)

Examples:	`#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)`
	
	`void main(void) {`
	`   unsigned int16 current_tick;`
	
	`   current_tick = get_ticks();`
	`}`

Example Files:	None
Also See:	**#USE TIMER**, **set_ticks()**

get_timerA( )

Syntax:	**value=get_timerA();**
Parameters:	none
Returns:	The current value of the timer as an int8
Function:	Returns the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, …).
Availability:	This function is only available on devices with Timer A hardware.
Requires:	Nothing

Examples:	`set_timerA(0);`
	`while(timerA < 200);`

Example Files:	none
Also See:	set_timerA( ), setup_timer_A( ), TimerA Overview

get_timerB( )

Syntax:	**value=get_timerB();**
Parameters:	none
Returns:	The current value of the timer as an int8
Function:	Returns the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, …).
Availability:	This function is only available on devices with Timer B hardware.
Requires:	Nothing

Examples:	`set_timerB(0);`
	`while(timerB < 200);`

Example Files:	none
Also See:	set_timerB( ), setup_timer_B( ), TimerB Overview

get_timerx( )

Syntax:	**value=get_timer0() Same as: value=get_rtcc()** **value=get_timer1()** **value=get_timer2()** **value=get_timer3()** **value=get_timer4()** **value=get_timer5()** **value=get_timer6()** **value=get_timer7()** **value=get_timer8()** **value=get_timer10()** **value=get_timer12()**
Parameters:	None
Returns:	Timers 1, 3, 5 and 7 return a 16 bit int. Timers 2 ,4, 6, 8, 10 and 12 return an 8 bit int. Timer 0 (AKA RTCC) returns a 8 bit int except on the PIC18XXX where it returns a 16 bit int.
Function:	Returns the count value of a real time clock/counter. RTCC and Timer0 are the same. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2...).
Availability:	Timer 0 - All devices Timers 1 & 2 - Most but not all PCM devices

	Timer 3, 5 and 7 - Some PIC18 and Enhanced PIC16 devices Timer 4,6,8,10 and 12- Some PIC18 and Enhanced PIC16 devices
Requires:	Nothing

Examples:	`set_timer0(0);`
	`while ( get_timer0() < 200 ) ;`

Example Files:	ex_stwt.c
Also See:	set_timerx() , Timer0 Overview , Timer1 Overview , Timer2 Overview , Timer5 Overview

get_tris_x( )

Syntax:	**value = get_tris_A();**
	value = get_tris_B();
	value = get_tris_C();
	value = get_tris_D();
	value = get_tris_E();
	value = get_tris_F();
	value = get_tris_G();
	value = get_tris_H();
	value = get_tris_J();
	value = get_tris_K()

Parameters:	None
Returns:	int16, the value of TRIS register
Function:	Returns the value of the TRIS register of port A, B, C, D, E, F, G, H, J, or K.
Availability:	All devices.
Requires:	Nothing
Examples:	`tris_a = GET_TRIS_A();`
Example Files:	None
Also See:	input(), output_low(), output_high()

getenv( )

Syntax:	**value = getenv (*cstring*);**

Parameters:	cstring is a constant string with a recognized keyword
Returns:	A constant number, a constant string or 0
Function:	This function obtains information about the execution environment. The following are recognized keywords. This function returns a constant 0 if the keyword is not understood.

FUSE_SET:fffff	**Returns 1 if fuse fffff is enabled**
FUSE_VALID:fffff	Returns 1 if fuse fffff is valid
INT:iiiii	Returns 1 if the interrupt iiiii is valid
ID	Returns the device ID (set by #ID)
DEVICE	Returns the device name string (like "PIC16C74")
CLOCK	Returns the MPU FOSC
VERSION	Returns the compiler version as a float
VERSION_STRING	Returns the compiler version as a string
PROGRAM_MEMORY	Returns the size of memory for code (in words)
STACK	Returns the stack size
SCRATCH	Returns the start of the compiler scratch area
DATA_EEPROM	Returns the number of bytes of data EEPROM
EEPROM_ADDRESS	Returns the address of the start of EEPROM. 0 if not supported by the device.
READ_PROGRAM	Returns a 1 if the code memory can be read
ADC_CHANNELS	Returns the number of A/D channels
ADC_RESOLUTION	Returns the number of bits returned from READ_ADC()
ICD	Returns a 1 if this is being compiled for a ICD
SPI	Returns a 1 if the device has SPI
USB	Returns a 1 if the device has USB
CAN	Returns a 1 if the device has CAN
I2C_SLAVE	Returns a 1 if the device has I2C slave H/W
I2C_MASTER	Returns a 1 if the device has I2C master H/W

PSP	Returns a 1 if the device has PSP
COMP	Returns a 1 if the device has a comparator
VREF	Returns a 1 if the device has a voltage reference
LCD	Returns a 1 if the device has direct LCD H/W
UART	Returns the number of H/W UARTs
AUART	Returns 1 if the device has an ADV UART
CCPx	Returns a 1 if the device has CCP number x
TIMERx	Returns a 1 if the device has TIMER number x
FLASH_WRITE_SIZE	Smallest number of bytes that can be written to FLASH
FLASH_ERASE_SIZE	Smallest number of bytes that can be erased in FLASH
BYTES_PER_ADDRESS	Returns the number of bytes at an address location
BITS_PER_INSTRUCTION	Returns the size of an instruction in bits
RAM	Returns the number of RAM bytes available for your device.
SFR:name	Returns the address of the specified special file register. The output format can be used with the preprocessor command #bit. name must match SFR denomination of your target PIC (example: STATUS, INTCON, TXREG, RCREG, etc)
BIT:name	Returns the bit address of the specified special file register bit. The output format will be in “address:bit”, which can be used with the preprocessor command #byte. name must match SFR.bit denomination of your target PIC (example: C, Z, GIE, TMR0IF, etc)
SFR_VALID:name	Returns TRUE if the specified special file register name is valid and exists for your target PIC (example: getenv("SFR_VALID:INTCON"))

BIT_VALID:name	Returns TRUE if the specified special file register bit is valid and exists for your target PIC (example: getenv("BIT_VALID:TMR0IF"))
PIN:PB	Returns 1 if PB is a valid I/O PIN (like A2)
UARTx_RX	Returns UARTxPin (like PINxC7)
UARTx_TX	Returns UARTxPin (like PINxC6)
SPIx_DI	Returns SPIxDI Pin
SPIxDO	Returns SPIxDO Pin
SPIxCLK	Returns SPIxCLK Pin
ETHERNET	Returns 1 if device supports Ethernet
QEI	Returns 1 if device has QEI
DAC	Returns 1 if device has a D/A Converter
DSP	Returns 1 if device supports DSP instructions
DCI	Returns 1 if device has a DCI module
DMA	Returns 1 if device supports DMA
CRC	Returns 1 if device has a CRC module
CWG	Returns 1 if device has a CWG module
NCO	Returns 1 if device has a NCO module
CLC	Returns 1 if device has a CLC module
DSM	Returns 1 if device has a DSM module
OPAMP	Returns 1 if device has op amps
RTC	Returns 1 if device has a Real Time Clock
CAP_SENSE	Returns 1 if device has a CSM cap sense module and 2 if it has a CTMU module
EXTERNAL_MEMORY	Returns 1 if device supports external program memory
INSTRUCTION_CLOCK	Returns the MPU instruction clock
ENH16	Returns 1 for Enhanced 16 devices

Availability: All devices

Requires:	Nothing

Examples:	`#IF  getenv("VERSION")<3.050`
	`   #ERROR  Compiler version too old`
	`#ENDIF`
	
	`for(i=0;i<getenv("DATA_EEPROM");i++)`
	`   write_eeprom(i,0);`
	
	`#IF getenv("FUSE_VALID:BROWNOUT")`
	`   #FUSE BROWNOUT`
	`#ENDIF`
	
	`#byte status_reg=GETENV("SFR:STATUS")`
	
	`#bit carry_flag=GETENV("BIT:C")`

Example Files:	None
Also See:	None

goto_address( )

Syntax:	**goto_address(***location***);**
Parameters:	location is a ROM address, 16 or 32 bit int.
Returns:	Nothing
Function:	This function jumps to the address specified by location. Jumps outside of the current function should be done only with great caution. This is not a normally used function except in very special situations.
Availability:	All devices
Requires:	Nothing

Examples:	`#define LOAD_REQUEST PIN_B1`
	`#define LOADER 0x1f00`
	
	`if(input(LOAD_REQUEST))`
	`   goto_address(LOADER);`

Example Files:	setjmp.h

Also See:	label_address( )

high_speed_adc_done( )

Syntax:	**value = high_speed_adc_done([*pair*]);**
Parameters:	**pair** – Optional parameter that determines which ADC pair's ready flag to check. If not used all ready flags are checked.
Returns:	An int16. If pair is used 1 will be return if ADC is done with conversion, 0 will be return if still busy. If pair isn't use it will return a bit map of which conversion are ready to be read. For example a return value of 0x0041 means that ADC pair 6, AN12 and AN13, and ADC pair 0, AN0 and AN1, are ready to be read.
Function:	Can be polled to determine if the ADC has valid data to be read.
Availability:	Only on dsPIC33FJxxGSxxx devices.
Requires:	None

Examples:	`int16 result[2]`
	`setup_high_speed_adc_pair(1,  INDIVIDUAL_SOFTWARE_TRIGGER);`
	`setup_high_speed_adc( ADC_CLOCK_DIV_4);`
	
	`read_high_speed_adc(1, ADC_START_ONLY);`
	`while(!high_speed_adc_done(1));`
	`read_high_speed_adc(1, ADC_READ_ONLY, result);`
	`printf("AN2 value = %LX, AN3 value = %LX\n\r",result[0],result[1]);`

Example Files:	None
Also See:	setup_high_speed_adc(), setup_high_speed_adc_pair(), read_high_speed_adc()

i2c_init( )

Syntax:	**i2c_init([stream],baud);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE I2C. baud – if baud is 0, I2C peripheral will be disable. If baud is 1, I2C peripheral is initialized and enabled with baud rate specified in #USE I2C directive. If baud is > 1 then I2C peripheral is initialized and enabled to specified baud rate.

Returns:	Nothing
Function:	To initialize I2C peripheral at run time to specified baud rate.
Availability:	All devices.
Requires:	#USE I2C

Examples:	#USE I2C(MASTER,I2C1, FAST,NOINIT)
	i2c_init(TRUE); //initialize and enable I2C peripheral to baud rate specified in //#USE I2C
	i2c_init(500000); //initialize and enable I2C peripheral to a baud rate of 500 //KBPS

Example Files:	None
Also See:	I2C_POLL( ), i2c_speed( ), I2C_SlaveAddr( ), I2C_ISR_STATE( ) ,I2C_WRITE( ), I2C_READ( ), _USE_I2C( ), I2C( )

i2c_isr_state( )

Syntax:	**state = i2c_isr_state();**
	state = i2c_isr_state(stream**);**

Parameters:	None
Returns:	state is an 8 bit int 0 - Address match received with R/W bit clear, perform i2c_read( ) to read the I2C address. 1-0x7F - Master has written data; i2c_read() will immediately return the data 0x80 - Address match received with R/W bit set; perform i2c_read( ) to read the I2C address, and use i2c_write( ) to pre-load the transmit buffer for the next transaction (next I2C read performed by master will read this byte). 0x81-0xFF - Transmission completed and acknowledged; respond with i2c_write() to pre-load the transmit buffer for the next transation (the next I2C read performed by master will read this byte).
Function:	Returns the state of I2C communications in I2C slave mode after an SSP interrupt. The return value increments with each byte received or sent. If 0x00 or 0x80 is returned, an i2C_read( ) needs to be performed to read the I2C address that was sent (it will match the address configured by #USE I2C so this value can be ignored)
Availability:	Devices with i2c hardware
Requires:	#USE I2C
Examples:	see below

```
#INT_SSP
   void i2c_isr() {
      state = i2c_isr_state();
      if(state== 0 ) i2c_read();
        i@c_read();
      if(state == 0x80)
       i2c_read(2);
      if(state >= 0x80)
         i2c_write(send_buffer[state - 0x80]);
      else if(state > 0)
         rcv_buffer[state - 1] = i2c_read();
}
```

Example Files:	ex_slave.c
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_poll( )

Syntax:	**i2c_poll()**
	i2c_poll(stream**)**

Parameters:	**stream** (optional)- specify the stream defined in #USE I2C
Returns:	1 (TRUE) or 0 (FALSE)
Function:	The I2C_POLL() function should only be used when the built-in SSP is used. This function returns TRUE if the hardware has a received byte in the buffer. When a TRUE is returned, a call to I2C_READ() will immediately return the byte that was received.
Availability:	Devices with built in I2C
Requires:	#USE I2C

Examples:	`if(i2c-poll())`
	`buffer [index]=i2c-read();//read data`

Example Files:	None
Also See:	i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_read( )

Syntax:	**data = i2c_read();**
	data = i2c_read(ack);
	data = i2c_read(stream, ack);

Parameters:	***ack*** -Optional, defaults to 1. 0 indicates do not ack. 1 indicates to ack. 2 slave only, indicates to not release clock at end of read. Use when i2c_isr_state () returns 0x80. **stream** - specify the stream defined in #USE I2C
Returns:	data - 8 bit int

Function:	Reads a byte over the I2C interface. In master mode this function will generate the clock and in slave mode it will wait for the clock. There is no timeout for the slave, use i2c_poll() to prevent a lockup. Use restart_wdt() in the #USE I2C to strobe the watch-dog timer in the slave mode while waiting.
Availability:	All devices.
Requires:	#USE I2C

Examples:	`i2c_start();`
	`i2c_write(0xa1);`
	`data1 = i2c_read(TRUE);`
	`data2 = i2c_read(FALSE);`
	`i2c_stop();`

Example Files:	ex_extee.c with 2416.c
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, #USE I2C, I2C Overview

i2c_slaveaddr( )

Syntax:	**I2C_SlaveAddr(**addr**);**
	I2C_SlaveAddr(stream, addr**);**

Parameters:	**addr** = 8 bit device address **stream**(optional) - specifies the stream used in #USE I2C
Returns:	Nothing
Function:	This functions sets the address for the I2C interface in slave mode.
Availability:	Devices with built in I2C
Requires:	#USE I2C

Examples:	`i2c_SlaveAddr(0x08);`
	`i2c_SlaveAddr(i2cStream1, 0x08);`

Example Files:	ex_slave.c
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_speed( )

Syntax:	**i2c_speed (***baud***)** **i2c_speed** (stream**,** *baud***)**
Parameters:	**baud** is the number of bits per second. **stream** - specify the stream defined in #USE I2C
Returns:	Nothing.
Function:	This function changes the I2c bit rate at run time. This only works if the hardware I2C module is being used.
Availability:	All devices.
Requires:	#USE I2C
Examples:	`I2C_Speed (400000);`
Example Files:	none
Also See:	i2c_poll, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_start( )

Syntax:	**i2c_start()**
	i2c_start(stream**)**
	i2c_start(stream**, restart)**

Parameters:	**stream: specify the stream defined in #USE I2C** **restart**: 2 – new restart is forced instead of start 1 – normal start is performed 0 (or not specified) – restart is done only if the compiler last encountered a I2C_START and no I2C_STOP
Returns:	undefined
Function:	Issues a start condition when in the I2C master mode. After the start condition the clock is held low until I2C_WRITE() is called. If another I2C_start is called in the same function before an i2c_stop is called, then a special restart condition is issued. Note that specific I2C protocol depends on the slave device. The I2C_START function will now accept an optional parameter. If 1 the compiler assumes the bus is in the stopped state. If 2 the compiler treats this I2C_START as a restart. If no parameter is passed a 2 is used only if the compiler compiled a I2C_START last with no I2C_STOP since.
Availability:	All devices.

Requires:	#USE I2C

Examples:	`i2c_start();`
	`i2c_write(0xa0);      // Device address`
	`i2c_write(address);   // Data to device`
	`i2c_start();          // Restart`
	`i2c_write(0xa1);      // to change data direction`
	`data=i2c_read(0);     // Now read from slave`
	`i2c_stop();`

Example Files:	ex_extee.c with 2416.c
Also See:	i2c_poll, i2c_speed, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_stop( )

Syntax:	**i2c_stop()**
	i2c_stop(stream)

Parameters:	stream: (optional) specify stream defined in #USE I2C
Returns:	undefined
Function:	Issues a stop condition when in the I2C master mode.
Availability:	All devices.
Requires:	#USE I2C

Examples:	`i2c_start();     // Start condition`
	`i2c_write(0xa0); // Device address`
	`i2c_write(5);    // Device command`
	`i2c_write(12);   // Device data`
	`i2c_stop();      // Stop condition`

Example Files:	ex_extee.c with 2416.c
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_slaveaddr, i2c_isr_state, i2c_write, i2c_read, #USE I2C, I2C Overview

i2c_write( )

Syntax:	**i2c_write (*data*)**

	i2c_write (stream, *data*)
Parameters:	***data*** is an 8 bit int **stream** - specify the stream defined in #USE I2C
Returns:	This function returns the ACK Bit. 0 means ACK, 1 means NO ACK, 2 means there was a collision if in Multi_Master Mode. This does not return an ACK if using i2c in slave mode.
Function:	Sends a single byte over the I2C interface. In master mode this function will generate a clock with the data and in slave mode it will wait for the clock from the master. No automatic timeout is provided in this function. This function returns the ACK bit. The LSB of the first write after a start determines the direction of data transfer (0 is master to slave). Note that specific I2C protocol depends on the slave device.
Availability:	All devices.
Requires:	#USE I2C

Examples:	`long cmd;`
	`   ...`
	`i2c_start();    // Start condition`
	`i2c_write(0xa0);// Device address`
	`i2c_write(cmd);// Low byte of command`
	`i2c_write(cmd>>8);// High byte of command`
	`i2c_stop();     // Stop condition`

Example Files:	ex_extee.c with 2416.c
Also See:	i2c_poll, i2c_speed, i2c_start, i2c_stop, i2c_slaveaddr, i2c_isr_state, i2c_read, #USE I2C, I2C Overview

input( )

Syntax:	**value = input (*pin*)**
Parameters:	***Pin*** to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #define PIN_A3 43 . The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. note that doing I/O with a variable instead of a constant will take much longer time.
Returns:	0 (or FALSE) if the pin is low, 1 (or TRUE) if the pin is high
Function:	This function returns the state of the indicated pin. The method of I/O is dependent on the last USE *_IO directive. By default with standard I/O before the input is done the data direction is set to input.

Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file

Examples:	`while ( !input(PIN_B1) );`
	`// waits for B1 to go high`
	
	`if( input(PIN_A0) )`
	`   printf("A0 is now high\r\n");`
	
	`int16 i=PIN_B1;`
	`while(!i);`
	`//waits for B1 to go high`

Example Files:	ex_pulse.c
Also See:	input_x(), output_low(), output_high(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

input_change_x( )

Syntax:	**value = input_change_a( );**
	value = input_change_b( );
	value = input_change_c( );
	value = input_change_d( );
	value = input_change_e( );
	value = input_change_f( );
	value = input_change_g( );
	value = input_change_h( );
	value = input_change_j( );
	value = input_change_k( );

Parameters:	None
Returns:	An 8-bit or 16-bit int representing the changes on the port.
Function:	This function reads the level of the pins on the port and compares them to the results the last time the input_change_x( ) function was called. A 1 is returned if the value has changed, 0 if the value is unchanged.
Availability:	All devices.
Requires:	None
Examples:	`pin_check = input_change_b( );`
Example Files:	None
Also See:	input( ), input_x( ), output_x( ), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

input_state( )

Syntax:	**value = input_state(*pin*)**
Parameters:	***pin*** to read. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #define PIN_A3 43 .
Returns:	Bit specifying whether pin is high or low. A 1 indicates the pin is high and a 0 indicates it is low.
Function:	This function reads the level of a pin without changing the direction of the pin as INPUT() does.
Availability:	All devices.
Requires:	Nothing

Examples:	`level = input_state(pin_A3);`
	`printf("level: %d",level);`

Example Files:	None
Also See:	input(), set_tris_x(), output_low(), output_high(), General Purpose I/O

input_x( )

Syntax:	**value = input_a()** **value = input_b()** **value = input_c()** **value = input_d()** **value = input_e()** **value = input_f()** **value = input_g()** **value = input_h()** **value = input_j()** **value = input_k()**
Parameters:	None
Returns:	An 8 bit int representing the port input data.
Function:	Inputs an entire byte from a port. The direction register is changed in accordance with the last specified #USE *_IO directive. By default with standard I/O before the input is done the data direction is set to input.

Availability:	All devices.
Requires:	Nothing
Examples:	`data = input_b();`
Example Files:	ex_psp.c
Also See:	input(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO

interrupt_active( )

Syntax:	**interrupt_active (**interrupt**)**
Parameters:	**Interrupt** – constant specifying the interrupt
Returns:	Boolean value
Function:	The function checks the interrupt flag of the specified interrupt and returns true in case the flag is set.
Availability:	Device with interrupts
Requires:	Should have a #INT_xxxx, Constants are defined in the devices .h file.

Examples:	`interrupt_active(INT_TIMER0);`
	`interrupt_active(INT_TIMER1);`

Example Files:	None
Also See:	disable_interrupts() , #INT , Interrupts Overview clear_interrupt, enable_interrupts()

isalnum(char) isalpha(char) iscntrl(x) isdigit(char) isgraph(x) islower(char) isspace(char) isupper(char) isxdigit(char) isprint(x) ispunct(x)

Syntax:	**value = isalnum(***datac***)** **value = isalpha(***datac***)** **value = isdigit(***datac***)** **value = islower(***datac***)** **value = isspace(***datac***)** **value = isupper(***datac***)**

	value = isxdigit(*datac*) **value = iscntrl(*datac*)** **value = isgraph(*datac*)** **value = isprint(*datac*)** **value = punct(*datac*)**
Parameters:	***datac*** is a 8 bit character
Returns:	0 (or FALSE) if datac dose not match the criteria, 1 (or TRUE) if datac does match the criteria.
Function:	Tests a character to see if it meets specific criteria as follows:

isalnum(x)	**X is 0..9, 'A'..'Z', or 'a'..'z'**
isalpha(x)	X is 'A'..'Z' or 'a'..'z
isdigit(x)	X is '0'..'9'
islower(x)	X is 'a'..'z'
isupper(x)	X is 'A'..'Z
isspace(x)	X is a space
isxdigit(x)	X is '0'..'9', 'A'..'F', or 'a'..'f
iscntrl(x)	X is less than a space
isgraph(x)	X is greater than a space
isprint(x)	X is greater than or equal to a space
ispunct(x)	X is greater than a space and not a letter or number

Availability: All devices.

Requires: #INCLUDE <ctype.h>

Examples:

```
char id[20];
   ...
if(isalpha(id[0])) {
   valid_id=TRUE;
   for(i=1;i<strlen(id);i++)
    valid_id=valid_id && isalnum(id[i]);
} else
   valid_id=FALSE;
```

Example Files: ex_str.c

Also See: isamong()

isamong( )

Syntax:	**result = isamong (*value, cstring*)**
Parameters:	***value*** is a character ***cstring*** is a constant sting
Returns:	0 (or FALSE) if value is not in cstring 1 (or TRUE) if value is in cstring

Function:	Returns TRUE if a character is one of the characters in a constant string.
Availability:	All devices
Requires:	Nothing

Examples:	`char x= 'x';`
	`...`
	`if ( isamong ( x,`
	`     "0123456789ABCDEFGHIJKLMNOPQRSTUVWXYZ") )`
	`    printf ("The character is valid");`

Example Files:	#INCLUDE <ctype.h>
Also See:	isalnum( ), isalpha( ), isdigit( ), isspace( ), islower( ), isupper( ), isxdigit( )

itoa( )

Syntax:	string **= itoa(**i32value**,** i8base, string**)**
Parameters:	**i32value** is a 32 bit int **i8base** is a 8 bit int **string** is a pointer to a null terminated string of characters
Returns:	**string** is a pointer to a null terminated string of characters
Function:	Converts the signed int32 to a string according to the provided base and returns the converted value if any. If the result cannot be represented, the function will return 0.
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>

Examples:	`int32 x=1234;`
	`char string[5];`
	
	`itoa(x,10, string);`
	`// string is now "1234"`

Example Files:	None
Also See:	None

jump_to_isr( )

Syntax:	**jump_to_isr (*address*)**
Parameters:	***address*** is a valid program memory address
Returns:	No value
Function:	The jump_to_isr function is used when the location of the interrupt service routines are not at the default location in program memory. When an interrupt occurs, program execution will jump to the default location and then jump to the specified address.
Availability:	All devices
Requires:	Nothing

Examples:	`int_global`
	`void global_isr(void) {`
	`        jump_to_isr(isr_address);`
	`}`

Example Files:	ex_bootloader.c
Also See:	#BUILD

kbhit( )

Syntax:	**value = kbhit()** **value = kbhit (*stream*)**
Parameters:	***stream*** is the stream id assigned to an available RS232 port. If the stream parameter is not included, the function uses the primary stream used by getc().
Returns:	0 (or FALSE) if getc() will need to wait for a character to come in, 1 (or TRUE) if a character is ready for getc()
Function:	If the RS232 is under software control this function returns TRUE if the start bit of a character is being sent on the RS232 RCV pin. If the RS232 is hardware this function returns TRUE if a character has been received and is waiting in the hardware buffer for getc() to read. This function may be used to poll for data without stopping and waiting for the data to appear. Note that in the case of software RS232 this function should be called at least 10 times the bit rate to ensure incoming data is not lost.
Availability:	All devices.
Requires:	#USE RS232
Examples:	`char timed_getc() {`

```
   long timeout;

   timeout_error=FALSE;
   timeout=0;
   while(!kbhit()&&(++timeout<50000)) // 1/2
                                      // second
          delay_us(10);
   if(kbhit())
          return(getc());
   else {
          timeout_error=TRUE;
          return(0);
   }
}
```

Example Files:	ex_tgetc.c
Also See:	getc(), #USE RS232, RS232 I/O Overview

label_address( )

Syntax:	**value = label_address(*label*);**
Parameters:	***label*** is a C label anywhere in the function
Returns:	A 16 bit int in PCB,PCM and a 32 bit int for PCH, PCD
Function:	This function obtains the address in ROM of the next instruction after the label. This is not a normally used function except in very special situations.
Availability:	All devices.
Requires:	Nothing
Examples:	see below

```
start:
   a = (b+c)<<2;
end:
   printf("It takes %lu ROM locations.\r\n",
   label_address(end)-label_address(start));
```

Example Files:	setjmp.h
Also See:	goto_address()

labs( )

Syntax:	**result = labs (*value*)**
Parameters:	***value*** is a 16 bit signed long int
Returns:	A 16 bit signed long int
Function:	Computes the absolute value of a long integer.
Availability:	All devices.
Requires:	#INCLUDE <stdlib.h>

Examples:	`if(labs( target_value - actual_value ) > 500)`
	`   printf("Error is over 500 points\r\n");`

Example Files:	None
Also See:	abs()

lcd_contrast( )

Syntax:	**lcd_contrast (*contrast*)**
Parameters:	***contrast*** is used to set the internal contrast control resistance ladder.
Returns:	undefined.
Function:	This function controls the contrast of the LCD segments with a value passed in between 0 and 7. A value of 0 will produce the minimum contrast, 7 will produce the maximum contrast.
Availability:	Only on select devices with built-in LCD Driver Module hardware.
Requires:	None.

Examples:	`lcd_contrast( 0 );     // Minimum Contrast`
	`lcd_contrast( 7 );     // Maximum Contrast`

Example Files:	None.
Also See:	lcd_load( ), lcd_symbol( ), setup_lcd( ), Internal LCD Overview

lcd_load( )

Syntax:	**lcd_load (***buffer_pointer***,** *offset***,** *length***);**
Parameters:	***buffer_pointer*** points to the user data to send to the LCD, ***offset*** is the offset into the LCD segment memory to write the data, ***length*** is the number of bytes to transfer to the LCD segment memory.
Returns:	undefined.
Function:	This function will load ***length*** bytes from ***buffer_pointer*** into the LCD segment memory beginning at ***offset***. The lcd_symbol( ) function provides as easier way to write data to the segment memory.
Availability:	Only on devices with built-in LCD Driver Module hardware.
Requires	Constants are defined in the devices *.*h* file.
Examples:	`lcd_load(buffer, 0, 16);`
Example Files:	ex_92lcd.c
Also See:	lcd_symbol(), setup_lcd(), lcd_contrast( ), Internal LCD Overview

lcd_symbol( )

Syntax:	**lcd_symbol (***symbol, bX_addr***);**
Parameters:	***symbol*** is a 8 bit or 16 bit constant. ***bX_addr*** is a bit address representing the segment location to be used for bit X of the specified symbol. 1-16 segments could be specified.
Returns:	undefined
Function:	This function loads the bits for the symbol into the segment data registers for the LCD with each bit address specified. If bit X in symbol is set, the segment at bX_addr is set, otherwise it is cleared. The bX_addr is a bit address into the LCD RAM.
Availability:	Only on devices with built-in LCD Driver Module hardware.
Requires	Constants are defined in the devices *.h file.

Examples:	`byte CONST DIGIT_MAP[10] = {0xFC, 0x60, 0xDA, 0xF2, 0x66, 0xB6, 0xBE, 0xE0, 0xFE, 0xE6};`
	
	`#define DIGIT1   COM1+20, COM1+18, COM2+18, COM3+20, COM2+28, COM1+28, COM2+20, COM3+18`

	`for(i = 0; i <= 9; i++) {`
	`     lcd_symbol( DIGIT_MAP[i], DIGIT1 );`
	`     delay_ms( 1000 );`
	`}`

Example Files:	ex_92lcd.c
Also See:	setup_lcd(), lcd_load(), lcd_contrast( ), Internal LCD Overview

ldexp( )

Syntax:	**result= ldexp (*value*, *exp*);**
Parameters:	***value*** is float ***exp*** is a signed int.
Returns:	result is a float with value result times 2 raised to power exp.
Function:	The ldexp function multiplies a floating-point number by an integral power of 2.
Availability:	All devices.
Requires:	#INCLUDE <math.h>

Examples:	`float result;`
	`result=ldexp(.5,0);`
	`// result is .5`

Example Files:	None
Also See:	frexp(), exp(), log(), log10(), modf()

log( )

Syntax:	**result = log (*value*)**
Parameters:	***value*** is a float
Returns:	A float
Function:	Computes the natural logarithm of the float x. If the argument is less than or equal to zero or too large, the behavior is undefined.

	Note on error handling: "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function. Domain error occurs in the following cases: • log: when the argument is negative
Availability:	All devices
Requires:	#INCLUDE <math.h>
Examples:	lnx = log(x);
Example Files:	None
Also See:	log10(), exp(), pow()

log10( )

Syntax:	**result = log10 (*value*)**
Parameters:	***value*** is a float
Returns:	A float
Function:	Computes the base-ten logarithm of the float x. If the argument is less than or equal to zero or too large, the behavior is undefined. Note on error handling: If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function. Domain error occurs in the following cases: • log10: when the argument is negative
Availability:	All devices
Requires:	#INCLUDE <math.h>
Examples:	`db = log10( read_adc()*(5.0/255) )*10;`
Example Files:	None
Also See:	log(), exp(), pow()

longjmp( )

Syntax:	**longjmp (***env, val***)**
Parameters:	***env***: The data object that will be restored by this function ***val***: The value that the function setjmp will return. If val is 0 then the function setjmp will return 1 instead.
Returns:	After longjmp is completed, program execution continues as if the corresponding invocation of the setjmp function had just returned the value specified by val.
Function:	Performs the non-local transfer of control.
Availability:	All devices
Requires:	#INCLUDE <setjmp.h>
Examples:	`longjmp(jmpbuf, 1);`
Example Files:	None
Also See:	setjmp()

make8( )

Syntax:	**i8 = MAKE8(***var***,** *offset***)**
Parameters:	***var*** is a 16 or 32 bit integer. ***offset*** is a byte offset of 0,1,2 or 3.
Returns:	An 8 bit integer
Function:	Extracts the byte at offset from var. Same as: i8 = (((var >> (offset*8)) & 0xff) except it is done with a single byte move.
Availability:	All devices
Requires:	Nothing

Examples:	`int32 x;`
	`int y;`
	
	`y = make8(x,3);  // Gets MSB of x`

Example Files:	None
Also See:	make16(), make32()

make16( )

Syntax:	**i16 = MAKE16(*varhigh*, *varlow*)**
Parameters:	***varhigh*** and ***varlow*** are 8 bit integers.
Returns:	A 16 bit integer
Function:	Makes a 16 bit number out of two 8 bit numbers. If either parameter is 16 or 32 bits only the lsb is used. Same as: i16 = (int16)(varhigh&0xff)*0x100+(varlow&0xff) except it is done with two byte moves.
Availability:	All devices
Requires:	Nothing

Examples:	`long x;`
	`int hi,lo;`
	
	`x = make16(hi,lo);`

Example Files:	ltc1298.c
Also See:	make8(), make32()

make32( )

Syntax:	**i32 = MAKE32(*var1*, *var2*, *var3*, *var4*)**
Parameters:	***var1-4*** are a 8 or 16 bit integers. ***var2-4*** are optional.
Returns:	A 32 bit integer
Function:	Makes a 32 bit number out of any combination of 8 and 16 bit numbers. Note that the number of parameters may be 1 to 4. The msb is first. If the total bits provided is less than 32 then zeros are added at the msb.
Availability:	All devices
Requires:	Nothing

Examples:	`int32 x;`
	`int y;`
	`long z;`
	
	`x = make32(1,2,3,4);  // x is 0x01020304`
	
	`y=0x12;`
	`z=0x4321;`
	
	`x = make32(y,z);  // x is 0x00124321`
	
	`x = make32(y,y,z);  // x is 0x12124321`

Example Files:	ex_freqc.c
Also See:	make8(), make16()

malloc( )

Syntax:	**ptr=malloc(*size*)**
Parameters:	***size*** is an integer representing the number of byes to be allocated.
Returns:	A pointer to the allocated memory, if any. Returns null otherwise.
Function:	The malloc function allocates space for an object whose size is specified by size and whose value is indeterminate.
Availability:	All devices
Requires:	#INCLUDE <stdlibm.h>

Examples:	`int * iptr;`
	`iptr=malloc(10);`
	`// iptr will point to a block of memory of 10 bytes.`

Example Files:	None
Also See:	realloc(), free(), calloc()

memcpy( )   memmove( )

Syntax:	**memcpy (*destination*, *source*, *n*)** **memmove(*destination*, *source*, *n*)**

Parameters:	***destination*** is a pointer to the destination memory. ***source*** is a pointer to the source memory,. ***n*** is the number of bytes to transfer
Returns:	undefined
Function:	Copies n bytes from source to destination in RAM. Be aware that array names are pointers where other variable names and structure names are not (and therefore need a & before them). Memmove performs a safe copy (overlapping objects doesn't cause a problem). Copying takes place as if the n characters from the source are first copied into a temporary array of n characters that doesn't overlap the destination and source objects. Then the n characters from the temporary array are copied to destination.
Availability:	All devices
Requires:	Nothing

Examples:	`memcpy(&structA, &structB, sizeof (structA));`
	`memcpy(arrayA,arrayB,sizeof (arrayA));`
	`memcpy(&structA, &databyte, 1);`
	
	`char a[20]="hello";`
	`memmove(a,a+2,5);`
	`// a is now "llo"`

Example Files:	None
Also See:	strcpy(), memset()

memset( )

Syntax:	**memset (***destination***,** *value***,** *n***)**
Parameters:	***destination*** is a pointer to memory. ***value*** is a 8 bit int ***n*** is a 16 bit int. On PCB and PCM parts n can only be 1-255.
Returns:	undefined
Function:	Sets n number of bytes, starting at destination, to value. Be aware that array names are pointers where other variable names and structure names are not (and therefore need a & before them).

Availability:	All devices
Requires:	Nothing

Examples:	`memset(arrayA, 0, sizeof(arrayA));`
	`memset(arrayB, '?', sizeof(arrayB));`
	`memset(&structA, 0xFF, sizeof(structA));`

Example Files:	None
Also See:	memcpy()

modf( )

Syntax:	**result= modf (*value*, & *integral*)**
Parameters:	***value*** is a float ***integral*** is a float
Returns:	result is a float
Function:	The modf function breaks the argument value into integral and fractional parts, each of which has the same sign as the argument. It stores the integral part as a float in the object integral.
Availability:	All devices
Requires:	#INCLUDE <math.h>

Examples:	`float result, integral;`
	`result=modf(123.987,&integral);`
	`// result is .987 and integral is 123.0000`

Example Files:	None
Also See:	None

_mul( )

Syntax:	**prod=_mul(*val1, val2*);**
Parameters:	***val1*** and ***val2*** are both 8-bit or 16-bit integers
Returns:	A 16-bit integer if both parameters are 8-bit integers, or a 32-bit integer if both parameters

	are 16-bit integers.
Function:	Performs an optimized multiplication. By accepting a different type than it returns, this function avoids the overhead of converting the parameters to a larger type.
Availability:	All devices
Requires:	Nothing

Examples:	`int a=50, b=100;`
	`long int c;`
	`c = _mul(a, b);      //c holds 5000`

Example Files:	None
Also See:	None

nargs( )

Syntax:	**void foo(char *** str, **int** count, **...)**
Parameters:	The function can take variable parameters. The user can use stdarg library to create functions that take variable parameters.
Returns:	Function dependent.
Function:	The stdarg library allows the user to create functions that supports variable arguments. The function that will accept a variable number of arguments must have at least one actual, known parameters, and it may have more. The number of arguments is often passed to the function in one of its actual parameters. If the variable-length argument list can involve more that one type, the type information is generally passed as well. Before processing can begin, the function creates a special argument pointer of type va_list.
Availability:	All devices
Requires:	#INCLUDE <stdarg.h>
Examples:	see below

```
int foo(int num, ...)
{
 int sum = 0;
 int i;
 va_list argptr;  // create special argument pointer
 va_start(argptr,num);  // initialize argptr
 for(i=0; i<num; i++)
   sum = sum + va_arg(argptr, int);
 va_end(argptr);  // end variable processing
 return sum;
}

 void main()
{
 int total;
 total = foo(2,4,6,9,10,2);
}
```

Example Files:	None
Also See:	va_start( ) , va_end( ) , va_arg( )

offsetof( ) offsetofbit( )

Syntax:

value = offsetof(*stype*, *field*);
value = offsetofbit(*stype*, *field*);

Parameters:

stype is a structure type name.
Field is a field from the above structure

Returns: An 8 bit byte

Function: These functions return an offset into a structure for the indicated field.
offsetof returns the offset in bytes and offsetofbit returns the offset in bits.

Availability: All devices

Requires: #INCLUDE <stddef.h>

Examples:

```
struct  time_structure {
          int hour, min, sec;
          int zone : 4;
          intl daylight_savings;
}

x = offsetof(time_structure, sec);
          // x will be 2
x = offsetofbit(time_structure, sec);
          // x will be 16
x = offsetof (time_structure,
              daylight_savings);
          // x will be 3
x = offsetofbit(time_structure,
                daylight_savings);
          // x will be 28
```

Example Files: None

Also See:	None

output_x( )

Syntax:	**output_a (*value*)** **output_b (*value*)** **output_c (*value*)** **output_d (*value*)** **output_e (*value*)** **output_f (*value*)** **output_g (*value*)** **output_h (*value*)** **output_j (*value*)** **output_k (*value*)**
Parameters:	***value*** is a 8 bit int
Returns:	undefined
Function:	Output an entire byte to a port. The direction register is changed in accordance with the last specified #USE *_IO directive.
Availability:	All devices, however not all devices have all ports (A-E)
Requires:	Nothing
Examples:	`OUTPUT_B(0xf0);`
Example Files:	ex_patg.c
Also See:	input(), output_low(), output_high(), output_float(), output_bit(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_bit( )

Syntax:	**output_bit (*pin*, *value*)**
Parameters:	***Pins*** are defined in the devices .h file. The actual number is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #define PIN_A3 43 . The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time. ***Value*** is a 1 or a 0.
Returns:	undefined

Function:	Outputs the specified value (0 or 1) to the specified I/O pin. The method of setting the direction register is determined by the last #USE *_IO directive.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file

Examples:	`output_bit( PIN_B0, 0);`
	`// Same as output_low(pin_B0);`
	
	`output_bit( PIN_B0,input( PIN_B1 ) );`
	`// Make pin B0 the same as B1`
	
	`output_bit( PIN_B0,shift_left(&data,1,input(PIN_B1)));`
	`// Output the MSB of data to`
	`// B0 and at the same time`
	`// shift B1 into the LSB of data`
	
	`int16 i=PIN_B0;`
	`ouput_bit(i,shift_left(&data,1,input(PIN_B1)));`
	`//same as above example, but`
	`//uses a variable instead of a constant`

Example Files:	ex_extee.c with 9356.c
Also See:	input(), output_low(), output_high(), output_float(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_drive( )

Syntax:	**output_drive(pin)**
Parameters:	***Pins*** are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #DEFINE PIN_A3 43 .
Returns:	undefined
Function:	Sets the specified pin to the output mode.
Availability:	All devices.
Requires:	Pin constants are defined in the devices.h file.

Examples:	`output_drive(pin_A0);  // sets pin_A0 to output its value`
	`output_bit(pin_B0, input(pin_A0))  // makes B0 the same as A0`

Example Files:	None
Also See:	input(), output_low(), output_high(), output_bit(), output_x(), output_float()

.

output_float( )

Syntax:	**output_float (*pin*)**
Parameters:	***Pins*** are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #DEFINE PIN_A3 43 . The PIN could also be a variable to identify the pin. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. Note that doing I/O with a variable instead of a constant will take much longer time.
Returns:	undefined
Function:	Sets the specified pin to the input mode. This will allow the pin to float high to represent a high on an open collector type of connection.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file

Examples:	`if( (data & 0x80)==0 )`
	`   output_low(pin_A0);`
	`else`
	`   output_float(pin_A0);`

Example Files:	None
Also See:	input(), output_low(), output_high(), output_bit(), output_x(), output_drive(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_high( )

Syntax:	**output_high (*pin*)**
Parameters:	***Pin*** to write to. Pins are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #DEFINE PIN_A3 43 . The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.

Returns:	undefined
Function:	Sets a given pin to the high state. The method of I/O used is dependent on the last USE *_IO directive.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file

Examples:	`output_high(PIN_A0);`
	
	`Int16 i=PIN_A1;`
	`output_low(PIN_A1);`

Example Files:	ex_sqw.c
Also See:	input(), output_low(), output_float(), output_bit(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_low( )

Syntax:	**output_low (*pin*)**
Parameters:	***Pins*** are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #DEFINE PIN_A3 43 . The PIN could also be a variable. The variable must have a value equal to one of the constants (like PIN_A1) to work properly. The tristate register is updated unless the FAST_IO mode is set on port A. Note that doing I/O with a variable instead of a constant will take much longer time.
Returns:	undefined
Function:	Sets a given pin to the ground state. The method of I/O used is dependent on the last USE *_IO directive.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file

Examples:	`output_low(PIN_A0);`
	
	`Int16i=PIN_A1;`
	`output_low(PIN_A1);`

Example Files:	ex_sqw.c
Also See:	input(), output_high(), output_float(), output_bit(), output_x(), #USE FIXED_IO, #USE FAST_IO, #USE STANDARD_IO, General Purpose I/O

output_toggle( )

Syntax:	**output_toggle(***pin***)**
Parameters:	**Pins** are defined in the devices .h file. The actual value is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43 . This is defined as follows: #DEFINE PIN_A3 43 .
Returns:	Undefined
Function:	Toggles the high/low state of the specified pin.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file
Examples:	`output_toggle(PIN_B4);`
Example Files:	None
Also See:	Input(), output_high(), output_low(), output_bit(), output_x()

perror( )

Syntax:	**perror(***string***);**
Parameters:	***string*** is a constant string or array of characters (null terminated).
Returns:	Nothing
Function:	This function prints out to STDERR the supplied string and a description of the last system error (usually a math error).
Availability:	All devices.
Requires:	#USE RS232, #INCLUDE <errno.h>
Examples:	see below
Example Files:	None

```
x = sin(y);

if(errno!=0)
   perror("Problem in find_area");
```

Also See:	RS232 I/O Overview

pid_busy( )

Syntax:	**result = pid_busy();**
Parameters:	None
Returns:	TRUE if PID module is busy or FALSE is PID module is not busy.
Function:	To check if the PID module is busy with a calculation.
Availability:	All devices with a PID module.
Requires:	Nothing

Examples:	`pid__get_result(PID_START_ONLY, ADCResult);`
	`while(pid_busy());`
	`pid_get_result(PID_READ_ONLY, &PIDResult);`

Example Files:	None
Also See:	setup_pid(), pid_write(), pid_get_result(), pid_read()

pid_get_result( )

Syntax:	**pid_get_result(**set_point, input, &output**);** **//Start and Read** **pid_get_result(**mode, set_point, input**);** **//Start Only** **pid_get_result(**mode, &output**)** **//Read Only** **pid_get_result(**mode, set_point, input, &output**);**
Parameters:	**mode**- constant parameter specifying whether to only start the calculation, only read the result, or start the calculation and read the result. The options are defined in the device's header file as: · PID_START_READ · PID_READ_ONLY · PID_START_ONLY **set_point** -a 16-bit variable or constant representing the set point of the control system, the value the input from the control system is compared against to determine the error in

	the system. **input** - a 16-bit variable or constant representing the input from the control system. **output** - a structure that the output of the PID module will be saved to. Either pass the address of the structure as the parameter, or a pointer to the structure as the parameter.
Returns:	Nothing
Function:	To pass the set point and input from the control system to the PID module, start the PID calculation and get the result of the PID calculation. The PID calculation starts, automatically when the input is written to the PID module's input registers.
Availability:	All devices with a PID module.
Requires:	Constants are defined in the device's .h file.

Examples:	`pid_get_result(SetPoint, ADCResult, &PIDOutput);      //Start and Read`
	`pid_get_result(PID_START_ONLY, SetPoint, ADCResult);  //Start Only`
	`pid_get_result(PID_READ_ONLY, &PIDResult);            //Read Only`

Example Files:	None
Also See:	setup_pid(), pid_read(), pid_write(), pid_busy()

pid_read( )

Syntax:	**pid_read(**register, &output**);**
Parameters:	**register**- constant specifying which PID registers to read. The registers that can be written are defined in the device's header file as: · PID_ADDR_ACCUMULATOR · PID_ADDR_OUTPUT · PID_ADDR_Z1 · PID_ADDR_Z2 · PID_ADDR_K1 · PID_ADDR_K2 · PID_ADDR_K3 **output** -a 16-bit variable, 32-bit variable or structure that specified PID registers value will be saved to. The size depends on the registers that are being read. Either pass the address of the variable or structure as the parameter, or a pointer to the variable or structure as the parameter.
Returns:	Nothing

Function:	To read the current value of the Accumulator, Output, Z1, Z2, Set Point, K1, K2 or K3 PID registers. If the PID is busy with a calculation the function will wait for module to finish calculation before reading the specified register.
Availability:	All devices with a PID module.
Requires:	Constants are defined in the device's .h file.
Examples:	`pid_read(PID_ADDR_Z1, &value_z1);`
Example Files:	None
Also See:	setup_pid(), pid_write(), pid_get_result(), pid_busy()

pid_write( )

Syntax:	**pid_write(**register, &input**);**
Parameters:	**register**- constant specifying which PID registers to write. The registers that can be written are defined in the device's header file as: · PID_ADDR_ACCUMULATOR · PID_ADDR_OUTPUT · PID_ADDR_Z1 · PID_ADDR_Z2 · PID_ADDR_Z3 · PID_ADDR_K1 · PID_ADDR_K2 · PID_ADDR_K3 **input** -a 16-bit variable, 32-bit variable or structure that contains the data to be written. The size depends on the registers that are being written. Either pass the address of the variable or structure as the parameter, or a pointer to the variable or structure as the parameter.
Returns:	Nothing
Function:	To write a new value for the Accumulator, Output, Z1, Z2, Set Point, K1, K2 or K3 PID registers. If the PID is busy with a calculation the function will wait for module to finish the calculation before writing the specified register.
Availability:	All devices with a PID module.

Requires:	Constants are defined in the device's .h file.
Examples:	`pid_write(PID_ADDR_Z1, &value_z1);`
Example Files:	None
Also See:	setup_pid(), pid_read(), pid_get_result(), pid_busy()

pll_locked( )

Syntax:	**result=pll_locked();**
Parameters:	None
Returns:	A short int. TRUE if the PLL is locked/ready, FALSE if PLL is not locked/ready
Function:	This function allows testing the PLL Ready Flag bit to determined if the PLL is stable and running.
Availability:	Devices with a Phase Locked Loop (PLL). Not all devices have a PLL Ready Flag, for those devices the pll_locked() function will always return TRUE.
Requires:	Nothing.
Examples:	while(!pll_locked());
Example Files:	None
Also See:	#use delay

port_x_pullups ( )

Syntax:	**port_a_pullups (*value*)** **port_b_pullups (*value*)**

	port_d_pullups (*value***)** **port_e_pullups (***value***)** **port_j_pullups (***value***)** **port_x_pullups (***upmask***)** **port_x_pullups (***upmask***,** *downmask***)**
Parameters:	***value*** is TRUE or FALSE on most parts, some parts that allow pullups to be specified on individual pins permit an 8 bit int here, one bit for each port pin. ***upmask*** for ports that permit pullups to be specified on a pin basis. This mask indicates what pins should have pullups activated. A 1 indicates the pullups is on. ***downmask*** for ports that permit pulldowns to be specified on a pin basis. This mask indicates what pins should have pulldowns activated. A 1 indicates the pulldowns is on.
Returns:	undefined
Function:	Sets the input pullups. TRUE will activate, and a FALSE will deactivate.
Availability:	Only 14 and 16 bit devices (PCM and PCH). (Note: use SETUP_COUNTERS on PCB parts).
Requires:	Nothing
Examples:	`port_a_pullups(FALSE);`
Example Files:	ex_lcdkb.c, kbd.c
Also See:	input(), input_x(), output_float()

pow( ) pwr( )

Syntax:	**f = pow (***x***,***y***)** **f = pwr (***x***,***y***)**
Parameters:	***x*** and ***y*** are of type float
Returns:	A float
Function:	Calculates X to the Y power. Note on error handling: If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function. Range error occurs in the following case: • pow: when the argument X is negative
Availability:	All Devices

Requires:	#INCLUDE <math.h>
Examples:	`area = pow (size,3.0);`
Example Files:	None
Also See:	None

printf( ) fprintf( )

Syntax:

printf (*string***)**
or
printf (*cstring*, *values*...**)**
or
printf (*fname*, *cstring*, *values*...**)**
fprintf (*stream*, *cstring*, *values*...**)**

Parameters:

String is a constant string or an array of characters null terminated.

Values is a list of variables separated by commas, fname is a function name to be used for outputting (default is putc is none is specified.

Stream is a stream identifier (a constant byte). Note that format specifies do not work in ram band strings.

Returns: undefined

Function:

Outputs a string of characters to either the standard RS-232 pins (first two forms) or to a specified function. Formatting is in accordance with the string argument. When variables are used this string must be a constant. The % character is used within the string to indicate a variable value is to be formatted and output. Longs in the printf may be 16 or 32 bit. A %% will output a single %. Formatting rules for the % follows.

See the Expressions > Constants and Trigraph sections of this manual for other escape character that may be part of the string.

If fprintf() is used then the specified stream is used where printf() defaults to STDOUT (the last USE RS232).

Format:

The format takes the generic form %nt. n is optional and may be 1-9 to specify how many characters are to be outputted, or 01-09 to indicate leading zeros, or 1.1 to 9.9 for floating point and %w output. t is the type and may be one of the following:

c	Character
s	String or character
u	Unsigned int
d	Signed int
Lu	Long unsigned int
Ld	Long signed int
x	Hex int (lower case)
X	Hex int (upper case)

Lx	Hex long int (lower case)
LX	Hex long int (upper case)
f	Float with truncated decimal
g	Float with rounded decimal
e	Float in exponential format
w	Unsigned int with decimal place inserted. Specify two numbers for n. The first is a total field width. The second is the desired number of decimal places.

Example formats:

Specifier	Value=0x12	Value=0xfe
%03u	018	254
%u	18	254
%2u	18	*
%5	18	254
%d	18	-2
%x	12	fe
%X	12	FE
%4X	0012	00FE
%3.1w	1.8	25.4

* Result is undefined - Assume garbage.

Availability: All Devices

Requires: #USE RS232 (unless fname is used)

Examples:

```
byte  x,y,z;
printf("HiThere");
printf("RTCCValue=>%2x\n\r",get_rtcc());
printf("%2u %X %4X\n\r",x,y,z);
printf(LCD_PUTC, "n=%u",n);
```

Example Files: ex_admm.c, ex_lcdkb.c

Also See: atoi(), puts(), putc(), getc() (for a stream example), RS232 I/O Overview

profileout()

Syntax: **profileout(string);**
profileout(string, value);
profileout(value);

Parameters: string is any constant string, and value can be any constant or variable integer. Despite the length of string the user specifies here, the code profile run-time will actually only send a one or two byte identifier tag to the code profile tool to keep transmission and execution time to a minimum.

Returns: Undefined

Function: Typically the code profiler will log and display function entry and exits, to show the call sequence and profile the execution time of the functions. By using

	profileout(), the user can add any message or display any variable in the code profile tool. Most messages sent by profileout() are displayed in the 'Data Messages' and 'Call Sequence' screens of the code profile tool. If a profileout(string) is used and the first word of string is "START", the code profile tool will then measure the time it takes until it sees the same profileout(string) where the "START" is replaced with "STOP". This measurement is then displayed in the 'Statistics' screen of the code profile tool, using string as the name (without "START" or "STOP")
Availability:	Any device.
Requires:	**#use profile()** used somewhere in the project source code.

Examples:	`// send a simple string.`
	`profileout("This is a text string");`
	`// send a variable with a string identifier.`
	`profileout("RemoteSensor=", adc);`
	`// just send a variable.`
	`profileout(adc);`
	`// time how long a block of code takes to execute.`
	`// this will be displayed in the 'Statistics' of the`
	`// Code Profile tool.`
	`profileout("start my algorithm");`
	` /* code goes here */`
	`profileout("stop my algorithm");`

Example Files:	ex_profile.c
Also See:	#use profile(), #profile, Code Profile overview

psmc_blanking( )

Syntax:	**psmc_blanking(***unit, rising_edge, rise_time, falling_edge, fall_time***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***rising_edge*** are the events that are ignored after the signal activates. ***rise_time*** is the time in ticks (0-255) that the above events are ignored. ***falling_edge*** are the events that are ignored after the signal goes inactive. ***fall_time*** is the time in ticks (0-255) that the above events are ignored. Events: • PSMC_EVENT_C1OUT

	• PSMC_EVENT_C2OUT • PSMC_EVENT_C3OUT • PSMC_EVENT_C4OUT • PSMC_EVENT_IN_PIN
Returns:	undefined
Function:	This function is used when system noise can cause an incorrect trigger from one of the specified events. This function allows for ignoring these events for a period of time around either edge of the signal. See setup_psmc() for a definition of a tick. Pass a 0 or FALSE for the events to disable blanking for an edge.
Availability:	All devices equipped with PSMC module.
Requires:	
Examples:	
Example Files:	None
Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psmc_deadband( )

Syntax:	**psmc_deadband(***unit,rising_edge, falling_edge***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***rising_edge*** is the deadband time in ticks after the signal goes active. If this function is not called, 0 is used. ***falling_edge*** is the deadband time in ticks after the signal goes inactive. If this function is not called, 0 is used.
Returns:	undefined
Function:	This function sets the deadband time values. Deadbands are a gap in time where both sides of a complementary signal are forced to be inactive. The time values are in ticks. See setup_psmc() for a definition of a tick.

Availability:	All devices equipped with PSMC module.
Requires:	undefined

Examples:	`// 5 tick deadband when the signal goes active.`
	`   psmc_deadband(1, 5, 0);`

Example Files:	None
Also See:	setup_psmc(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psmc_duty( )

Syntax:	**psmc_pins(***unit, pins_used, pins_active_low***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***fall_time*** is the time in ticks that the signal goes inactive (after the start of the period) assuming the event PSMC_EVENT_TIME has been specified in the setup_psmc().
Returns:	Undefined
Function:	This function changes the fall time (within the period) for the active signal. This can be used to change the duty of the active pulse. Note that the time is NOT a percentage nor is it the time the signal is active. It is the time from the start of the period that the signal will go inactive. If the rise_time was set to 0, then this time is the total time the signal will be active.
Availability:	All devices equipped with PSMC module.
Requires:	
Examples:	see below

```
// For a 10khz PWM, based on Fosc divided by 1
// the following sets the duty from
// 0% to 100% baed on the ADC reading
while(TRUE)  {
   psmc_duty(1,(read_adc()*(int16)10)/25)*
      (getenv("CLOCK")/1000000));
}
```

Example Files:	None
Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_freq_adjust(), psmc_pins()

psmc_freq_adjust( )

Syntax:	**psmc_freq_adjust(***unit, freq_adjust***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***freq_adjust*** is the time in tick/16 increments to add to the period. The value may be 0-15.
Returns:	Undefined
Function:	This function adds a fraction of a tick to the period time for some modes of operation.
Availability:	All devices equipped with PSMC module.
Requires:	
Examples:	
Example Files:	None
Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_dutyt(), psmc_pins()

psmc_modulation( )

Syntax:	**psmc_modulation(***unit, options***);**

Parameters:	***unit*** is the PSMC unit number 1-4 ***Options*** may be one of the following: • PSMC_MOD_OFF • PSMC_MOD_ACTIVE • PSMC_MOD_INACTIVE • PSMC_MOD_C1OUT • PSMC_MOD_C2OUT • PSMC_MOD_C3OUT • PSMC_MOD_C4OUT • PSMC_MOD_CCP1 • PSMC_MOD_CCP2 • PSMC_MOD_IN_PIN The following may be OR'ed with the above • PSMC_MOD_INVERT • PSMC_MOD_NOT_BDF • PSMC_MOD_NOT_ACE
Returns:	undefined
Function:	This function allows some source to control if the PWM is running or not. The active/inactive are used for software to control the modulation. The other sources are hardware controlled modulation. There are also options to invert the inputs, and to ignore some of the PWM outputs for the purpose of modulation.
Availability:	All devices equipped with PSMC module.
Requires:	
Examples:	
Example Files:	None
Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psmc_pins( )

Syntax:

psmc_pins(*unit, pins_used, pins_active_low***);**

Parameters:

unit is the PSMC unit number 1-4

used_pins is the any combination of the following or'ed together:

- PSMC_A
- PSMC_B
- PSMC_C
- PSMC_D
- PSMC_E
- PSMC_F
- PSMC_ON_NEXT_PERIOD

If the last constant is used, all the changes made take effect on the next period (as opposed to immediate)

pins_active_low is an optional parameter. When used it lists the same pins from above as the pins that should have an inverted polarity.

Returns:

Undefined

Function:

This function identified the pins allocated to the PSMC unit, the polarity of those pins and it enables the PSMC unit. The tri-state register for each pin is set to the output state.

Availability:

All devices equipped with PSMC module.

Requires:

Examples:

```
// Simple PWM, 10khz out on pin C0 assuming a 20mhz crystal
// Duty is initially set to 25%
   setup_psmc(1, PSMC)SINGLE,
      PSMC_EVENT_TIME | PSMC_SOURCE_FOSC, us(100,
      PSMC_EVENT_TIME, 0,
      PSMC_EVENT_TIME, us(25));

   psmc_pins(1, PSMC_A);
```

Example Files:

None

Also See:

setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust()

psmc_shutdown( )

Syntax:	**psmc_shutdown(***unit, options, source, pins_high***);** **psmc_shutdown(***unit, command***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***Options*** may be one of the following: • PSMC_SHUTDOWN_OFF • PSMC_SHUTDOWN_NORMAL • PSMC_SHUTDOWN_AUTO_RESTART ***command*** may be one of the following: • PSMC_SHUTDOWN_RESTART • PSMC_SHUTDOWN_FORCE • PSMC_SHUTDOWN_CHECK ***source*** may be any of the following or'ed together: • PSMC_SHUTDOWN_C1OUT • PSMC_SHUTDOWN_C2OUT • PSMC_SHUTDOWN_C3OUT • PSMC_SHUTDOWN_C4OUT • PSMC_SHUTDOWN_IN_PIN ***pins_high*** is any combination of the following or'ed together: • PSMC_A • PSMC_B • PSMC_C • PSMC_D • PSMC_E • PSMC_F
Returns:	Non-zero if the unit is now in shutdown.
Function:	This function implements a shutdown capability. when any of the listed events activate the PSMC unit will shutdown and the output pins are driver low unless they are listed in the pins that will be driven high. The auto restart option will restart when the condition goes inactive, otherwise a call with the restart command must be used. Software can force a shutdown with the force command.
Availability:	All devices equipped with PSMC module.

Requires:	
Examples:	
Example Files:	None
Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psmc_sync( )

Syntax:	**psmc_sync(***slave_unit, master_unit, options***);**
Parameters:	***slave_unit*** is the PSMC unit number 1-4 to be controlled. ***master_unit*** is the PSMC unit number 1-4 to be synchronized to Options may be: • PSMC_SOURCE_IS_PHASE • PSMC_SOURCE_IS_PERIOD • PSMC_DISCONNECT The following may be OR'ed with the above: • PSMC_INVERT_DUTY • PSMC_INVET_PERIOD
Returns:	undefined
Function:	This function allows one PSMC unit (the slave) to be synchronized (the outputs) with another PSMC unit (the master).
Availability:	All devices equipped with PSMC module.
Requires:	
Examples:	
Example Files:	None

Also See:	setup_psmc(), psmc_deadband(), psmc_sync(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

psp_output_full( ) psp_input_full( ) psp_overflow( )

Syntax:	**result = psp_output_full()**
	result = psp_input_full()
	result = psp_overflow()
	result = psp_error(); //EPMP only
	result = psp_timeout(); //EPMP only

Parameters:	None
Returns:	A 0 (FALSE) or 1 (TRUE)
Function:	These functions check the Parallel Slave Port (PSP) for the indicated conditions and return TRUE or FALSE.
Availability:	This function is only available on devices with PSP hardware on chips.
Requires:	Nothing

Examples:	`while (psp_output_full()) ;`
	`psp_data = command;`
	`while(!psp_input_full()) ;`
	`if ( psp_overflow() )`
	`   error = TRUE;`
	`else`
	`   data = psp_data;`

Example Files:	ex_psp.c
Also See:	setup_psp(), PSP Overview

putc_send( ) fputc_send( )

Syntax:	**putc_send();**
	fputc_send(stream**);**

Parameters:	**stream** – parameter specifying the stream defined in #USE RS232.
Returns:	Nothing

Function:	Function used to transmit bytes loaded in transmit buffer over RS232. Depending on the options used in #USE RS232 controls if function is available and how it works. If using hardware UARTx with NOTXISR option it will check if currently transmitting. If not transmitting it will then check for data in transmit buffer. If there is data in transmit buffer it will load next byte from transmit buffer into the hardware TX buffer, unless using CTS flow control option. In that case it will first check to see if CTS line is at its active state before loading next byte from transmit buffer into the hardware TX buffer. If using hardware UARTx with TXISR option, function only available if using CTS flow control option, it will test to see if the TBEx interrupt is enabled. If not enabled it will then test for data in transmit buffer to send. If there is data to send it will then test the CTS flow control line and if at its active state it will enable the TBEx interrupt. When using the TXISR mode the TBEx interrupt takes care off moving data from the transmit buffer into the hardware TX buffer. If using software RS232, only useful if using CTS flow control, it will check if there is data in transmit buffer to send. If there is data it will then check the CTS flow control line, and if at its active state it will clock out the next data byte.
Availability:	All devices
Requires:	#USE RS232

Examples:	#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50,NOTXISR)
	printf("Testing Transmit Buffer");
	while(TRUE){
	   putc_send();
	}

Example Files:	None
Also See:	_USE_RS232( ), RCV_BUFFER_FULL( ), TX_BUFFER_FULL( ), TX_BUFFER_BYTES( ), GET( ), PUTC( ) RINTF( ), SETUP_UART( ), PUTC( )_SEND

pwm_off()

Syntax:	**pwm_off([stream]);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE PWM.
Returns:	Nothing.
Function:	To turn off the PWM signal.
Availability:	All devices.
Requires:	#USE PWM

Examples:	#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
	 while(TRUE){
	   if(kbhit()){
	      c = getc();

	` if(c=='F')`
	`   pwm_off();`
	` }`
	`}`

Example Files:	None
Also See:	#use_pwm, pwm_on(), pwm_set_duty_percent(), pwm_set_duty(), pwm_set_frequency()

pwm_on()

Syntax:	**pwm_on([stream]);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE PWM.
Returns:	Nothing.
Function:	To turn on the PWM signal.
Availability:	All devices.
Requires:	#USE PWM
Examples:	see below
Example Files:	None
Also See:	#use_pwm, pwm_off(), pwm_set_duty_percent(), pwm_set_duty, pwm_set_frequency()

```
#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)
 while(TRUE){
   if(kbhit()){
      c = getc();

      if(c=='O')
         pwm_on();
   }
}
```

pwm_set_duty()

Syntax:	**pwm_set_duty([**stream**],**duty)**;**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE PWM. **duty** – an int16 constant or variable specifying the new PWM high time.
Returns:	Nothing.
Function:	To change the duty cycle of the PWM signal. The duty cycle percentage depends on the period of the PWM signal. This function is faster than pwm_set_duty_percent(), but requires you to know what the period of the PWM signal is.
Availability:	All devices.
Requires:	#USE PWM

Examples:	`#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)`
Example Files:	None
Also See:	#use_pwm, pwm_on, pwm_off(), pwm_set_frequency(), pwm_set_duty_percent()

pwm_set_duty_percent

Syntax:	**pwm_set_duty_percent([stream]), percent**
Parameters:	stream – optional parameter specifying the stream defined in #USE PWM. percent- an int16 constant or variable ranging from 0 to 1000 specifying the new PWM duty cycle, D is 0% and 1000 is 100.0%.
Returns:	Nothing.
Function:	To change the duty cycle of the PWM signal. Duty cycle percentage is based off the current frequency/period of the PWM signal.
Availability:	All devices.
Requires:	#USE PWM

Examples:	`#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)`
	`pwm_set_duty_percent(500);   //set PWM duty cycle to 50%`

Example Files:	None
Also See:	#use_pwm, pwm_on(), pwm_off(), pwm_set_frequency(), pwm_set_duty()

pwm_set_frequency

Syntax:	**pwm_set_frequency([stream],frequency);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE PWM. **frequency** – an int32 constant or variable specifying the new PWM frequency.
Returns:	Nothing.
Function:	To change the frequency of the PWM signal. Warning this may change the resolution of the PWM signal.
Availability:	All devices.
Requires:	#USE PWM

Examples:	`#USE PWM(OUTPUT=PIN_C2, FREQUENCY=10kHz, DUTY=25)`
	`pwm_set_frequency(1000);   //set PWM frequency to 1kHz`

Example Files:	None
Also See:	#use_pwm, pwm_on(), pwm_off(), pwm_set_duty_percent, pwm_set_duty()

pwm1_interrupt_active( ) pwm2_interrupt_active( ) pwm3_interrupt_active( ) pwm4_interrupt_active( ) pwm5_interrupt_active( ) pwm6_interrupt_active( )

Syntax:	**result_pwm1_interrupt_active (***interrupt***)** **result_pwm2_interrupt_active (***interrupt***)** **result_pwm3_interrupt_active (***interrupt***)** **result_pwm4_interrupt_active (***interrupt***)** **result_pwm5_interrupt_active (***interrupt***)** **result_pwm6_interrupt_active (***interrupt***)**
Parameters:	***interrupt*** - 8-bit constant or variable. Constants are defined in the device's header file as: • PWM_PERIOD_INTERRUPT • PWM_DUTY_INTERRUPT • PWM_PHASE_INTERRUPT • PWM_OFFSET_INTERRUPT
Returns:	TRUE if interrupt is active. FALSE if interrupt is not active.
Function:	Tests to see if one of the above PWM interrupts is active, interrupt flag is set.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`if(pwm1_interrupt_active(PWM_PERIOD_INTERRUPT))`
	`   clear_pwm1_interrupt(PWM_PERIOD_INTERRUPT);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_phase(), set_pwm_period(), set_pwm_offset(), enable_pwm_interrupt(), clear_pwm_interrupt(), disable_pwm_interrupt()

qei_get_count( )

Syntax:	**value = qei_get_count([***type***]);**
Parameters:	***type*** - Optional parameter to specify which counter to get, defaults to position counter. Defined in devices .h file as: QEI_GET_POSITION_COUNT QEI_GET_VELOCITY_COUNT
Returns:	The 16-bit value of the position counter or velocity counter.

Function:	Reads the current 16-bit value of the position or velocity counter.
Availability:	Devices that have the QEI module.
Requires:	Nothing.

Examples:	`value = qei_get_counter(QEI_GET_POSITION_COUNT);`
	`value = qei_get_counter();`
	`value = qei_get_counter(QEI_GET_VELOCITY_COUNT);`

Example Files:	None
Also See:	setup_qei() , qei_set_count() , qei_status().

qei_status( )

Syntax:	**status = qei_status( );**
Parameters:	None
Returns:	The status of the QEI module.
Function:	Returns the status of the QEI module.
Availability:	Devices that have the QEI module.
Requires:	Nothing.
Examples:	`status = qei_status();`
Example Files:	None
Also See:	setup_qei() , qei_set_count() , qei_get_count().

qsort( )

Syntax:	**qsort (***base, num, width, compare***)**
Parameters:	**base**: Pointer to array of sort data **num**: Number of elements **width**: Width of elements **compare**: Function that compares two elements

Returns:	None
Function:	Performs the shell-metzner sort (not the quick sort algorithm). The contents of the array are sorted into ascending order according to a comparison function pointed to by compare.
Availability:	All devices
Requires:	#INCLUDE <stdlib.h>
Examples:	see below
Example Files:	ex_qsort.c
Also See:	bsearch()

```
int nums[5]={ 2,3,1,5,4};
int compar(void *arg1,void *arg2);

void main()  {
   qsort ( nums, 5, sizeof(int), compar);
}

int compar(void *arg1,void *arg2)  {
   if ( * (int *) arg1 < ( * (int *) arg2) return -1
   else if ( * (int *) arg1 == ( * (int *) arg2) return 0
   else return 1;
}
```

rand( )

Syntax:	**re=rand()**
Parameters:	None
Returns:	A pseudo-random integer.
Function:	The rand function returns a sequence of pseudo-random integers in the range of 0 to RAND_MAX.
Availability:	All devices
Requires:	#INCLUDE <STDLIB.H>
Examples:	see below

```
int I;
I=rand();
```

Example Files:	None
Also See:	srand()

rcv_buffer_bytes( )

Syntax:	**value = rcv_buffer_bytes([**stream**]);**
Parameters:	stream – optional parameter specifying the stream defined in #USE RS232.
Returns:	Number of bytes in receive buffer that still need to be retrieved.
Function:	Function to determine the number of bytes in receive buffer that still need to be retrieved.
Availability:	All devices
Requires:	#USE RS232

Examples:	#USE_RS232(UART1,BAUD=9600,RECEIVE_BUFFER=100)
	void main(void) {
	   char c;
	   if(rcv_buffer_bytes() > 10)
	   c = getc();
	}

Example Files:	None
Also See:	_USE_RS232( ), RCV_BUFFER_FULL( ), TX_BUFFER_FULL( ), TX_BUFFER_BYTES( ), GETC( ), PUTC( ) ,PRINTF( ), SETUP_UART( ), PUTC_SEND( )

rcv_buffer_full( )

Syntax:	**value = rcv_buffer_full([stream]);**
Parameters:	stream – optional parameter specifying the stream defined in #USE RS232.
Returns:	TRUE if receive buffer is full, FALSE otherwise.
Function:	Function to test if the receive buffer is full.
Availability:	All devices
Requires:	#USE RS232

Examples:	#USE_RS232(UART1,BAUD=9600,RECEIVE_BUFFER=100)
	void main(void) {
	   char c;
	   if(rcv_buffer_full())

	c = getc();
	}

Example Files:	None
Also See:	_USE_RS232( ),RCV_BUFFER_BYTES( ), TX_BUFFER_BYTES( ) ,TX_BUFFER_FULL( ), GETC( ), PUTC( ), PRINTF( ), SETUP_UART( ), PUTC_SEND( )

read_adc( )

Syntax: **value = read_adc ([*mode*])**

Parameters: ***mode*** is an optional parameter. If used the values may be:
ADC_START_AND_READ (continually takes readings, this is the default)
ADC_START_ONLY (starts the conversion and returns)
ADC_READ_ONLY (reads last conversion result)

Returns: Either a 8 or 16 bit int depending on #DEVICE ADC= directive.

Function: This function will read the digital value from the analog to digital converter. Calls to setup_adc(), setup_adc_ports() and set_adc_channel() should be made sometime before this function is called. The range of the return value depends on number of bits in the chips A/D converter and the setting in the #DEVICE ADC= directive as follows:

#DEVICE	8 bit	10 bit	11 bit	12 bit	16 bit
ADC=8	00-FF	00-FF	00-FF	00-FF	00-FF
ADC=10	x	0-3FF	x	0-3FF	x
ADC=11	x	x	0-7FF	x	x
ADC=16	0FF00	0-FFC0	0-FFEO	0-FFF0	0-FFFF

Note: x is not defined

Availability: This function is only available on devices with A/D hardware.

Requires: Pin constants are defined in the devices .h file.

Examples:

```
setup_adc(  ADC_CLOCK_INTERNAL  );
setup_adc_ports( ALL_ANALOG );
set_adc_channel(1);
while ( input(PIN_B0) ) {
   delay_ms( 5000 );
   value = read_adc();
   printf("A/D value = %2x\n\r", value);
}

read_adc(ADC_START_ONLY);
sleep();
value=read_adc(ADC_READ_ONLY);
```

Example Files: ex_admm.c, ex_14kad.c

Also See:	setup_adc(), set_adc_channel(), setup_adc_ports(), #DEVICE, ADC Overview

read_bank( )

Syntax:	**value = read_bank (*bank*, *offset*)**
Parameters:	***bank*** is the physical RAM bank 1-3 (depending on the device) ***offset*** is the offset into user RAM for that bank (starts at 0),
Returns:	8 bit int
Function:	Read a data byte from the user RAM area of the specified memory bank. This function may be used on some devices where full RAM access by auto variables is not efficient. For example, setting the pointer size to 5 bits on the PIC16C57 chip will generate the most efficient ROM code. However, auto variables can not be above 1Fh. Instead of going to 8 bit pointers, you can save ROM by using this function to read from the hard-to-reach banks. In this case, the bank may be 1-3 and the offset may be 0-15.
Availability:	All devices but only useful on PCB parts with memory over 1Fh and PCM parts with memory over FFh.
Requires:	Nothing

Examples:	`// See write_bank() example to see`
	`// how we got the data`
	`// Moves data from buffer to LCD`
	`i=0;`
	`do {`
	`   c=read_bank(1,i++);`
	`   if(c!=0x13)`
	`     lcd_putc(c);`
	`} while (c!=0x13);`

Example Files:	ex_psp.c
Also See:	write_bank(), and the "Common Questions and Answers" section for more information.

read_calibration( )

Syntax:	**value = read_calibration (*n*)**
Parameters:	***n*** is an offset into calibration memory beginning at 0

Returns:	An 8 bit byte
Function:	The read_calibration function reads location "n" of the 14000-calibration memory.
Availability:	This function is only available on the PIC14000.
Requires:	Nothing
Examples:	fin = read_calibration(16);
Example Files:	ex_14kad.c with 14kcal.c
Also See:	None

read_configuration_memory( )

Syntax:	**read_configuration_memory(**[offset], ramPtr, n**)**
Parameters:	***ramPtr*** is the destination pointer for the read results ***count*** is an 8 bit integer **offset** is an optional parameter specifying the offset into configuration memory to start reading from, offset defaults to zero if not used.
Returns:	undefined
Function:	For PIC18-Reads ***n*** bytes of configuration memory and saves the values to ***ramPtr***. For Enhanced16 devices function reads User ID, Device ID and configuration memory regions.
Availability:	All PIC18 Flash and Enhanced16 devices
Requires:	Nothing

Examples:	`int data[6];`
	`read_configuration_memory(data,6);`

Example Files:	None
Also See:	write_configuration_memory(), read_program_memory(), Configuration Memory Overview,

read_eeprom( )

Syntax:	**value = read_eeprom (***address* **)**
Parameters:	***address*** is an 8 bit or 16 bit int depending on the part
Returns:	An 8 bit int
Function:	Reads a byte from the specified data EEPROM address. The address begins at 0 and the range depends on the part.
Availability:	This command is only for parts with built-in EEPROMS
Requires:	Nothing

Examples:	`#define LAST_VOLUME  10`
	`volume = read_EEPROM (LAST_VOLUME);`

Example Files:	None
Also See:	write_eeprom(), Data Eeprom Overview

read_extended_ram( )

Syntax:	**read_extended_ram(**page,address,data,count**);**
Parameters:	**page** – the page in extended RAM to read from **address** – the address on the selected page to start reading from **data** – pointer to the variable to return the data to **count** – the number of bytes to read (0-32768)
Returns:	Undefined
Function:	To read data from the extended RAM of the PIC.
Availability:	On devices with more then 30K of RAM.
Requires:	Nothing

Examples:	`unsigned int8 data[8];`
	`read_extended_ram(1,0x0000,data,8);`

Example Files:	None

Also See:	read_extended_ram(), Extended RAM Overview

read_program_memory( ) read_external_memory( )

Syntax:	**READ_PROGRAM_MEMORY (***address***,** *dataptr***,** *count* **);**
	READ_EXTERNAL_MEMORY (*address***,** *dataptr***,** *count* **);**

Parameters:	***address*** is 16 bits on PCM parts and 32 bits on PCH parts . The least significant bit should always be 0 in PCM. ***dataptr*** is a pointer to one or more bytes. ***count*** is a 8 bit integer on PIC16 and 16-bit for PIC18
Returns:	undefined
Function:	Reads ***count*** bytes from program memory at ***address*** to RAM at ***dataptr***. B oth of these functions operate exactly the same.
Availability:	Only devices that allow reads from program memory.
Requires:	Nothing

Examples:	`char buffer[64];`
	`read_external_memory(0x40000, buffer, 64);`

Example Files:	None
Also See:	write program memory( ), External memory overview , Program Eeprom Overview

read_high_speed_adc( )

Syntax:	**read_high_speed_adc(**pair**,**mode**,**result**);** **// Individual start and read or // read only** **read_high_speed_adc(**pair**,**result**);** **// Individual start and read** **read_high_speed_adc(**pair**);** **// Individual start only** **read_high_speed_adc(**mode**,**result**);** **// Global start and read or // read only** **read_high_speed_adc(**result**);** **// Global start and read** **read_high_speed_adc();** **// Global start only**
Parameters:	**pair** – Optional parameter that determines which ADC pair number to start and/or read. Valid values are 0 to total number of ADC pairs. 0 starts and/or reads ADC pair AN0 and AN1, 1 starts and/or reads ADC pair AN2 and AN3, etc. If omitted then a global start and/or read will be performed. **mode** – Optional parameter, if used the values may be: • ADC_START_AND_READ (starts conversion and reads result)

	▪ ADC_START_ONLY (starts conversion and returns) ▪ ADC_READ_ONLY(reads conversion result) **result** – Pointer to return ADC conversion too. Parameter is optional, if not used the read_fast_adc() function can only perform a start.
Returns:	Undefined
Function:	This function is used to start an analog to digital conversion and/or read the digital value when the conversion is complete. Calls to setup_high_speed_adc() and setup_high_speed_adc_pairs() should be made sometime before this function is called. When using this function to perform an individual start and read or individual start only, the function assumes that the pair's trigger source was set to INDIVIDUAL_SOFTWARE_TRIGGER. When using this function to perform a global start and read, global start only, or global read only. The function will perform the following steps: 1. Determine which ADC pairs are set for GLOBAL_SOFTWARE_TRIGGER. 2. Clear the corresponding ready flags (if doing a start). 3. Set the global software trigger (if doing a start). 4. Read the corresponding ADC pairs in order from lowest to highest (if doing a read). 5. Clear the corresponding ready flags (if doing a read). When using this function to perform a individual read only. The function can read the ADC result from any trigger source.
Availability:	Only on dsPIC33FJxxGSxxx devices.
Requires:	Constants are define in the device .h file.
Examples:	see below

```
//Individual start and read
int16 result[2];

setup_high_speed_adc(ADC_CLOCK_DIV_4);
setup_high_speed_adc_pair(0,  INDIVIDUAL_SOFTWARE_TRIGGER);
read_high_speed_adc(0, result); //starts conversion for AN0 and AN1 and
stores
                         //result in result[0] and result[1]

//Global start and read
int16 result[4];

setup_high_speed_adc(ADC_CLOCK_DIV_4);
setup_high_speed_adc_pair(0, GLOBAL_SOFTWARE_TRIGGER);
setup_high_speed_adc_pair(4, GLOBAL_SOFTWARE_TRIGGER);
read_high_speed_adc(result); //starts conversion for AN0, AN1,
                            //AN8 and AN9 and
                            //stores result in result[0], result //[1],
result[2]
```

	`and result[3]`
Example Files:	None
Also See:	setup_high_speed_adc(), setup_high_speed_adc_pair(), high_speed_adc_done()

read_rom_memory( )

Syntax:	**READ_ROM_MEMORY (***address*, *dataptr*, *count* **);**
Parameters:	***address*** is 32 bits. The least significant bit should always be 0. ***dataptr*** is a pointer to one or more bytes. ***count*** is a 16 bit integer
Returns:	undefined
Function:	Reads ***count*** bytes from program memory at ***address*** to ***dataptr***. Due to the 24 bit program instruction size on the PCD devices, three bytes are read from each address location.
Availability:	Only devices that allow reads from program memory.
Requires:	Nothing

Examples:	`char buffer[64];`
	`read_program_memory(0x40000, buffer, 64);`

Example Files:	None
Also See:	write_program_eeprom() , write_eeprom(), read_eeprom(), Program eeprom overview

read_sd_adc( )

Syntax:	**value = read_sd_adc();**
Parameters:	None
Returns:	A signed 32 bit int.
Function:	To poll the SDRDY bit and if set return the signed 32 bit value stored in the SD1RESH and SD1RESL registers, and clear the SDRDY bit. The result returned depends on settings made with the setup_sd_adc() function, but will always be a signed int32 value with the most significant bits being meaningful. Refer to Section 66, 16-bit Sigma-Delta A/D Converter, of the PIC24F Family Reference Manual for more information on the module and the result format.

Availability:	Only devices with a Sigma-Delta Analog to Digital Converter (SD ADC) module.
Examples:	value = read_sd_adc()
Example Files:	None
Also See:	setup_sd_adc(), set_sd_adc_calibration(), set_sd_adc_channel()

realloc( )

Syntax:	**realloc (*ptr*, *size*)**
Parameters:	***ptr*** is a null pointer or a pointer previously returned by calloc or malloc or realloc function, size is an integer representing the number of byes to be allocated.
Returns:	A pointer to the possibly moved allocated memory, if any. Returns null otherwise.
Function:	The realloc function changes the size of the object pointed to by the ptr to the size specified by the size. The contents of the object shall be unchanged up to the lesser of new and old sizes. If the new size is larger, the value of the newly allocated space is indeterminate. If ptr is a null pointer, the realloc function behaves like malloc function for the specified size. If the ptr does not match a pointer earlier returned by the calloc, malloc or realloc, or if the space has been deallocated by a call to free or realloc function, the behavior is undefined. If the space cannot be allocated, the object pointed to by ptr is unchanged. If size is zero and the ptr is not a null pointer, the object is to be freed.
Availability:	All devices
Requires:	#INCLUDE <stdlibm.h>

Examples:	`int * iptr;`
	`iptr=malloc(10);`
	`realloc(iptr,20)`
	
	`// iptr will point to a block of memory of 20 bytes, if available.`

Example Files:	None
Also See:	malloc(), free(), calloc()

release_io()

Syntax:	**release_io();**
Parameters:	none
Returns:	nothing
Function:	The function releases the I/O pins after the device wakes up from deep sleep, allowing the state of the I/O pins to change
Availability:	Devices with a deep sleep module.
Requires:	Nothing

Examples:	`unsigned int16 restart;`
	
	`restart = restart_cause();`
	
	`if(restart == RTC_FROM_DS)`
	`    release_io();`

Example Files:	None
Also See:	sleep()

reset_cpu( )

Syntax:	**reset_cpu()**
Parameters:	None
Returns:	This function never returns
Function:	This is a general purpose device reset. It will jump to location 0 on PCB and PCM parts and also reset the registers to power-up state on the PIC18XXX.
Availability:	All devices
Requires:	Nothing

Examples:	`if(checksum!=0)`
	`   reset_cpu();`

Example Files:	None
Also See:	None

restart_cause( )

Syntax:	**value = restart_cause()**
Parameters:	None
Returns:	A value indicating the cause of the last processor reset. The actual values are device dependent. See the device .h file for specific values for a specific device. Some example values are: WDT_FROM_SLEEP, WDT_TIMEOUT, MCLR_FROM_SLEEP and NORMAL_POWER_UP.
Function:	Returns the cause of the last processor reset.
Availability:	All devices
Requires:	Constants are defined in the devices .h file.

Examples:	`switch ( restart_cause() ) {`
	`     case WDT_FROM_SLEEP:`
	`   case WDT_TIMEOUT:`
	
	`          handle_error();`
	`}`

Example Files:	ex_wdt.c
Also See:	restart_wdt(), reset_cpu()

restart_wdt( )

Syntax:	**restart_wdt()**
Parameters:	None
Returns:	undefined
Function:	Restarts the watchdog timer. If the watchdog timer is enabled, this must be called periodically to prevent the processor from resetting. The watchdog timer is used to cause a hardware reset if the software appears to be stuck. The timer must be enabled, the timeout time set and software must periodically restart the timer. These are done differently on the PCB/PCM and PCH parts as follows:

	PCB/PCM	PCH
Enable/Disable	#fuses	setup_wdt()
Timeout time	setup_wdt()	#fuses
restart	restart_wdt()	restart_wdt()

Availability: All devices

Requires: #FUSES

Examples:

```
#fuses WDT      // PCB/PCM example
                // See setup_wdt for a
                // PIC18 example
main() {
   setup_wdt(WDT_2304MS);
   while (TRUE) {
    restart_wdt();
    perform_activity();
   }
}
```

Example Files: ex_wdt.c

Also See: #FUSES, setup_wdt(), WDT or Watch Dog Timer Overview

rotate_left( )

Syntax: **rotate_left (*address*, *bytes*)**

Parameters: ***address*** is a pointer to memory
bytes is a count of the number of bytes to work with.

Returns: undefined

Function: Rotates a bit through an array or structure. The address may be an array identifier or an address to a byte or structure (such as &data). Bit 0 of the lowest BYTE in RAM is considered the LSB.

Availability: All devices

Requires: Nothing

Examples:

```
x = 0x86;
rotate_left( &x, 1);
// x is now 0x0d
```

Example Files: None

Also See: rotate_right(), shift_left(), shift_right()

rotate_right( )

Syntax:	**rotate_right (*address*, *bytes*)**
Parameters:	***address*** is a pointer to memory, ***bytes*** is a count of the number of bytes to work with.
Returns:	undefined
Function:	Rotates a bit through an array or structure. The address may be an array identifier or an address to a byte or structure (such as &data). Bit 0 of the lowest BYTE in RAM is considered the LSB.
Availability:	All devices
Requires:	Nothing

Examples:	`struct {`
	`   int cell_1 : 4;`
	`   int cell_2 : 4;`
	`   int cell_3 : 4;`
	`   int cell_4 : 4; } cells;`
	`rotate_right( &cells, 2);`
	`rotate_right( &cells, 2);`
	`rotate_right( &cells, 2);`
	`rotate_right( &cells, 2);`
	`// cell_1->4, 2->1, 3->2 and 4-> 3`

Example Files:	None
Also See:	rotate_left(), shift_left(), shift_right()

rtc_alarm_read( )

Syntax:	**rtc_alarm_read(&*datetime*);**
Parameters:	***datetime***- A structure that will contain the values to be written to the alarm in the RTCC module. Structure used in read and write functions are defined in the device header file as rtc_time_t
Returns:	void
Function:	Reads the date and time from the alarm in the RTCC module to structure ***datetime***.

Availability:	Devices that have the RTCC module.
Requires:	Nothing.
Examples:	`rtc_alarm_read(&datetime);`
Example Files:	None
Also See:	rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(), setup_rtc()

rtc_alarm_write( )

Syntax:	**rtc_alarm_write(&*datetime*);**
Parameters:	***datetime***- A structure that will contain the values to be written to the alarm in the RTCC module. Structure used in read and write functions are defined in the device header file as rtc_time_t.
Returns:	void
Function:	Writes the date and time to the alarm in the RTCC module as specified in the structure date time.
Availability:	Devices that have the RTCC module.
Requires:	Nothing.
Examples:	`rtc_alarm_write(&datetime);`
Example Files:	None
Also See:	rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(), setup_rtc()

rtc_read( )

Syntax:	**rtc_read(&*datetime*);**
Parameters:	***datetime***- A structure that will contain the values returned by the RTCC module. Structure used in read and write functions are defined in the device header file as rtc_time_t.
Returns:	void
Function:	Reads the current value of Time and Date from the RTCC module and stores the structure date time.
Availability:	Devices that have the RTCC module.
Requires:	Nothing.
Examples:	`rtc_read(&datetime);`
Example Files:	ex_rtcc.c
Also See:	rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(), setup_rtc()

rtc_write( )

Syntax:	**rtc_write(&*datetime*);**
Parameters:	***datetime***- A structure that will contain the values to be written to the RTCC module. Structure used in read and write functions are defined in the device header file as rtc_time_t.
Returns:	void
Function:	Writes the date and time to the RTCC module as specified in the structure date time.
Availability:	Devices that have the RTCC module.
Requires:	Nothing.
Examples:	`rtc_write(&datetime);`
Example Files:	ex_rtcc.c

Also See:	rtc_read() , rtc_alarm_read() , rtc_alarm_write() , setup_rtc_alarm() , rtc_write(), setup_rtc()

rtos_await( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_await (***expre***)**
Parameters:	***expre*** is a logical expression.
Returns:	None
Function:	This function can only be used in an RTOS task. This function waits for ***expre*** to be true before continuing execution of the rest of the code of the RTOS task. This function allows other tasks to execute while the task waits for ***expre*** to be true.
Availability:	All devices
Requires:	#USE RTOS
Examples:	rtos_await(kbhit());
Also See:	None

rtos_disable( )

The RTOS is only included in the PCW, PCWH, and PCWHD software packages.

Syntax:	**rtos_disable** *(task)*
Parameters:	***task*** is the identifier of a function that is being used as an RTOS task.
Returns:	None
Function:	This function disables a task which causes the task to not execute until enabled by rtos_enable(). All tasks are enabled by default.
Availability:	All devices
Requires:	#USE RTOS

Examples:	`rtos_disable(toggle_green)`
Also See:	rtos enable()

rtos_enable( )

The RTOS is only included in the PCW, PCWH, and PCWHD software packages.

Syntax:	**rtos_enable** *(task)*
Parameters:	***task*** is the identifier of a function that is being used as an RTOS task.
Returns:	None
Function:	This function enables a task to execute at it's specified rate.
Availability:	All devices
Requires:	#USE RTOS
Examples:	`rtos_enable(toggle_green);`
Also See:	rtos disable()

rtos_msg_poll( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**i = rtos_msg_poll()**
Parameters:	None
Returns:	An integer that specifies how many messages are in the queue.
Function:	This function can only be used inside an RTOS task. This function returns the number of messages that are in the queue for the task that the rtos_msg_poll() function is used in.
Availability:	All devices
Requires:	#USE RTOS

Examples:	`if(rtos_msg_poll())`
Also See:	rtos msg send(), rtos msg read()

rtos_msg_read( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**b = rtos_msg_read()**
Parameters:	None
Returns:	A byte that is a message for the task.
Function:	This function can only be used inside an RTOS task. This function reads in the next (message) of the queue for the task that the rtos_msg_read() function is used in.
Availability:	All devices
Requires:	#USE RTOS

Examples:	`if(rtos_msg_poll()) {`
	`       b = rtos_msg_read();`

Also See:	rtos msg poll(), rtos msg send()

rtos_msg_send( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_msg_send(***task, byte***)**
Parameters:	***task*** is the identifier of a function that is being used as an RTOS task ***byte*** is the byte to send to ***task*** as a message.
Returns:	None
Function:	This function can be used anytime after rtos_run() has been called. This function sends a byte long message (***byte***) to the task identified by ***task***.
Availability:	All devices
Requires:	#USE RTOS

Examples:	`if(kbhit())`
	`{`
	`      rtos_msg_send(echo, getc());`
	`}`

Also See:	rtos_msg_poll(), rtos_msg_read()

rtos_overrun( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_overrun(***[task]***)**
Parameters:	***task*** is an optional parameter that is the identifier of a function that is being used as an RTOS task
Returns:	A 0 (FALSE) or 1 (TRUE)
Function:	This function returns TRUE if the specified task took more time to execute than it was allocated. If no task was specified, then it returns TRUE if any task ran over it's alloted execution time.
Availability:	All devices
Requires:	#USE RTOS(statistics)
Examples:	`rtos_overrun()`
Also See:	None

rtos_run( )

The RTOS is only included in the PCW, PCWH, and PCWHD software packages.

Syntax:	**rtos_run()**
Parameters:	None
Returns:	None
Function:	This function begins the execution of all enabled RTOS tasks. This function controls the execution of the RTOS tasks at the allocated rate for each task. This function will return only when rtos_terminate() is called.

Availability:	All devices
Requires:	#USE RTOS
Examples:	`rtos_run()`
Also See:	rtos terminate()

rtos_signal( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_signal** *(sem)*
Parameters:	***sem*** is a global variable that represents the current availability of a shared system resource (a semaphore).
Returns:	None
Function:	This function can only be used by an RTOS task. This function increments ***sem*** to let waiting tasks know that a shared resource is available for use.
Availability:	All devices
Requires:	#USE RTOS
Examples:	`rtos_signal(uart_use)`
Also See:	rtos wait()

rtos_stats( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_stats(***task,&stat***)**

Parameters:	***task*** is the identifier of a function that is being used as an RTOS task.
	stat is a structure containing the following:
	struct rtos_stas_struct {
	unsigned int32 task_total_ticks; //number of ticks the task has //used
	unsigned int16 task_min_ticks; //the minimum number of ticks //used
	unsigned int16 task_max_ticks; //the maximum number of ticks

	//used
	unsigned int16 hns_per_tick; //us = (ticks*hns_per_tick)/10
	};

Returns:	Undefined
Function:	This function returns the statistic data for a specified ***task***.
Availability:	All devices
Requires:	#USE RTOS(statistics)
Examples:	`rtos_stats(echo, &stats)`
Also See:	None

rtos_terminate( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_terminate()**
Parameters:	None
Returns:	None
Function:	This function ends the execution of all RTOS tasks. The execution of the program will continue with the first line of code after the rtos_run() call in the program. (This function causes rtos_run() to return.)
Availability:	All devices
Requires:	#USE RTOS
Examples:	`rtos_terminate()`
Also See:	rtos run()

rtos_wait( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_wait (*sem*)**
Parameters:	***sem*** is a global variable that represents the current availability of a shared

	system resource (a semaphore).
Returns:	None
Function:	This function can only be used by an RTOS task. This function waits for ***sem*** to be greater than 0 (shared resource is available), then decrements ***sem*** to claim usage of the shared resource and continues the execution of the rest of the code the RTOS task. This function allows other tasks to execute while the task waits for the shared resource to be available.
Availability:	All devices
Requires:	#USE RTOS
Examples:	`rtos_wait(uart_use)`
Also See:	rtos signal()

rtos_yield( )

The RTOS is only included in the PCW, PCWH and PCWHD software packages.

Syntax:	**rtos_yield()**
Parameters:	None
Returns:	None
Function:	This function can only be used in an RTOS task. This function stops the execution of the current task and returns control of the processor to rtos_run(). When the next task executes, it will start it's execution on the line of code after the rtos_yield().
Availability:	All devices
Requires:	#USE RTOS

Examples:	`void yield(void)`
	`{`
	`     printf("Yielding...\r\n");`
	`     rtos_yield();`
	`     printf("Executing code after yield\r\n");`
	`}`

Also See:	None

set_adc_channel( )

Syntax:	**set_adc_channel (***chan* **[,***neg***]))**
Parameters:	***chan*** is the channel number to select. Channel numbers start at 0 and are labeled in the data sheet AN0, AN1. For devices with a differential ADC it sets the positive channel to use. ***neg*** is optional and is used for devices with a differential ADC only. It sets the negative channel to use, channel numbers can be 0 to 6 or VSS. If no parameter is used the negative channel will be set to VSS by default.
Returns:	undefined
Function:	Specifies the channel to use for the next read_adc() call. Be aware that you must wait a short time after changing the channel before you can get a valid read. The time varies depending on the impedance of the input source. In general 10us is good for most applications. You need not change the channel before every read if the channel does not change.
Availability:	This function is only available on devices with A/D hardware.
Requires:	Nothing

Examples:	`set_adc_channel(2);`
	`delay_us(10);`
	`value = read_adc();`

Example Files:	ex_admm.c
Also See:	read_adc(), setup_adc(), setup_adc_ports(), ADC Overview

set_analog_pins( )

Syntax:	**set_analog_pins(**pin, pin, pin, ...**)**
Parameters:	***pin*** - pin to set as an analog pin. Pins are defined in the device's .h file. The actual value is a bit address. For example, bit 3 of port A at address 5, would have a value of 5*8+3 or 43. This is defined as follows: #define PIN_A3 43
Returns:	undefined
Function:	To set which pins are analog and digital. Usage of function depends on method device has for setting pins to analog or digital. For devices with ANSELx, x being the port letter, registers the function is used as described above. For all other devices the function works the same as setup_adc_ports() function.

	Refer to the setup_adc_ports() page for documentation on how to use.
Availability:	On all devices with an Analog to Digital Converter
Requires:	Nothing
Examples:	`set_analog_pins(PIN_A0,PIN_A1,PIN_E1,PIN_B0,PIN_B5);`
Example Files:	
Also See:	setup_adc_reference(), set_adc_channel(), read_adc(), setup_adc(), setup_adc_ports(), ADC Overview

scanf( )

Syntax:	**scanf(**cstring**);**
	scanf(cstring, values...**)**
	fscanf(stream, cstring, values...**)**

Parameters:	***cstring*** is a constant string. **values** is a list of variables separated by commas. **stream** is a stream identifier.
Returns:	0 if a failure occurred, otherwise it returns the number of conversion specifiers that were read in, plus the number of constant strings read in.
Function:	Reads in a string of characters from the standard RS-232 pins and formats the string according to the format specifiers. The format specifier character (%) used within the string indicates that a conversion specification is to be done and the value is to be saved into the corresponding argument variable. A %% will input a single %. Formatting rules for the format specifier as follows: If fscanf() is used, then the specified stream is used, where scanf() defaults to STDIN (the last USE RS232). Format: The format takes the generic form %nt. **n** is an option and may be 1-99 specifying the field width, the number of characters to be inputted. **t** is the type and maybe one of the following: **c** Matches a sequence of characters of the number specified by the field width (1 if no field width is specified). The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence. **s** Matches a sequence of non-white space characters. The

	corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.
u	Matches an unsigned decimal integer. The corresponding argument shall be a pointer to an unsigned integer.
Lu	Matches a long unsigned decimal integer. The corresponding argument shall be a pointer to a long unsigned integer.
d	Matches a signed decimal integer. The corresponding argument shall be a pointer to a signed integer.
Ld	Matches a long signed decimal integer. The corresponding argument shall be a pointer to a long signed integer.
o	Matches a signed or unsigned octal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
Lo	Matches a long signed or unsigned octal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
x or X	Matches a hexadecimal integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
Lx or LX	Matches a long hexadecimal integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
i	Matches a signed or unsigned integer. The corresponding argument shall be a pointer to a signed or unsigned integer.
Li	Matches a long signed or unsigned integer. The corresponding argument shall be a pointer to a long signed or unsigned integer.
f,g or e	Matches a floating point number in decimal or exponential format. The corresponding argument shall be a pointer to a float.
[	Matches a non-empty sequence of characters from a set of expected characters. The sequence of characters included in the set are made up of all character following the left bracket ([) up to the matching right bracket (]). Unless the first character after the left bracket is a **^**, in which case the set of characters contain all characters that do not appear between the brackets. If a **-** character is in the set and is not the first or second, where the first is a **^**, nor the last character, then the set includes all characters from the character before the **-** to the character after the **-**. For example, %[a-z] would include all characters from **a** to **z** in the set and %[^a-z] would exclude all characters from **a** to **z** from the set. The corresponding argument shall be a pointer to the initial character of an array long enough to accept the sequence and a terminating null character, which will be added automatically.
n	Assigns the number of characters read thus far by the call to scanf() to the corresponding argument. The corresponding argument shall be a pointer to an unsigned integer.

	An optional assignment-suppressing character (*****) can be used after the format specifier to indicate that the conversion specification is to be done, but not saved into a corresponding variable. In this case, no corresponding argument variable should be passed to the scanf() function. A string composed of ordinary non-white space characters is executed by reading the next character of the string. If one of the inputted characters differs from the string, the function fails and exits. If a white-space character precedes the ordinary non-white space characters, then white-space characters are first read in until a non-white space character is read. White-space characters are skipped, except for the conversion specifiers **[**, **c** or **n**, unless a white-space character precedes the **[** or **c** specifiers.
Availability:	All Devices
Requires:	#USE RS232

Examples:	`char name[2-];`
	`unsigned int8 number;`
	`signed int32 time;`
	
	`if(scanf("%u%s%ld",&number,name,&time))`
	`   printf"\r\nName: %s, Number: %u, Time: %ld",name,number,time);`

Example Files:	None
Also See:	RS232 I/O Overview, getc(), putc(), printf()

set_cog_blanking( )

Syntax:	**set_cog_blanking(falling_time, rising_time);**
Parameters:	**falling time** - sets the falling edge blanking time. **rising time** - sets the rising edge blanking time.
Returns:	Nothing
Function:	To set the falling and rising edge blanking times on the Complementary Output Generator (COG) module. The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device, refer to the device's datasheet for the correct width.

Availability:	All devices with a COG module.
Examples:	`set_cog_blanking(10,10);`
Example Files:	None
Also See:	setup_cog(), set_cog_phase(), set_cog_dead_band(), cog_status(), cog_restart()

set_cog_dead_band( )

Syntax:	**set_cog_dead_band(falling_time, rising_time);**
Parameters:	**falling time** - sets the falling edge dead-band time. **rising time** - sets the rising edge dead-band time.
Returns:	Nothing
Function:	To set the falling and rising edge dead-band times on the Complementary Output Generator (COG) module. The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device, refer to the device's datasheet for the correct width.
Availability:	All devices with a COG module.
Examples:	`set_cog_dead_band(16,32);`
Example Files:	None
Also See:	setup_cog(), set_cog_phase(), set_cog_blanking(), cog_status(), cog_restart()

set_cog_phase( )

Syntax:	**set_cog_phase(rising_time);**
	set_cog_phase(falling_time, rising_time);

Parameters:	**falling time** - sets the falling edge phase time. **rising time** - sets the rising edge phase time.
Returns:	Nothing
Function:	To set the falling and rising edge phase times on the Complementary

	Output Generator (COG) module. The time is based off the source clock of the COG module, the times are either a 4-bit or 6-bit value, depending on the device. Some devices only have a rising edge delay, refer to the device's datasheet.
Availability:	All devices with a COG module.
Examples:	`set_cog_phase(10,10);`
Example Files:	None
Also See:	setup_cog(), set_cog_dead_band(), set_cog_blanking(), cog_status(), cog_restart()

set_compare_time( )

Syntax:	**set_compare_time(***x*, **o***cr, [ocrs]***])**
Parameters:	***x*** is 1-16 and defines which output compare module to set time for ***ocr*** is the compare time for the primary compare register. ***ocrs*** is the optional compare time for the secondary register. Used for dual compare mode.
Returns:	None
Function:	This function sets the compare value for the output compare module. If the output compare module is to perform only a single compare than the ***ocrs*** register is not used. If the output compare module is using double compare to generate an output pulse, the ***ocr*** signifies the start of the pulse and ***ocrs*** defines the pulse termination time.
Availability:	Only available on devices with output compare modules.
Requires:	Nothing

Examples:	`// Pin OC1 will be set when timer 2 is equal to 0xF000`
	`setup_timer2(TMR_INTERNAL | TIMER_DIV_BY_8);`
	`setup_compare_time(1, 0xF000);`
	`setup_compare(1, COMPARE_SET_ON_MATCH | COMPARE_TIMER2);`

Example Files:	None
Also See:	get_capture( ), setup_compare( ), Output Compare, PWM Overview

set_dedicated_adc_channel( )

Syntax:	**set_dedicated_adc_channel(**core,channel, [differential]**);**
Parameters:	**core** - the dedicated ADC core to setup **channel** - the channel assigned to the specified ADC core. Channels are defined in the device's .h file as follows: • ADC_CHANNEL_AN0 • ADC_CHANNEL_AN7 • ADC_CHANNEL_PGA1 • ADC_CHANNEL_AN0ALT • ADC_CHANNEL_AN1 • ADC_CHANNEL_AN18 • ADC_CHANNEL_PGA2 • ADC_CHANNEL_AN1ALT • ADC_CHANNEL_AN2 • ADC_CHANNEL_AN11 • ADC_CHANNEL_VREF_BAND_GAP • ADC_CHANNEL_AN3 • ADC_CHANNEL_AN15 Not all of the above defines can be used with all the dedicated ADC cores. Refer to the device's header for which can be used with each dedicated ADC core. **differential** - optional parameter to specify if channel is differential or single-ended. TRUE is differential and FALSE is single-ended.
Returns:	Undefined
Function:	Sets the channel that will be assigned to the specified dedicated ADC core. Function does not set the channel that will be read with the next call to read_adc(), use set_adc_channel() or read_adc() functions to set the channel that will be read.
Availability:	On the dsPIC33EPxxGSxxx family of devices.
Requires:	Nothing.
Examples:	setup_dedicated_adc_channel(0,ADC_CHANNEL_AN0);
Example Files:	None
Also See:	setup_adc(), setup_adc_ports(), set_adc_channel(), read_adc(), adc_done(), setup_dedicated_adc(), ADC Overview

set_hspwm_duty( )

Syntax:	**setup_hspwm_duty(**duty**);**
	set_hspwm_duty(unit, primary, [secondary]**);**

Parameters:	**duty** - A 16-bit constant or variable to set the master duty cycle **unit** - The High Speed PWM unit to set. **primary** - A 16-bit constant or variable to set the primary duty cycle. **secondary** - An optional 16-bit constant or variable to set the secondary duty cycle. Secondary duty cycle is only used in Independent PWM mode. Not available on all devices, refer to device datasheet for availability.
Returns:	undefined
Function:	Sets up the specified High Speed PWM unit.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	Constants are defined in the device's .h file

Examples:	`set_hspwm_duty(0x7FFF);        //sets the High Speed PWM master duty cycle`
	`set_hspwm_duty(1, 0x3FFF);     //sets unit 1's primary duty cycle`

Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

set_hspwm_event( )   set_hspwm_event_secondary( )

Syntax:	**set_hspwm_event(**settings, compare_time**);** **set_shwpm_event_secondary(**settings, compare_time**);** **//if available**
Parameters:	**settings** - special event timer setting or'd with a value from 1 to 16 to set the prescaler. The following are the settings available for the special event time: · HSPWM_SPECIAL_EVENT_INT_ENABLED · HSPWM_SPECIAL_EVENT_INT_DISABLED

	compare_time - the compare time for the special event to occur.
Returns:	undefined
Function:	Sets up the specified High Speed PWM unit.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	Constants are defined in the device's .h file
Examples:	`set_hspwm_event(HSPWM_SPECIAL_EVENT_INT_ENABLED,0x1000);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

set_hspwm_override( )

Syntax:	**set_hspwm_override(**unit, setting**);**
Parameters:	**unit** - the High Speed PWM unit to override. **settings** - the override settings to use. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include: · HSPWM_FORCE_H_1 · HSPWM_FORCE_H_0 · HSPWM_FORCE_L_1 · HSPWM_FORCE_L_0
Returns:	Undefined
Function:	Setup and High Speed PWM uoverride settings.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None
Examples:	`setup_hspwm_override(1,HSPWM_FORCE_H_1|HSPWM_FORCE_L_0);`

Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

set_hspwm_phase( )

Syntax:	**set_hspwm_phase(**unit, primary, [secondary]**);**
Parameters:	**unit** - The High Speed PWM unit to set. **primary** - A 16-bit constant or variable to set the primary duty cycle. **secondary** - An optional 16-bit constant or variable to set the secondary duty cycle. Secondary duty cycle is only used in Independent PWM mode. Not available on all devices, refer to device datasheet for availability.
Returns:	undefined
Function:	Sets up the specified High Speed PWM unit.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	Constants are defined in the device's .h file
Examples:	`set_hspwm(1,0x1000,0x8000);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

set_nco_inc_value( )

Syntax:	**set_nco_inc_value**(value)**;**
Parameters:	**value**- value to set the NCO increment registers
Returns:	Undefined
Function:	Sets the value that the NCO's accumulator will be incremented by on each clock pulse. The increment registers are double buffered so the new value won't be applied until the accumulator rolls-over.
Availability:	On devices with a NCO module.
Examples:	`set_nco_inc_value(inc_value);       //sets the new increment value`
Example Files:	None
Also See:	setup_nco( ), get_nco_accumulator( ), get_nco_inc_value( )

set_open_drain( )

Syntax:	**set_open_drain_a(value)**
	set_open_drain_b(value)
	set_open_drain_c(value)
	set_open_drain_d(value)
	set_open_drain_e(value)
	set_open_drain_f(value)
	set_open_drain_g(value)
	set_open_drain_h(value)
	set_open_drain_j(value)
	set_open_drain_k(value)

Parameters:	**valu**e – is a bitmap corresponding to the pins of the port. Setting a bit causes the corresponding pin to act as an open-drain output.
Returns:	Nothing
Function	Enables/Disables open-drain output capability on port pins. Not all ports or port pins have open-drain capability, refer to devices datasheet for port and pin availability.
Availability	On device that have open-drain capability.
Examples:	set_open_drain_b(0x0001); //enables open-drain output on PIN_B0, disable on all //other port B pins.
Example Files:	None.

set_power_pwm_override( )

Syntax:	**set_power_pwm_override(***pwm*, *override*, *value***)**
Parameters:	***pwm*** is a constant between 0 and 7 ***Override*** is true or false ***Value*** is 0 or 1
Returns:	undefined
Function:	***pwm*** selects which module will be affected. **Override** determines whether the output is to be determined by the OVDCONS register or the PDC registers. When override is false, the PDC registers determine the output. When override is true, the output is determined by the value stored in OVDCONS. ***value*** determines if pin is driven to it's active staet or if pin will be inactive. I will be driven to its active state, 0 pin will be inactive.
Availability:	All devices equipped with PWM.
Requires:	None

Examples:	`set_power_pwm_override(1, true, 1);  //PWM1 will be`
	`//overridden to active`
	`//state`
	`set_power_pwm_override(1, false, 0); //PMW1 will not be`
	`//overidden`

Example Files:	None
Also See:	setup_power_pwm(), setup_power_pwm_pins(), set_power_pwmX_duty()

set_power_pwmx_duty( )

Syntax:	**set_power_pwm*X*_duty(***duty***)**
Parameters:	***X*** is 0, 2, 4, or 6 ***Duty*** is an integer between 0 and 16383.
Returns:	undefined
Function:	Stores the value of duty into the appropriate PDCXL/H register. This duty value is the amount of time that the PWM output is in the active state.
Availability:	All devices equipped with PWM.
Requires:	None

Examples:	`set_power_pwmx_duty(4000);`
Example Files:	None
Also See:	setup_power_pwm(), setup_power_pwm_pins(), set_power_pwm_override()

set_pulldown( )

Syntax:	**set_Pulldown(state [, pin])**
Parameters:	**Pins** are defined in the devices .h file. If no pin is provided in the function call, then all of the pins are set to the passed in state. **State** is either true or false.
Returns:	undefined
Function:	Sets the pin's pull down state to the passed in state value. If no pin is included in the function call, then all valid pins are set to the passed in state.
Availability:	All devices that have pull-down hardware.
Requires:	Pin constants are defined in the devices .h file.

Examples:	`set_pulldown(true, PIN_B0);`
	`    //Sets pin B0's pull down state to true`
	
	`         set_pullup(false);`
	`    //Sets all pin's pull down state to false`

Example Files:	None
Also See:	None

set_pullup( )

Syntax:	set_Pullup(state, [pin])
Parameters:	Pins are defined in the devices .h file. If no pin is provided in the function call, then all of the pins are set to the passed in state.

	State is either true or false. Pins are defined in the devices .h file. The actual number is a bit address. For example, port a (byte 5) bit 3 would have a value of 5*8+3 or 43. This is defined as follows: #DEFINE PIN_A3 43 . The pin could also be a variable that has a value equal to one of the predefined pin constants. Note if no pin is provided in the function call, then all of the pins are set to the passed in state. **State** is either true or false.
Returns:	undefined
Function:	Sets the pin's pull up state to the passed in state value. If no pin is included in the function call, then all valid pins are set to the passed in state.
Availability:	All devices.
Requires:	Pin constants are defined in the devices .h file.

Examples:	`set_pullup(true, PIN_B0);`
	`    //Sets pin B0's pull up state to true`
	
	`         set_pullup(false);`
	`    //Sets all pin's pull up state to false`

Example Files:	None
Also See:	None

set_pwm1_duty( ) set_pwm2_duty( ) set_pwm3_duty( ) set_pwm4_duty( ) set_pwm5_duty( )

Syntax:	**set_pwm1_duty (***value***)** **set_pwm2_duty (***value***)** **set_pwm3_duty (***value***)** **set_pwm4_duty (***value***)** **set_pwm5_duty (***value***)**
Parameters:	***value*** may be an 8 or 16 bit constant or variable.
Returns:	undefined
Function:	Writes the 10-bit value to the PWM to set the duty. An 8-bit value may be used if the most significant bits are not required. The 10 bit value is then used to determine the duty cycle of the PWM signal as follows:

	•□ duty cycle = value / [4 * (PR2 +1)] If an 8-bit value is used, the duty cycle of the PWM signal is determined as follows: •□ duty cycle=value/(PR2+1) Where PR2 is the maximum value timer 2 will count to before toggling the output pin.
Availability:	This function is only available on devices with CCP/PWM hardware.
Requires:	None

Examples:	`// For a 20 mhz clock, 1.2 khz frequency,`
	`// t2DIV set to 16, PR2 set to 200`
	`// the following sets the duty to 50% (or 416 us).`
	
	`long duty;`
	
	`duty = 408; // [408/(4*(200+1))]=0.5=50%`
	`set_pwm1_duty(duty);`

Example Files:	ex_pwm.c
Also See:	setup_ccpX(), set_ccpX_compare_time(), set_timer_period_ccpX(), set_timer_ccpX(), get_timer_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

set_pwm1_offset( ) set_pwm2_offset( ) set_pwm3_offset( ) set_pwm4_offset( ) set_pwm5_offset( ) set_pwm6_offset( )

Syntax:	**set_pwm1_offset (***value***)** **set_pwm2_offset (***value***)** **set_pwm3_offset (***value***)** **set_pwm4_offset (***value***)** **set_pwm5_offset (***value***)** **set_pwm6_offset (***value***)**
Parameters:	***value*** - 16-bit constant or variable.
Returns:	undefined.
Function:	Writes the 16-bit to the PWM to set the offset. The offset is used to adjust the waveform of a slae PWM module relative to the waveform of a master PWM module.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`set_pwm1_offset(0x0100);`
	`set_pwm1_offset(offset);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_period(), clear_pwm_interrupt(), set_pwm_phase(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

set_pwm1_period( ) set_pwm2_period( ) set_pwm3_period( ) set_pwm4_period( ) set_pwm5_period( ) set_pwm6_period( )

Syntax:	**set_pwm1_period (***value***)** **set_pwm2_period (***value***)** **set_pwm3_period (***value***)** **set_pwm4_period (***value***)** **set_pwm5_period (***value***)** **set_pwm6_period (***value***)**
Parameters:	***value*** - 16-bit constant or variable.
Returns:	undefined.
Function:	Writes the 16-bit to the PWM to set the period. When the PWM module is set-up for standard mode it sets the period of the PWM signal. When set-up for set on match mode, it sets the maximum value at which the phase match can occur. When in toggle on match and center aligned modes it sets the maximum value the PWMxTMR will count to, the actual period of PWM signal will be twice what the period was set to.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`set_pwm1_period(0x8000);`
	`set_pwm1_period(period);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_phase(), clear_pwm_interrupt(), set_pwm_offset(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

set_pwm1_phase( ) set_pwm2_phase( ) set_pwm3_phase( ) set_pwm4_phase( ) set_pwm5_phase( ) set_pwm6_phase( )

Syntax:	**set_pwm1_phase (***value***)** **set_pwm2_phase (***value***)** **set_pwm3_phase (***value***)** **set_pwm4_phase (***value***)** **set_pwm5_phase (***value***)** **set_pwm6_phase (***value***)**
Parameters:	***value*** - 16-bit constant or variable.
Returns:	undefined.
Function:	Writes the 16-bit to the PWM to set the phase. When the PWM module is set-up for standard mode the phaes specifies the start of the duty cycle, when in set on match mode it specifies when the output goes high, and when in toggle on match mode it specifies when the output toggles. Phase is not used when in center aligned mode.
Availability:	Devices with a 16-bit PWM module.
Requires:	Nothing

Examples:	`set_pwm1_phase(0);`
	`set_pwm1_phase(phase);`

Example Files:	
Also See:	setup_pwm(), set_pwm_duty(), set_pwm_period(), clear_pwm_interrupt(), set_pwm_offset(), enable_pwm_interrupt(), disable_pwm_interrupt(), pwm_interrupt_active()

set_open_drain_x()

Syntax:	**set_open_drain_a(**value**)**
	set_open_drain_b(value**)**
	set_open_drain_v(value**)**
	set_open_drain_d(value**)**
	set_open_drain_e(value**)**
	set_open_drain_f(value**)**
	set_open_drain_g(value**)**
	set_open_drain_h(value**)**
	set_open_drain_j(value**)**
	set_open_drain_k(value**)**

Parameters:	**value** is an 16-bit int with each bit representing a bit of the I/O port.
Returns:	undefined
Function:	These functions allow the I/O port Open-Drain Control (ODC) registers to be set. Each bit

	in the value represents one pin. A 1 sets the corresponding pin to act as an open-drain output, and a 0 sets the corresponding pin to act as a digital output.
Availability:	All devices with ODC registers, however not all devices have all I/O ports and not all devices port's have a corresponding ODC register.
Requires:	Nothing
Examples:	`set_open_drain_a(0x0001);    //makes PIN_A0 an open-drain output`
Example Files:	None
Also See:	output_high(), output_low(), output_bit(), output_x(), General Purpose I/O

set_rtcc( ) set_timer0( ) set_timer1( ) set_timer2( ) set_timer3( ) set_timer4( ) set_timer5( )

Syntax:	**set_timer0(value) or set_rtcc (value)**
	set_timer1(value)
	set_timer2(value)
	set_timer3(value)
	set_timer4(value)
	set_timer5(value)

Parameters:	Timers 1 & 5 get a 16 bit int. Timer 2 and 4 gets an 8 bit int. Timer 0 (AKA RTCC) gets an 8 bit int except on the PIC18XXX where it needs a 16 bit int. Timer 3 is 8 bit on PIC16 and 16 bit on PIC18
Returns:	undefined
Function:	Sets the count value of a real time clock/counter. RTCC and Timer0 are the same. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2...)
Availability:	Timer 0 - All devices Timers 1 & 2 - Most but not all PCM devices Timer 3 - Only PIC18XXX and some pick devices Timer 4 - Some PCH devices Timer 5 - Only PIC18XX31
Requires:	Nothing

Examples:	`// 20 mhz clock, no prescaler, set timer 0`
	`// to overflow in 35us`
	
	`set_timer0(81);        // 256-(.000035/(4/20000000))`

Example Files:	ex_patg.c

Also See:	set_timer1(), get_timerX() Timer0 Overview, Timer1Overview, Timer2 Overview, Timer5 Overview

set_ticks( )

Syntax:	**set_ticks([**stream**],**value**);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE TIMER **value** – a 8, 16 or 32 bit integer, specifying the new value of the tick timer. (int8, int16 or int32)
Returns:	void
Function:	Sets the new value of the tick timer. Size passed depends on the size of the tick timer.
Availability:	All devices.
Requires:	#USE TIMER(options)

Examples:	`#USE TIMER(TIMER=1,TICK=1ms,BITS=16,NOISR)`
	
	`void main(void) {`
	`   unsigned int16 value = 0x1000;`
	
	`   set_ticks(value);`
	`}`

Example Files:	None
Also See:	#USE TIMER, get_ticks()

setup_sd_adc_calibration( )

Syntax:	**setup_sd_adc_calibration(model);**
Parameters:	***mode***- selects whether to enable or disable calibration mode for the SD ADC module. The following defines are made in the device's *.h* file: 1 SDADC_START_CALIBRATION_MODE 2 SDADC_END_CALIBRATION_MODE
Returns:	Nothing
Function:	To enable or disable calibration mode on the Sigma-Delta Analog to Digital Converter (SD ADC) module. This can be used to determine the offset error of the module, which then can be subtracted from future readings.

Availability:	Only devices with a SD ADC module.

Examples:	signed int 32 result, calibration;
	
	set_sd_adc_calibration(SDADC_START_CALIBRATION_MODE);
	calibration = read_sd_adc();
	set_sd_adc_calibration(SDADC_END_CALIBRATION_MODE);
	
	result = read_sd_adc() - calibration;

Example Files:	None
Also See:	setup_sd_adc(), read_sd_adc(), set_sd_adc_channel()

set_sd_adc_channel( )

Syntax:	**setup_sd_adc(channel);**
Parameters:	***channel***- sets the SD ADC channel to read. Channel can be 0 to read the difference between CH0+ and CH0-, 1 to read the difference between CH1+ and CH1-, or one of the following: 1 SDADC_CH1SE_SVSS 2 SDADC_REFERENCE
Returns:	Nothing
Function:	To select the channel that the Sigma-Delta Analog to Digital Converter (SD ADC) performs the conversion on.
Availability:	Only devices with a SD ADC module.
Examples:	set_sd_adc_channel(0);
Example Files:	None
Also See:	setup_sd_adc(), read_sd_adc(), set_sd_adc_calibration()

set_timerA( )

Syntax:	**set_timerA(**value**);**
Parameters:	An 8 bit integer. Specifying the new value of the timer. (int8)

Returns:	undefined
Function:	Sets the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, …).
Availability:	This function is only available on devices with Timer A hardware.
Requires:	Nothing

Examples:	`// 20 mhz clock, no prescaler, set timer A`
	`// to overflow in 35us`
	
	`set_timerA(81); // 256-(.000035/(4/20000000))`

Example Files:	none
Also See:	get_timerA( ), setup_timer_A( ), TimerA Overview

set_timerB( )

Syntax:	**set_timerB(**value**);**
Parameters:	An 8 bit integer. Specifying the new value of the timer. (int8)
Returns:	undefined
Function:	Sets the current value of the timer. All timers count up. When a timer reaches the maximum value it will flip over to 0 and continue counting (254, 255, 0, 1, 2, …).
Availability:	This function is only available on devices with Timer B hardware.
Requires:	Nothing

Examples:	`// 20 mhz clock, no prescaler, set timer B`
	`// to overflow in 35us`
	
	`set_timerB(81); // 256-(.000035/(4/20000000))`

Example Files:	none
Also See:	get_timerB( ), setup_timer_B( ), TimerB Overview

set_timerx( )

Syntax:	**set_timerX(*value*)**
Parameters:	A 16 bit integer, specifiying the new value of the timer. (int16)
Returns:	void
Function:	Allows the user to set the value of the timer.
Availability:	This function is available on all devices that have a valid timerX.
Requires:	Nothing

Examples:	`if(EventOccured())`
	`      set_timer2(0);//reset the timer.`

Example Files:	None
Also See:	Timer Overview, set_timerX()

set_tris_x( )

Syntax:	**set_tris_a (*value*)** **set_tris_b (*value*)** **set_tris_c (*value*)** **set_tris_d (*value*)** **set_tris_e (*value*)** **set_tris_f (*value*)** **set_tris_g (*value*)** **set_tris_h (*value*)** **set_tris_j (*value*)** **set_tris_k (*value*)**
Parameters:	***value*** is an 8 bit int with each bit representing a bit of the I/O port.
Returns:	undefined
Function:	These functions allow the I/O port direction (TRI-State) registers to be set. This must be used with FAST_IO and when I/O ports are accessed as memory such as when a # BYTE directive is used to access an I/O port. Using the default standard I/O the built in functions set the I/O direction automatically. Each bit in the value represents one pin. A 1 indicates the pin is input and a 0 indicates it is output.
Availability:	All devices (however not all devices have all I/O ports)

Requires:	Nothing

Examples:	`SET_TRIS_B( 0x0F );`
	`   // B7,B6,B5,B4 are outputs`
	`   // B3,B2,B1,B0 are inputs`

Example Files:	lcd.c
Also See:	#USE FAST_IO, #USE FIXED_IO, #USE STANDARD_IO, General Purpose I/O

set_uart_speed( )

Syntax:	**set_uart_speed (***baud***, [***stream, clock***])**
Parameters:	***baud*** is a constant representing the number of bits per second. ***stream*** is an optional stream identifier. ***clock*** is an optional parameter to indicate what the current clock is if it is different from the #use delay value
Returns:	undefined
Function:	Changes the baud rate of the built-in hardware RS232 serial port at run-time.
Availability:	This function is only available on devices with a built in UART.
Requires:	#USE RS232
Examples:	see below
Example Files:	loader.c
Also See:	#USE RS232, putc(), getc(), setup uart(), RS232 I/O Overview,

Examples:

```
// Set baud rate based on setting
// of pins B0 and B1

switch( input_b() & 3 ) {
   case 0 : set_uart_speed(2400);   break;
   case 1 : set_uart_speed(4800);   break;
   case 2 : set_uart_speed(9600);   break;
   case 3 : set_uart_speed(19200);  break;
}
```

setjmp( )

Syntax:	**result = setjmp (*env*)**
Parameters:	***env***: The data object that will receive the current environment
Returns:	If the return is from a direct invocation, this function returns 0. If the return is from a call to the longjmp function, the setjmp function returns a nonzero value and it's the same value passed to the longjmp function.
Function:	Stores information on the current calling context in a data object of type jmp_buf and which marks where you want control to pass on a corresponding longjmp call.
Availability:	All devices
Requires:	#INCLUDE <setjmp.h>
Examples:	`result = setjmp(jmpbuf);`
Example Files:	None
Also See:	longjmp()

setup_adc(mode)

Syntax:	**setup_adc (*mode*);**
	setup_adc2(*mode*);

Parameters:	***mode***- Analog to digital mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include: • ADC_OFF • ADC_CLOCK_INTERNAL • ADC_CLOCK_DIV_32
Returns:	undefined
Function:	Configures the analog to digital converter.
Availability:	Only the devices with built in analog to digital converter.
Requires:	Constants are defined in the devices .h file.

Examples:	`setup_adc_ports( ALL_ANALOG );`
	`setup_adc(ADC_CLOCK_INTERNAL );`
	`set_adc_channel( 0 );`
	`value = read_adc();`
	`setup_adc( ADC_OFF );`

Example Files:	ex_admm.c
Also See:	setup_adc_ports(), set_adc_channel(), read_adc(), #DEVICE, ADC Overview, see header file for device selected

setup_adc_ports( )

Syntax:	**setup_adc_ports (***value***)** **setup_adc_ports (***ports, [reference]***)**
Parameters:	***value*** - a constant defined in the devices .h file ***ports*** - is a constant specifying the ADC pins to use ***reference*** - is an optional constant specifying the ADC reference to use By default, the reference voltage are Vss and Vdd
Returns:	undefined
Function:	Sets up the ADC pins to be analog, digital, or a combination and the voltage reference to use when computing the ADC value. The allowed analog pin combinations vary depending on the chip and are defined by using the bitwise OR to concatenate selected pins together. Check the device include file for a complete list of available pins and reference voltage settings. The constants ALL_ANALOG and NO_ANALOGS are valid for all chips. Some other example pin definitions are:
Also See:	setup_adc(), read_adc(), set_adc_channel(), ADC Overview

setup_adc_reference( )

Syntax:	**setup_adc_reference(**reference**)**
Parameters:	**reference** - the voltage reference to set the ADC. The valid options depend on the device, see the device's .h file for all options. Typical options include: · VSS_VDD · VSS_VREF · VREF_VREF · VREF_VDD
Returns:	undefined
Function:	To set the positive and negative voltage reference for the Analog to Digital Converter (ADC) uses.
Availability:	Only on devices with an ADC and has ANSELx, x being the port letter, registers for setting which pins are analog or digital.

Requires:	Nothing
Examples:	`set_adc_reference(VSS_VREF);`
Example Files:	
Also See:	set_analog_pins(), set_adc_channel(), read_adc(), setup_adc(), setup_adc_ports(), ADC Overview

setup_at( )

Syntax:	**setup_at(**settings);
Parameters:	**settings** - the setup of the AT module. See the device's header file for all options. Some typical options include: · AT_ENABLED · AT_DISABLED · AT_MULTI_PULSE_MODE · AT_SINGLE_PULSE_MODE
Returns:	Nothing
Function:	To setup the Angular Timer (AT) module.
Availability:	All devices with an AT module.
Requires:	Constants defined in the device's .h file
Examples:	`setup_at(AT_ENABLED|AT_MULTI_PULSE_MODE|AT_INPUT_ATIN);`
Example Files:	None
Also See:	at_set_resolution(), at_get_resolution(), at_set_missing_pulse_delay(), at_get_missing_pulse_delay(), at_get_period(), at_get_phase_counter(), at_set_set_point(), at_get_set_point(), at_get_set_point_error(), at_enable_interrupts(), at_disable_interrupts(), at_clear_interrupts(), at_interrupt_active(), at_setup_cc(), at_set_compare_time(), at_get_capture(), at_get_status()

setup_ccp1( ) setup_ccp2( ) setup_ccp3( ) setup_ccp4( ) setup_ccp5( ) setup_ccp6( )

Syntax:	**setup_ccp1 (***mode***)** **or setup_ccp1 (***mode, pwm***)**

	setup_ccp2 (*mode***)** **or setup_ccp2 (***mode, pwm***)** **setup_ccp3 (***mode***)** **or setup_ccp3 (***mode, pwm***)** **setup_ccp5 (***mode***)** **or setup_ccp5 (***mode, pwm***)** **setup_ccp6 (***mode***)** **or setup_ccp6 (***mode, pwm***)**
Parameters:	***mode*** is a constant. Valid constants are defined in the devices .h file and refer to devices .h file for all options, some options are as follows:

Disable the CCP:

CCP_OFF

Set CCP to capture mode:

CCP_CAPTURE_FE	**Capture on falling edge**
CCP_CAPTURE_RE	Capture on rising edge
CCP_CAPTURE_DIV_4	Capture after 4 pulses
CCP_CAPTURE_DIV_16	Capture after 16 pulses

Set CCP to compare mode:

CCP_COMPARE_SET_ON_MATCH	**Output high on compare**
CCP_COMPARE_CLR_ON_MATCH	Output low on compare
CCP_COMPARE_INT	interrupt on compare
CCP_COMPARE_RESET_TIMER	Reset timer on compare

Set CCP to PWM mode:

CCP_PWM	**Enable Pulse Width Modulator**

Constants used for ECCP modules are as follows:

CCP_PWM_H_H	
CCP_PWM_H_L	
CCP_PWM_L_H	
CCP_PWM_L_L	
CCP_PWM_FULL_BRIDGE	
CCP_PWM_FULL_BRIDGE_REV	
CCP_PWM_HALF_BRIDGE	
CCP_SHUTDOWN_ON_COMP1	shutdown on Comparator 1 change
CCP_SHUTDOWN_ON_COMP2	shutdown on Comparator 2 change
CCP_SHUTDOWN_ON_COMP	Either Comp. 1 or 2 change
CCP_SHUTDOWN_ON_INT0	VIL on INT pin
CCP_SHUTDOWN_ON_COMP1_INT0	VIL on INT pin or Comparator 1 change
CCP_SHUTDOWN_ON_COMP2_INT0	VIL on INT pin or Comparator 2 change
CCP_SHUTDOWN_ON_COMP_INT0	VIL on INT pin or Comparator 1 or 2 change
CCP_SHUTDOWN_AC_L	Drive pins A and C high
CCP_SHUTDOWN_AC_H	Drive pins A and C low
CCP_SHUTDOWN_AC_F	Drive pins A and C tri-state
CCP_SHUTDOWN_BD_L	Drive pins B and D high
CCP_SHUTDOWN_BD_H	Drive pins B and D low

	CCP_SHUTDOWN_BD_F Drive pins B and D tri-state **CCP_SHUTDOWN_RESTART** the device restart after a shutdown event **CCP_DELAY** use the dead-band delay ***pwm*** parameter is an optional parameter for chips that includes ECCP module. This parameter allows setting the shutdown time. The value may be 0-255.
Returns:	Undefined
Function:	Initialize the CCP. The CCP counters may be accessed using the long variables CCP_1 and CCP_2. The CCP operates in 3 modes. In capture mode it will copy the timer 1 count value to CCP_x when the input pin event occurs. In compare mode it will trigger an action when timer 1 and CCP_x are equal. In PWM mode it will generate a square wave. The PCW wizard will help to set the correct mode and timer settings for a particular application.
Availability:	This function is only available on devices with CCP hardware.
Requires:	Constants are defined in the devices .h file.
Examples:	`setup_ccp1(CCP_CAPTURE_RE);`
Example Files:	ex_pwm.c, ex_ccpmp.c, ex_ccp1s.c
Also See:	set_pwmX_duty(), set_ccpX_compare_time(), set_timer_period_ccpX(), set_timer_ccpX(), get_timer_ccpX(), get_capture_ccpX(), get_captures32_ccpX()

setup_clc1() setup_clc2() setup_clc3() setup_clc4()

Syntax:	setup_clc1(mode);
	setup_clc2(mode);
	setup_clc3(mode);
	setup_clc4(mode);

Parameters:	**mode** – The mode to setup the Configurable Logic Cell (CLC) module into. See the device's .h file for all options. Some typical options include: CLC_ENABLED CLC_OUTPUT CLC_MODE_AND_OR CLC_MODE_OR_XOR
Returns:	Undefined.
Function:	Sets up the CLC module to performed the specified logic. Please refer to the device datasheet to determine what each input to the CLC module does for the select logic function

Availability:	On devices with a CLC module.
Returns:	Undefined.
Examples:	`setup_clc1(CLC_ENABLED | CLC_MODE_AND_OR);`
Example Files:	None
Also See:	clcx_setup_gate(), clcx_setup_input()

setup_comparator( )

Syntax:	**setup_comparator (*mode*)**
Parameters:	***mode*** is a constant. Valid constants are in the devices .h file refer to devices .h file for valid options. Some typical options are as follows: A0_A3_A1_A2 A0_A2_A1_A2 NC_NC_A1_A2 NC_NC_NC_NC A0_VR_A1_VR A3_VR_A2_VR A0_A2_A1_A2_OUT_ON_A3_A4 A3_A2_A1_A2
Returns:	undefined
Function:	Sets the analog comparator module. The above constants have four parts representing the inputs: C1-, C1+, C2-, C2+
Availability:	This function is only available on devices with an analog comparator.
Requires	Constants are defined in the devices .h file.

Examples:	`// Sets up two independent comparators (C1 and C2),`
	`// C1 uses A0 and A3 as inputs (- and +), and C2`
	`// uses A1 and A2 as inputs`
	`setup_comparator(A0_A3_A1_A2);`

Example Files:	ex_comp.c
Also See:	Analog Comparator overview

setup_counters( )

Syntax:	**setup_counters (***rtcc_state***,** *ps_state***)**
Parameters:	***rtcc_state*** may be one of the constants defined in the devices .h file. For example: RTCC_INTERNAL, RTCC_EXT_L_TO_H or RTCC_EXT_H_TO_L ***ps_state*** may be one of the constants defined in the devices .h file. For example: RTCC_DIV_2, RTCC_DIV_4, RTCC_DIV_8, RTCC_DIV_16, RTCC_DIV_32, RTCC_DIV_64, RTCC_DIV_128, RTCC_DIV_256, WDT_18MS, WDT_36MS, WDT_72MS, WDT_144MS, WDT_288MS, WDT_576MS, WDT_1152MS, WDT_2304MS
Returns:	undefined
Function:	Sets up the RTCC or WDT. The rtcc_state determines what drives the RTCC. The PS state sets a prescaler for either the RTCC or WDT. The prescaler will lengthen the cycle of the indicated counter. If the RTCC prescaler is set the WDT will be set to WDT_18MS. If the WDT prescaler is set the RTCC is set to RTCC_DIV_1. This function is provided for compatibility with older versions. setup_timer_0 and setup_WDT are the recommended replacements when possible. For PCB devices if an external RTCC clock is used and a WDT prescaler is used then this function must be used.
Availability:	All devices
Requires:	Constants are defined in the devices .h file.
Examples:	`setup_counters (RTCC_INTERNAL, WDT_2304MS);`
Example Files:	None
Also See:	setup wdt(), setup_timer 0(), see header file for device selected

setup_cog( )

Syntax:	**setup_cog(**mode, [shutdown]**);**
	setup_cog(mode, [shutdown], [sterring]);

Parameters:	**mode**- the setup of the COG module. See the device's .h file for all options. Some typical options include: • COG_ENABLED

	• COG_DISABLED • COG_CLOCK_HFINTOSC • COG_CLOCK_FOSC **shutdown**- the setup for the auto-shutdown feature of COG module. See the device's .h file for all the options. Some typical options include: • COG_AUTO_RESTART • COG_SHUTDOWN_ON_C1OUT • COG_SHUTDOWN_ON_C2OUT **steering**- optional parameter for steering the PWM signal to COG output pins and/or selecting the COG pins static level. Used when COG is set for steered PWM or synchronous steered PWM modes. Not available on all devices, see the device's .h file if available and for all options. Some typical options include: • COG_PULSE_STEERING_A • COG_PULSE_STEERING_B • COG_PULSE_STEERING_C • COG_PULSE_STEERING_D
Returns:	undefined
Function:	Sets up the Complementary Output Generator (COG) module, the auto-shutdown feature of the module and if available steers the signal to the different output pins.
Availability:	All devices with a COG module.

Examples:	`setup_cog(COG_ENABLED | COG_PWM | COG_FALLING_SOURCE_PWM3 |`
	`COG_RISING_SOURCE_PWM3, COG_NO_AUTO_SHUTDOWN,`
	`COG_PULSE_STEERING_A | COG_PULSE_STEERING_B);`

Example Files:	None
Also See:	set_cog_dead_band(), set_cog_phase(), set_cog_blanking(), cog_status(), cog_restart()

setup_crc( )

Syntax:	**setup_crc(**polynomial terms**)**
Parameters:	**polynomial**- This will setup the actual polynomial in the CRC engine. The power of each term is passed separated by a comma. 0 is allowed, but ignored. The following define is added to the device's header file to enable little-endian shift direction: CRC_LITTLE_ENDIAN

Returns:	Nothing
Function:	Configures the CRC engine register with the polynomial.
Availability:	Only devices with a built-in CRC module.
Examples:	`setup_crc(12, 5);` // CRC Polynomial is $x^{12}+x^5+1$ `setup_crc(16, 15, 3, 1);` // CRC Polynomial is $x^{16}+x^{15}+x^3+x^1+1$
Example Files:	None
Also See:	crc_init(), crc_calc(), crc_calc8()

setup_cwg( )

Syntax:	**setup_cwg(**mode**,**shutdown**,**dead_time_rising**,**dead_time_falling**)**
Parameters:	**mode**- the setup of the CWG module. See the device's .h file for all options. Some typical options include: • CWG_ENABLED • CWG_DISABLED • CWG_OUTPUT_B • CWG_OUTPUT_A **shutdown**- the setup for the auto-shutdown feature of CWG module. See the device's .h file for all the options. Some typical options include: CWG_AUTO_RESTART CWG_SHUTDOWN_ON)COMP1 CWG_SHUTDOWN_ON_FLT CWG_SHUTDOWN_ON_CLC2 **dead_time_rising**- value specifying the dead time between A and B on the rising edge. (0-63) **dead_time_rising**- value specifying the dead time between A and B on the falling edge. (0-63)
Returns:	undefined
Function:	Sets up the CWG module, the auto-shutdown feature of module and the rising and falling dead times of the module.
Availability:	All devices with a CWG module.
Examples:	`setup_cwg(CWG_ENABLED|CWG_OUTPUT_A|CWG_OUTPUT_B|`

	`CWG_INPUT_PWM1,CWG_SHUTDOWN_ON_FLT,60,30);`
Example Files:	None
Also See:	cwg_status( ), cwg_restart( )

setup_dac( )

Syntax:	**setup_dac(mode);**
Parameters:	***mode-*** The valid options vary depending on the device. See the devices .h file for all options. Some typical options include: · DAC_OUTPUT
Returns:	undefined
Function:	Configures the DAC including reference voltage.
Availability:	Only the devices with built in digital to analog converter.
Requires:	Constants are defined in the devices .h file.

Examples:	`setup_dac(DAC_VDD | DAC_OUTPUT);`
	`dac_write(value);`

Example Files:	None
Also See:	dac_write( ), DAC Overview, See header file for device selected

setup_dedicated_adc( )

Syntax:	**setup_dedicated_adc(**core, mode**);**
Parameters:	**core** - the dedicated ADC core to setup **mode** - the mode to setup the dedicated ADC core in. See the device's .h file all options. Some typical options include:

	• ADC_DEDICATED_CLOCK_DIV_2 • ADC_DEDICATED_CLOCK_DIV_6 • ADC_DEDICATED_TAD_MUL_2 • ADC_DEDICATED_TAD_MUL_3
Returns:	Undefined
Function:	Configures one of the dedicated ADC core's clock speed and sample time. Function should be called after the setup_adc() function.
Availability:	On the dsPIC33EPxxGSxxx family of devices.
Requires:	Nothing.
Examples:	setup_dedicated_adc(0,ADC_DEDICATED_CLOCK_DIV_2 | ADC_DEDICATED_TAD_MUL_1025);
Example Files:	None
Also See:	setup_adc(), setup_adc_ports(), set_adc_channel(), read_adc(), adc_done(), set_dedicated_adc_channel(), ADC Overview

setup_external_memory( )

Syntax:	**SETUP_EXTERNAL_MEMORY(** *mode* **);**
Parameters:	***mode*** is one or more constants from the device header file OR'ed together.
Returns:	undefined
Function:	Sets the mode of the external memory bus.
Availability:	Only devices that allow external memory.
Requires:	Constants are defined in the device.h file

Examples:	`setup_external_memory(EXTMEM_WORD_WRITE`
	`                      |EXTMEM_WAIT_0 );`
	`setup_external_memory(EXTMEM_DISABLE);`

Example Files:	None
Also See:	WRITE PROGRAM EEPROM() , WRITE PROGRAM MEMORY(), External Memory Overview

setup_high_speed_adc( )

Syntax:	**setup_high_speed_adc (***mode***);**
Parameters:	**mode** – Analog to digital mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include: ▪ ADC_OFF ▪ ADC_CLOCK_DIV_1 ▪ ADC_HALT_IDLE – The ADC will not run when PIC is idle.
Returns:	Undefined
Function:	Configures the High-Speed ADC clock speed and other High-Speed ADC options including, when the ADC interrupts occurs, the output result format, the conversion order, whether the ADC pair is sampled sequentially or simultaneously, and whether the dedicated sample and hold is continuously sampled or samples when a trigger event occurs.
Availability:	Only on dsPIC33FJxxGSxxx devices.
Requires:	Constants are define in the device .h file.

Examples:	`setup_high_speed_adc_pair(0, INDIVIDUAL_SOFTWARE_TRIGGER);`
	`setup_high_speed_adc(ADC_CLOCK_DIV_4);`
	`read_high_speed_adc(0, START_AND_READ, result);`
	`setup_high_speed_adc(ADC_OFF);`

Example Files:	None
Also See:	setup_high_speed_adc_pair(), read_high_speed_adc(), high_speed_adc_done()

setup_high_speed_adc_pair( )

Syntax:	**setup_high_speed_adc_pair(***pair, mode***);**
Parameters:	**pair** – The High-Speed ADC pair number to setup, valid values are 0 to total number of ADC pairs. 0 sets up ADC pair AN0 and AN1, 1 sets up ADC pair AN2 and AN3, etc. **mode** – ADC pair mode. The valid options vary depending on the device. See the devices .h file for all options. Some typical options include: ▪ INDIVIDUAL_SOFTWARE_TRIGGER ▪ GLOBAL_SOFTWARE_TRIGGER ▪ PWM_PRIMARY_SE_TRIGGER ▪ PWM_GEN1_PRIMARY_TRIGGER ▪ PWM_GEN2_PRIMARY_TRIGGER
Returns:	Undefined

Function:	Sets up the analog pins and trigger source for the specified ADC pair. Also sets up whether ADC conversion for the specified pair triggers the common ADC interrupt. If zero is passed for the second parameter the corresponding analog pins will be set to digital pins.
Availability:	Only on dsPIC33FJxxGSxxx devices.
Requires:	Constants are define in the device .h file.

Examples:	`setup_high_speed_adc_pair(0, INDIVIDUAL_SOFTWARE_TRIGGER);`
	
	`setup_high_speed_adc_pair(1, GLOBAL_SOFTWARE_TRIGGER);`
	
	`setup_high_speed_adc_pair(2, 0) – sets AN4 and AN5 as digital pins.`

Example Files:	None
Also See:	setup_high_speed_adc(), read_high_speed_adc(), high_speed_adc_done()

setup_hspwm_blanking( )

Syntax:	**setup_hspwm_blanking(**unit, settings, delay**);**
Parameters:	**unit** - The High Speed PWM unit to set. **start_delay** - Optional value from 0 to 63 specifying then umber of PWM cycles to wait before generating the first trigger event. For some devices, one of the following may be optional or'd in with the value: · HSPWM_COMBINE_PRIMARY_AND_SECONDARY_TRIGGER · HSPWM_SEPERATE_PRIMARY_AND_SECONDARY_TRIGGER **divider** - optional value from 1 to 16 specifying the trigger event divisor. **trigger_value** - optional 16-bit value specifying the primary trigger compare time. **strigger_value** - optional 16-bit value specifying the secondary trigger compare time. Not available on all devices, see the device datasheet for availability.
Returns:	undefined
Function:	Sets up the High Speed PWM Trigger event.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None

Examples:	`setup_hspwm_trigger(1, 10, 1, 0x2000);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

setup_hspwm_chop_clock( )

Syntax:	**setup_hspwm_chop_clock(**settings**);**
Parameters:	**settings** - a value from 1 to 1024 to set the chop clock divider. Also one of the following can be or'd with the value: · HSPWM_CHOP_CLK_GENERATOR_ENABLED · HSPWM_CHOP_CLK_GENERATOR_DISABLED
Returns:	Undefined
Function:	Setup and High Speed PWM Chop Clock Generator and divisor.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None
Examples:	`setup_hspwm_chop_clock(HSPWM_CHOP_CLK_GENERATOR_ENABLED|32);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

setup_hspwm_trigger( )

Syntax:	**setup_hspwm_trigger(**unit, [start_ delay], [divider], [trigger_value], [strigger_value]**);**
Parameters:	**unit** - The High Speed PWM unit to set. **settings** - Settings to setup the High Speed PWM Leading-Edge Blanking. The valid options vary depending on the device. See the device's header file for all options. Some typical options include: · HSPWM_RE_PWMH_TRIGGERS_LE_BLANKING · HSPWM_FE_PWMH_TRIGGERS_LE_BLANKING · HSPWM_RE_PWML_TRIGGERS_LE_BLANKING · HSPWM_FE_PWML_TRIGGERS_LE_BLANKING · HSPWM_LE_BLANKING_APPLIED_TO_FAULT_INPUT · HSPWM_LE_BLANKING_APPLIED_TO_CURRENT_LIMIT_INPUT **delay** - 16-bit constant or variable to specify the leading-edge blanking time.
Returns:	undefined
Function:	Sets up the Leading-Edge Blanking and leading-edge blanking time of the High Speed PWM.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None
Examples:	`setup_hspwm_blanking(HSPWM_RE_PWMH_TRIGGERS_LE_BLANKING, 10);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

setup_hspwm_unit( )

Syntax:	**setup_hspwm_unit(**unit, mode, [dead_time], [alt_dead_time]**);**
	set_hspwm_duty(unit, primary, [secondary]**);**

Parameters:	**unit** - The High Speed PWM unit to set.

	mode - Mode to setup the High Speed PWM unit in. The valid option vary depending on the device. See the device's header file for all options. Some typical options include: · HSPWM_ENABLE · HSPWM_ENABLE_H · HSPWM_ENABLE_L · HSPWM_COMPLEMENTARY · HSPWM_PUSH_PULL **dead_time** - Optional 16-bit constant or variable to specify the dead time for this PWM unit, defaults to 0 if not specified. **alt_dead_time** - Optional 16-bit constant or variable to specify the alternate dead time for this PWM unit, default to 0 if not specified.
Returns:	undefined
Function:	Sets up the specified High Speed PWM unit.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	Constants are defined in the device's .h file
Examples:	`setup_hspwm_unit(1,HSPWM_ENABLE|SHPWM_COMPLEMENTARY, 100,100);`
Example Files:	None
Also See:	set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm(), setup_hspwm_secondary()

setup_hspwm( ) setup_hspwm_secondary( )

Syntax:	**setup_hspwm(**mode, value**);** **setup_hspwm_secondary(**mode, value**);** **//if available**
Parameters:	**mode** - Mode to setup the High Speed PWM module in. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include: · HSPWM_ENABLED · HSPWM_HALT_WHEN_IDLE · HSPWM_CLOCK_DIV_1 **value** - 16-bit constant or variable to specify the time bases period.
Returns:	undefined

Function:	To enable the High Speed PWM module and set up the Primary and Secondary Time base of the module.
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	Constants are defined in the device's .h file
Examples:	`setup_hspwm(HSPWM_ENABLED | HSPWM_CLOCK_DIV_BY4, 0x8000);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm_unit_chop_clock() setup_hspwm_secondary()

setup_hspwm_unit_chop_clock( )

Syntax:	**setup_hspwm_unit_chop_clock(**unit, settings**);**
Parameters:	**unit** - the High Speed PWM unit chop clock to setup. **settings** - a settings to setup the High Speed PWM unit chop clock. The valid options vary depending on the device. See the device's .h file for all options. Some typical options include: · HSPWM_PWMH_CHOPPING_ENABLED · HSPWM_PWML_CHOPPING_ENABLED · HSPWM_CHOPPING_DISABLED · HSPWM_CLOP_CLK_SOURCE_PWM2H · HSPWM_CLOP_CLK_SOURCE_PWM1H · HSPWM_CHOP_CLK_SOURCE_CHOP_CLK_GENERATOR
Returns:	Undefined
Function:	Setup and High Speed PWM unit's Chop Clock
Availability:	Only on devices with a built-in High Speed PWM module (dsPIC33FJxxGSxxx, dsPIC33EPxxxMUxxx, dsPIC33EPxxxMCxxx, and dsPIC33EVxxxGMxxx devices)
Requires:	None

Examples:	`setup_hspwm_unit_chop_clock(1,HSPWM_PWMH_CHOPPING_ENABLED|`
	`HSPWM_PWML_CHOPPIJNG_ENABLED|`

	`HSPWM_CLOP_CLK_SOURCE_PWM2H);`
Example Files:	None
Also See:	setup_hspwm_unit(), set_hspwm_phase(), set_hspwm_duty(), set_hspwm_event(), setup_hspwm_blanking(), setup_hspwm_trigger(), set_hspwm_override(), get_hspwm_capture(), setup_hspwm_chop_clock(), setup_hspwm(), setup_hspwm_secondary()

setup_lcd( )

Syntax:	**setup_lcd (***mode*, *prescale*, **[***segments0_31***]**,[segments32_47]**);**
Parameters:	***Mode*** may be any of the following constants to enable the LCD and may be or'ed with other constants in the devices *.*h* file: • LCD_DISABLED, LCD_STATIC, LCD_MUX12, LCD_MUX13, LCD_MUX14 See the devices .*h* file for other device specific options. ***Prescale*** may be 1-16 for the LCD clock**.** ***Segments0-31*** may be any of the following constants or'ed together when using the PIC16C92X series of chips:: • SEG0_4, SEG5_8, SEG9_11, SEG12_15, SEG16_19, SEG20_26, SEG27_28, SEG29_31 ALL_LCD_PINS When using the PIC16F/LF1xxx or PIC18F/LFxxxx series of chips, each of the segments are enabled individually. A value of 1 will enable the segment, 0 will disable it and use the pin for normal I/O operation. **Segments 32-47** when using a chip with more than 32 segments, this enables segments 32-47. A value 1 will enable the segment, 0 will disable it. Bit 0 corresponds to segment 32 and bit 15 corresponds to segment 47.
Returns:	undefined.
Function:	This function is used to initialize the LCD Driver Module on the PIC16C92X and PIC16F/LF193X series of chips.
Availability:	Only on devices with built-in LCD Driver Module hardware.
Requires	Constants are defined in the devices *.*h* file.

Examples:	`· setup_lcd( LCD_MUX14 | LCD_STOP_ON_SLEEP, 2, ALL_LCD_PINS );`
	`            // PIC16C92X`
	`· setup_lcd( LCD_MUX13 | LCD_REF_ENABLED | LCD_B_HIGH_POWER, 0, 0xFF0429);`
	
	`            // PIC16F/LF193X - Enables Segments 0, 3, 5, 10, 16, 17, 18, 19, 20, 21, 22, 23`

Example Files:	ex_92lcd.c
Also See:	lcd_symbol(), lcd_load(), lcd_contrast( ), Internal LCD Overview

setup_low_volt_detect( )

Syntax:	**setup_low_volt_detect(**mode**)**
Parameters:	**mode** may be one of the constants defined in the devices .h file. LVD_LVDIN, LVD_45, LVD_42, LVD_40, LVD_38, LVD_36, LVD_35, LVD_33, LVD_30, LVD_28, LVD_27, LVD_25, LVD_23, LVD_21, LVD_19 One of the following may be or'ed(via |) with the above if high voltage detect is also available in the device LVD_TRIGGER_BELOW, LVD_TRIGGER_ABOVE
Returns:	undefined
Function:	This function controls the high/low voltage detect module in the device. The mode constants specifies the voltage trip point and a direction of change from that point (available only if high voltage detect module is included in the device). If the device experiences a change past the trip point in the specified direction the interrupt flag is set and if the interrupt is enabled the execution branches to the interrupt service routine.
Availability:	This function is only available with devices that have the high/low voltage detect module.
Requires	Constants are defined in the devices.h file.
Examples:	`setup_low_volt_detect( LVD_TRIGGER_BELOW | LVD_36 );` This would trigger the interrupt when the voltage is below 3.6 volts

setup_nco( )

Syntax:	**setup_nco(**settings,inc_value**)**
Parameters:	**settings**- setup of the NCO module. See the device's .h file for all options. Some typical options include: · NCO_ENABLE · NCO_OUTPUT · NCO_PULSE_FREQ_MODE · NCO_FIXED_DUTY_MODE **inc_value**- value to increment the NCO 20 bit accumulator by.

Returns:	Undefined
Function:	Sets up the NCO module and sets the value to increment the 20-bit accumulator by.
Availability:	On devices with a NCO module.
Examples:	`setup_nco(NCO_ENABLED|NCO_OUTPUT|NCO_FIXED_DUTY_MODE| NCO_CLOCK_FOSC,8192);`
Example Files:	None
Also See:	get_nco_accumulator( ), set_nco_inc_value( ), get_nco_inc_value( )

setup_opamp1( )   setup_opamp2( )   setup_opamp3()

Syntax:	**setup_opamp1(*mode*)**
	setup_opamp2(*mode*)
	setup_opamp3(*mode*)

Parameters:	***mode*** - The mode of the operation amplifier. See the devices .h file for all options. Some typical options include: • OPAMP_ENABLED • OPAMP_DISABLED
Returns:	undefined
Function:	Enables or Disables the internal operational amplifier peripheral of certain PICmicros.
Availability:	Only parts with a built-in operational amplifier (for example, PIC16F785).
Requires:	Only parts with a built-in operational amplifier (for example, PIC16F785).

Examples:	`setup_opamp1(OPAMP_ENABLED);`
	`setup_opamp2(OPAMP_DISABLED);`
	`setup_opamp3(OPAMP_ENABLED | OPAMP_I_TO_OUTPUT);`

Example Files:	None
Also See:	None

setup_oscillator( )

Syntax:	**setup_oscillator(***mode*, *finetune***)**
Parameters:	***mode*** is dependent on the chip. For example, some chips allow speed setting such as OSC_8MHZ or OSC_32KHZ. Other chips permit changing the source like OSC_TIMER1. The ***finetune*** (only allowed on certain parts) is a signed int with a range of -31 to +31.
Returns:	Some chips return a state such as OSC_STATE_STABLE to indicate the oscillator is stable .
Function:	This function controls and returns the state of the internal RC oscillator on some parts. See the devices .h file for valid options for a particular device. Note that if INTRC or INTRC_IO is specified in #fuses and a #USE DELAY is used for a valid speed option, then the compiler will do this setup automatically at the start of main(). WARNING: If the speed is changed at run time the compiler may not generate the correct delays for some built in functions. The last #USE DELAY encountered in the file is always assumed to be the correct speed. You can have multiple #USE DELAY lines to control the compilers knowledge about the speed.
Availability:	Only parts with a OSCCON register.
Requires:	Constants are defined in the .h file.
Examples:	`setup_oscillator( OSC_2MHZ );`
Example Files:	None
Also See:	#FUSES, Internal oscillator Overview

setup_pga( )

Syntax:	**setup_pga(**module,settings**)**
Parameters:	**module** - constant specifying the Programmable Gain Amplifier (PGA) to setup.
Returns:	Undefined
Function:	This function allows for setting up one of the Programmable Gain Amplifier modules.
Availability:	Devices with a Programmable Gain Amplifier module.
Requires:	Nothing.
Examples:	setup_pga(PGA_ENABLED | PGA_POS_INPUT_PGAxP1 | PGA_GAIN_8X);

Example Files:	None
Also See:	

setup_pid( )

Syntax:	**setup_pid([**mode**,[**K1**],[**K2**],[**K3**]);**
Parameters:	**mode**- the setup of the PID module. The options for setting up the module are defined in the device's header file as: · PID_MODE_PID · PID_MODE_SIGNED_ADD_MULTIPLY_WITH_ACCUMULATION · PID_MODE_SIGNED_ADD_MULTIPLY · PID_MODE_UNSIGNED_ADD_MULTIPLY_WITH_ACCUMULATION · PID_MODE_UNSIGNED_ADD_MULTIPLY · PID_OUTPUT_LEFT_JUSTIFIED · PID_OUTPUT_RIGHT_JUSTIFIED **K1** - optional parameter specifying the K1 coefficient, defaults to zero if not specified. The K1 coefficient is used in the PID and ADD_MULTIPLY modes. When in PID mode the K1 coefficient can be calculated with the following formula: · K1 = Kp + Ki * T + Kd/T When in one of the ADD_MULTIPLY modes K1 is the multiple value. **K2** - optional parameter specifying the K2 coefficient, defaults to zero if not specified. The K2 coefficient is used in the PID mode only and is calculated with the following formula: · K2 = -(Kp + 2Kd/T) **K3** - optional parameter specifying the K3 coefficient, defaults to zero if not specified. The K3 coefficient is used in the PID mode, only and is calculated with the following formula: · K3 = Kd/T T is the sampling period in the above formulas.
Returns:	Nothing
Function:	To setup the Proportional Integral Derivative (PID) module, and to set the input coefficients (K1, K2 and K3).
Availability:	All devices with a PID module.
Requires:	Constants are defined in the device's .h file.

Examples:	`setup_pid(PID_MODE_PID, 10, -3, 50);`
Example Files:	None
Also See:	pid_get_result(), pid_read(), pid_write(), pid_busy()

setup_pmp(option,address_mask)

Syntax:	**setup_pmp(***options,address_mask***);**
Parameters:	**options**- The mode of the Parallel Master Port that allows to set the Master Port mode, read-write strobe options and other functionality of the PMPort module. See the device's .h file for all options. Some typical options include: · PAR_PSP_AUTO_INC · PAR_CONTINUE_IN_IDLE · PAR_INTR_ON_RW //Interrupt on read write · PAR_INC_ADDR //Increment address by 1 every //read/write cycle · PAR_MASTER_MODE_1 //Master Mode 1 · PAR_WAITE4 //4 Tcy Wait for data hold after // strobe **address_mask**- this allows the user to setup the address enable register with a 16-bit value. This value determines which address lines are active from the available 16 address lines PMA0:PMA15.
Returns:	Undefined.
Function:	Configures various options in the PMP module. The options are present in the device's .h file and they are used to setup the module. The PMP module is highly configurable and this function allows users to setup configurations like the Slave module, Interrupt options, address increment/decrement options, Address enable bits, and various strobe and delay options.
Availability:	Only the devices with a built-in Parallel Master Port module.
Requires:	Constants are defined in the device's .h file.

Examples:	`setup_psp(PAR_ENABLE|          //Sets up Master mode with address`
	`PAR_MASTER_MODE_1|PAR_        //lines PMA0:PMA7`
	`STOP_IN_IDLE,0x00FF);`

Example Files:	None
Also See:	setup_pmp( ), pmp_address( ), pmp_read( ), psp_read( ), psp_write( ), pmp_write( ), psp_output_full( ), psp_input_full( ), psp_overflow( ), pmp_output_full( ), pmp_input_full( ),

	pmp_overflow( ) See header file for device selected

setup_psmc( )

Syntax:	**setup_psmc(***unit, mode, period, period_time, rising_edge, rise_time, falling_edge, fall_time***);**
Parameters:	***unit*** is the PSMC unit number 1-4 ***mode*** is one of: • PSMC_SINGLE • PSMC_PUSH_PULL • PSMC_BRIDGE_PUSH_PULL • PSMC_PULSE_SKIPPING • PSMC_ECCP_BRIDGE_REVERSE • PSMC_ECCP_BRIDGE_FORWARD • PSMC_VARIABLE_FREQ • PSMC_3_PHASE For complementary outputs use a or bar (|) and PSMC_COMPLEMENTARY Normally the module is not started until the psmc_pins() call is made. To enable immediately or in PSMC_ENABLE_NOW. ***period*** has three parts or'ed together. The clock source, the clock divisor and the events that can cause the period to start. Sources: • PSMC_SOURCE_FOSC • PSMC_SOURCE_64MHZ • PSMC_SOURCE_CLK_PIN Divisors: • PSMC_DIV_1 • PSMC_DIV_2 • PSMC_DIV_4 • PSMC_DIV_8 Events: • Use any of the events listed below. ***period_time*** is the duration the period lasts in ticks. A tick is the above clock source divided by the divisor. ***rising_edge*** is any of the following events to trigger when the signal goes active.

	rise_time is the time in ticks that the signal goes active (after the start of the period) if the event is PSMC_EVENT_TIME, otherwise unused. ***falling_edg***e is any of the following events to trigger when the signal goes inactive. ***fall_time*** is the time in ticks that the signal goes inactive (after the start of the period) if the event is PSMC_EVENT_TIME, otherwise unused. Events: • PSMC_EVENT_TIME • PSMC_EVENT_C1OUT • PSMC_EVENT_C2OUT • PSMC_EVENT_C3OUT • PSMC_EVENT_C4OUT • PSMC_EVENT_PIN_PIN
Returns:	undefined
Function:	Initializes a PSMC unit with the primary characteristics such as the type of PWM, the period, duty and various advanced triggers. Normally this call does not start the PSMC. It is expected all the setup functions be called and the psmc_pins() be called last to start the PSMC module. These two calls are all that are required for a simple PWM. The other functions may be used for advanced settings and to dynamically change the signal.
Availability:	All devices equipped with PSMC module.
Requires:	None
Examples:	see below
Example Files:	None
Also See:	psmc_deadband(), psmc_sync(), psmc_blanking(), psmc_modulation(), psmc_shutdown(), psmc_duty(), psmc_freq_adjust(), psmc_pins()

```
// Simple PWM, 10khz out on pin C0 assuming a 20mhz crystal
// Duty is initially set to 25%
   setup_psmc(1, PSMC_SINGLE,
              PSMC_EVENT_TIME | PSMC_SOURCE_FOSC, us(100),
              PSMC_EVENT_TIME, 0,
              PSMC_EVENT_TIME, us(25));
   psmc_pins(1, PSMC_A);
```

setup_power_pwm( )

Syntax:	**setup_power_pwm(***modes***,** *postscale***,** *time_base***,** *period***,** *compare***,** *compare_postscale***,** *dead_time***)**
Parameters:	***modes*** values may be up to one from each group of the following:

	PWM_CLOCK_DIV_4, PWM_CLOCK_DIV_16, PWM_CLOCK_DIV_64, PWM_CLOCK_DIV_128 PWM_DISABLED, PWM_FREE_RUN, PWM_SINGLE_SHOT, PWM_UP_DOWN, PWM_UP_DOWN_INT PWM_OVERRIDE_SYNC PWM_UP_TRIGGER, PWM_DOWN_TRIGGER PWM_UPDATE_DISABLE, PWM_UPDATE_ENABLE PWM_DEAD_CLOCK_DIV_2, PWM_DEAD_CLOCK_DIV_4, PWM_DEAD_CLOCK_DIV_8, PWM_DEAD_CLOCK_DIV_16 ***postscale*** is an integer between 1 and 16. This value sets the PWM time base output postscale. ***time_base*** is an integer between 0 and 65535. This is the initial value of the PWM base ***period*** is an integer between 0 and 4095. The PWM time base is incremented until it reaches this number. ***compare*** is an integer between 0 and 255. This is the value that the PWM time base is compared to, to determine if a special event should be triggered. ***compare_postscale*** is an integer between 1 and 16. This postscaler affects compare, the special events trigger. ***dead_time*** is an integer between 0 and 63. This value specifies the length of an off period that should be inserted between the going off of a pin and the going on of it is a complementary pin.
Returns:	undefined
Function:	Initializes and configures the motor control Pulse Width Modulation (PWM) module.
Availability:	All devices equipped with motor control or power PWM module.
Requires:	None

Examples:	`setup_power_pwm(PWM_CLOCK_DIV_4 | PWM_FREE_RUN |`
	`    PWM_DEAD_CLOCK_DIV_4,1,10000,1000,0,1,0);`

Example Files:	None
Also See:	set_power_pwm_override(), setup_power_pwm_pins(), set_power_pwmX_duty()

setup_power_pwm_pins( )

Syntax:	**setup_power_pwm_pins(**module**0,**module**1,**module**2,**module**3)**
Parameters:	For each module (two pins) specify: PWM_PINS_DISABLED, PWM_ODD_ON, PWM_BOTH_ON, PWM_COMPLEMENTARY
Returns:	undefined
Function:	Configures the pins of the Pulse Width Modulation (PWM) device.
Availability:	All devices equipped with a power control PWM.
Requires:	None

Examples:	`setup_power_pwm_pins(PWM_PINS_DISABLED, PWM_PINS_DISABLED, PWM_PINS_DISABLED,`
	`   PWM_PINS_DISABLED);`
	`setup_power_pwm_pins(PWM_COMPLEMENTARY,`
	`   PWM_COMPLEMENTARY, PWM_PINS_DISABLED, PWM_PINS_DISABLED);`

Example Files:	None
Also See:	setup_power_pwm(), set_power_pwm_override(),set_power_pwmX_duty()

setup_psp(option,address_mask)

Syntax:	**setup_psp (***options,address_mask***);**
	setup_psp(*options***);**

Parameters:	***Option***- The mode of the Parallel slave port. This allows to set the slave port mode, read-write strobe options and other functionality of the PMP/EPMP module. See the devices .h file for all options. Some typical options include: · PAR_PSP_AUTO_INC · PAR_CONTINUE_IN_IDLE · PAR_INTR_ON_RW //Interrupt on read write · PAR_INC_ADDR //Increment address by 1 every //read/write cycle · PAR_WAITE4 //4 Tcy Wait for data hold after //strobe ***address_mask***- This allows the user to setup the address enable register with a 16 bit or 32 bit (EPMP) value. This value determines which address lines are active from the available 16 address lines PMA0: PMA15 or 32 address lines PMAO:PMA31 (EPMP only).

Returns:	Undefined.
Function:	Configures various options in the PMP/EPMP module. The options are present in the device.h file and they are used to setup the module. The PMP/EPMP module is highly configurable and this function allows users to setup configurations like the Slave mode, Interrupt options, address increment/decrement options, Address enable bits and various strobe and delay options.
Availability:	Only the devices with a built in Parallel Port module or Enhanced Parallel Master Port module.
Requires:	Constants are defined in the devices .h file.

Examples:	`setup_psp(PAR_PSP_AUTO_INC|      //Sets up legacy slave`
	`                                   //mode with`
	`PAR_STOP_IN_IDLE,0x00FF );         //read and write buffers`
	`                                   //auto increment.`

Example Files:	None
Also See:	psp_output_full(), psp_input_full(), psp_overflow(), See header file for device selected.

setup_pwm1( ) setup_pwm2( ) setup_pwm3( ) setup_pwm4( )

Syntax:	**setup_pwm1(**settings**);**
	setup_pwm2(settings**);**
	setup_pwm3(settings**);**
	setup_pwm4(settings**);**

Parameters:	**settings**- setup of the PWM module. See the device's .h file for all options. Some typical options include: · PWM_ENABLED · PWM_OUTPUT · PWM_ACTIVE_LOW
Returns:	Undefined
Function:	Sets up the PWM module.
Availability:	On devices with a PWM module.
Examples:	`setup_pwm1(PWM_ENABLED|PWM_OUTPUT);`
Example Files:	None
Also See:	set_pwm_duty( )

setup_qei( )

Syntax:	**setup_qei(** *options, filter, maxcount* **);**
Parameters:	***Options***- The mode of the QEI module. See the devices .h file for all options Some common options are: · QEI_MODE_X2 · QEI_MODE_X4 ***filter*** - This parameter is optional, the user can enable the digital filters and specify the clock divisor. ***maxcount*** - Specifies the value at which to reset the position counter.
Returns:	void
Function:	Configures the Quadrature Encoder Interface. Various settings like mode and filters can be setup.
Availability:	Devices that have the QEI module.
Requires:	Nothing.
Examples:	`setup_qei(QEI_MODE_X2|QEI_RESET_WHEN_MAXCOUNT, QEI_FILTER_ENABLE_QEA|QEI_FILTER_DIV_2,0x1000);`
Example Files:	None
Also See:	qei_set_count() , qei_get_count() , qei_status()

setup_rtc( )

Syntax:	**setup_rtc() (***options, calibration***);**
Parameters:	***Options***- The mode of the RTCC module. See the devices .h file for all options ***Calibration***- This parameter is optional and the user can specify an 8 bit value that will get written to the calibration configuration register.
Returns:	void
Function:	Configures the Real Time Clock and Calendar module. The module requires an external

	32.768 kHz clock crystal for operation.
Availability:	Devices that have the RTCC module.
Requires:	Nothing.

Examples:	`setup_rtc(RTC_ENABLE | RTC_OUTPUT SECONDS, 0x00);`
	`// Enable RTCC module with seconds clock and no calibration`

Example Files:	None
Also See:	rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(, setup_rtc()

setup_rtc_alarm( )

Syntax:	**setup_rtc_alarm(***options*, *mask*, *repeat***);**
Parameters:	***options***- The mode of the RTCC module. See the devices .h file for all options ***mask***- specifies the alarm mask bits for the alarm configuration. ***repeat***- Specifies the number of times the alarm will repeat. It can have a max value of 255.
Returns:	void
Function:	Configures the alarm of the RTCC module.
Availability:	Devices that have the RTCC module.
Requires:	Nothing.
Examples:	`setup_rtc_alarm(RTC_ALARM_ENABLE, RTC_ALARM_HOUR, 3);`
Example Files:	None
Also See:	rtc_read(), rtc_alarm_read(), rtc_alarm_write(), setup_rtc_alarm(), rtc_write(), setup_rtc()

setup_sd_adc( )

Syntax:	**setup_sd_adc(settings1, settings 2, settings3);**

Parameters:	***settings1***- settings for the SD1CON1 register of the SD ADC module. See the device's *.h* file for all options. Some options include: 1 SDADC_ENABLED 2 SDADC_NO_HALT 3 SDADC_GAIN_1 4 SDADC_NO_DITHER 5 SDADC_SVDD_SVSS 6 SDADC_BW_NORMAL ***settings2***- settings for the SD1CON2 register of the SD ADC module. See the device's *.h* file for all options. Some options include: 7 SDADC_CHOPPING_ENABLED 8 SDADC_INT_EVERY_SAMPLE 9 SDADC_RES_UPDATED_EVERY_INT 10 SDADC_NO_ROUNDING ***settings3***- settings for the SD1CON3 register of the SD ADC module. See the device's *.h* file for all options. Some options include: 11 SDADC_CLOCK_DIV_1 12 SDADC_OSR_1024 13 SDADC_CLK_SYSTEM
Returns:	Nothing
Function:	To setup the Sigma-Delta Analog to Digital Converter (SD ADC) module.
Availability:	Only devices with a SD ADC module.
Examples:	setup_sd_adc(SDADC_ENABLED | SDADC_DITHER_LOW, SDADC_CHOPPING_ENABLED | SDADC_INT_EVERY_5TH_SAMPLE | SDADC_RES_UPDATED_EVERY_INT, SDADC_CLK_SYSTEM | SDADC_CLOCK_DIV_4);
Example Files:	None
Also See:	set_sd_adc_channel(), read_sd_adc(), set_sd_adc_calibration()

setup_smtx( )

Syntax:	**setup_smt1(**mode,[period]**);**
	setup_smt2(mode,[period]**);**

Parameters:	**mode** - The setup of the SMT module. See the device's .h file for all aoptions. Some typical options include: SMT_ENABLED SMT_MODE_TIMER

	SMT_MODE_GATED_TIMER SMT_MODE_PERIOD_DUTY_CYCLE_ACQ **period** - Optional parameter for specifying the overflow value of the SMT timer, defaults to maximum value if not specified.
Returns:	Nothing
Function:	Configures the Signal Measurement Timer (SMT) module.
Availability:	Only devices with a built-in SMT module.

Examples:	`setup_smt1(SMT_ENABLED | SMT_MODE_PERIOD_DUTY_CYCLE_ACQ|`
	`SMT_REPEAT_DATA_ACQ_MODE | SMT_CLK_FOSC);`

Example Files:	None
Also See:	smtx_status(), stmx_start(), smtx_stop(), smtx_update(), smtx_reset_timer(), smtx_read(), smtx_write()

setup_spi( ) setup_spi2( )

Syntax:	**setup_spi (*mode*)** **setup_spi2 (*mode*)**
Parameters:	***mode*** may be: • SPI_MASTER, SPI_SLAVE, SPI_SS_DISABLED • SPI_L_TO_H, SPI_H_TO_L • SPI_CLK_DIV_4, SPI_CLK_DIV_16, • SPI_CLK_DIV_64, SPI_CLK_T2 • SPI_SAMPLE_AT_END, SPI_XMIT_L_TO_H • Constants from each group may be or'ed together with |.
Returns:	undefined
Function:	Initializes the Serial Port Interface (SPI). This is used for 2 or 3 wire serial devices that follow a common clock/data protocol.
Also See:	spi_write(), spi_read(), spi_data_is_in(), SPI Overview

setup_timer_A( )

Syntax:	**setup_timer_A (**mode**);**
Parameters:	***mode*** values may be: · TA_OFF, TA_INTERNAL, TA_EXT_H_TO_L, TA_EXT_L_TO_H · TA_DIV_1, TA_DIV_2, TA_DIV_4, TA_DIV_8, TA_DIV_16, TA_DIV_32,

	TA_DIV_64, TA_DIV_128, TA_DIV_256 · constants from different groups may be or'ed together with |.
Returns:	undefined
Function:	sets up Timer A.
Availability:	This function is only available on devices with Timer A hardware.
Requires:	Constants are defined in the device's .h file.

Examples:	`setup_timer_A(TA_OFF);`
	`setup_timer_A(TA_INTERNAL | TA_DIV_256);`
	`setup_timer_A(TA_EXT_L_TO_H | TA_DIV_1);`

Example Files:	none
Also See:	get_timerA( ), set_timerA( ), TimerA Overview

setup_timer_B( )

Syntax:	**setup_timer_B (**mode**);**
Parameters:	***mode*** values may be: · TB_OFF, TB_INTERNAL, TB_EXT_H_TO_L, TB_EXT_L_TO_H · TB_DIV_1, TB_DIV_2, TB_DIV_4, TB_DIV_8, TB_DIV_16, TB_DIV_32, TB_DIV_64, TB_DIV_128, TB_DIV_256 · constants from different groups may be or'ed together with |.
Returns:	undefined
Function:	sets up Timer B
Availability:	This function is only available on devices with Timer B hardware.
Requires:	Constants are defined in device's .h file.

Examples:	`setup_timer_B(TB_OFF);`
	`setup_timer_B(TB_INTERNAL | TB_DIV_256);`
	`setup_timer_B(TA_EXT_L_TO_H | TB_DIV_1);`

Example Files:	none
Also See:	get_timerB( ), set_timerB( ), TimerB Overview

setup_timer_0( )

Syntax:	**setup_timer_0 (***mode***)**
Parameters:	***mode*** may be one or two of the constants defined in the devices .h file. RTCC_INTERNAL, RTCC_EXT_L_TO_H or RTCC_EXT_H_TO_L RTCC_DIV_2, RTCC_DIV_4, RTCC_DIV_8, RTCC_DIV_16, RTCC_DIV_32, RTCC_DIV_64, RTCC_DIV_128, RTCC_DIV_256 PIC18XXX only: RTCC_OFF, RTCC_8_BIT One constant may be used from each group or'ed together with the | operator.
Returns:	undefined
Function:	Sets up the timer 0 (aka RTCC).
Warning:	On older PIC16 devices, set-up of the prescaler may undo the WDT prescaler.
Availability:	All devices.
Requires:	Constants are defined in the devices .h file.
Examples:	`setup_timer_0 (RTCC_DIV_2|RTCC_EXT_L_TO_H);`
Example Files:	
Also See:	get_timer0(), set_timer0(), setup counters()

setup_uart( )

Syntax:	**setup_uart(***baud***,** *stream***)**
	setup_uart(*baud***)**
	setup_uart(*baud, stream, clock)*

Parameters:	***baud*** is a constant representing the number of bits per second. A one or zero may also be passed to control the on/off status. ***Stream*** is an optional stream identifier. *Chips with the advanced UART may also use the following constants:* UART_ADDRESS UART only accepts data with 9th bit=1 UART_DATA UART accepts all data *Chips with the EUART H/W may use the following constants:* UART_AUTODETECT Waits for 0x55 character and sets the UART baud rate to match. UART_AUTODETECT_NOWAIT Same as above function, except returns before 0x55 is received. KBHIT() will be true when the match is made. A call to GETC() will clear the character.

	UART_WAKEUP_ON_RDA Wakes PIC up out of sleep when RCV goes from high to low ***clock*** - If specified this is the clock rate this function should assume. The default comes from the #USE DELAY.
Returns:	undefined
Function:	Very similar to SET_UART_SPEED. If 1 is passed as a parameter, the UART is turned on, and if 0 is passed, UART is turned off. If a BAUD rate is passed to it, the UART is also turned on, if not already on.
Availability:	This function is only available on devices with a built in UART.
Requires:	#USE RS232

Examples:	`setup_uart(9600);`
	`setup_uart(9600, rsOut);`

Example Files:	None
Also See:	#USE RS232, putc(), getc(), RS232 I/O Overview

setup_vref( )

Syntax:	**setup_vref (*mode* | *value*)**
Parameters:	***mode*** may be one of the following constants: • FALSE (off) • VREF_LOW for VDD*VALUE/24 • VREF_HIGH for VDD*VALUE/32 + VDD/4 • any may be or'ed with VREF_A2. ***value*** is an int 0-15.
Also See:	Voltage Reference Overview

setup_wdt( )

Syntax:	**setup_wdt (*mode*)**
Parameters:	Constants like: WDT_18MS, WDT_36MS, WDT_72MS, WDT_144MS,WDT_288MS, WDT_576MS, WDT_1152MS, WDT_2304MS For some parts: WDT_ON, WDT_OFF

	.
Warning:	On older PIC16 devices, set-up of the prescaler may undo the timer0 prescaler.
Als o See :	#FUSES , restart_wdt() , WDT or Watch Dog Timer Overview Internal Oscillator Overview

setup_zdc( )

Syntax:	**setup_zdc(mode);**
Parameters:	**mode**- the setup of the ZDC module. The options for setting up the module include: • ZCD_ENABLED • ZCD_DISABLED • ZCD_INVERTED • ZCD_INT_L_TO_H • ZCD_INT_H_TO_L
Returns:	Nothing
Function:	To set-up the Zero_Cross Detection (ZCD) module.
Availability:	All devices with a ZCD module.
Examples:	`setup_zcd(ZCD_ENABLE|ZCD_INT_H_TO_L);`
Example Files:	None
Also See:	zcd_status()

shift_left( )

Syntax:	**shift_left (*address*, *bytes*, *value*)**
Parameters:	***address*** is a pointer to memory. ***bytes*** is a count of the number of bytes to work with ***value*** is a 0 to 1 to be shifted in.
Returns:	0 or 1 for the bit shifted out
Function:	Shifts a bit into an array or structure. The address may be an array identifier or an address to a structure (such as &data). Bit 0 of the lowest byte in RAM is treated as the LSB.

Availability:	All devices
Requires:	Nothing

Examples:	`byte buffer[3];`
	`for(i=0; i<=24; ++i){`
	`   // Wait for clock high`
	`   while (!input(PIN_A2));`
	`   shift_left(buffer,3,input(PIN_A3));`
	`   // Wait for clock low`
	`   while (input(PIN_A2));`
	`}`
	`// reads 24 bits from pin A3,each bit is read`
	`// on a low to high on pin A2`

Example Files:	ex_extee.c, 9356.c
Also See:	shift_right(), rotate_right(), rotate_left(),

shift_right( )

Syntax:	**shift_right (*address*, *bytes*, *value*)**
Parameters:	***address*** is a pointer to memory ***bytes*** is a count of the number of bytes to work with ***value*** is a 0 to 1 to be shifted in.
Returns:	0 or 1 for the bit shifted out
Function:	Shifts a bit into an array or structure. The address may be an array identifier or an address to a structure (such as &data). Bit 0 of the lowest byte in RAM is treated as the LSB.
Availability:	All devices
Requires:	Nothing

Examples:	`// reads 16 bits from pin A1, each bit is read`
	`// on a low to high on pin A2`
	`struct {`
	`   byte time;`
	`   byte command : 4;`
	`   byte source  : 4;} msg;`
	
	`for(i=0; i<=16; ++i) {`
	`   while(!input(PIN_A2));`
	`   shift_right(&msg,3,input(PIN_A1));`
	`   while (input(PIN_A2)) ;}`
	
	`// This shifts 8 bits out PIN_A0, LSB first.`

	`for(i=0;i<8;++i)`
	`   output_bit(PIN_A0,shift_right(&data,1,0));`

Example Files:	ex_extee.c, 9356.c
Also See:	shift_left(), rotate_right(), rotate_left(),

sleep( )

Syntax:	**sleep(mode)**
Parameters:	***mode*** - for most chips this is not used. Check the device header for special options on some chips.
Returns:	Undefined
Function:	Issues a SLEEP instruction. Details are device dependent. However, in general the part will enter low power mode and halt program execution until woken by specific external events. Depending on the cause of the wake up execution may continue after the sleep instruction. The compiler inserts a sleep() after the last statement in main().
Availability:	All devices
Requires:	Nothing
Examples:	`SLEEP();`
Example Files:	ex_wakup.c
Also See:	reset cpu()

sleep_ulpwu( )

Syntax:	**sleep_ulpwu(*time*)**
Parameters:	***time*** specifies how long, in us, to charge the capacitor on the ultra-low power wakeup pin (by outputting a high on PIN_A0).
Returns:	undefined
Function:	Charges the ultra-low power wake-up capacitor on PIN_A0 for time microseconds, and then puts the PIC to sleep. The PIC will then wake-up on an 'Interrupt-on-Change' after the charge on the cap is lost.

Availability:	Ultra Low Power Wake-Up support on the PIC (example, PIC12F683)
Requires:	#USE DELAY
Examples:	see below
Example Files:	None
Also See:	#USE DELAY

```
while(TRUE)
{
    if (input(PIN_A1))
        //do something
    else
        sleep_ulpwu(10);  //cap will be charged for 10us,
                          //then goto sleep
}
```

sleep_ulpwu( )

Syntax:	**sleep_ulpwu(*time*)**
Parameters:	***time*** specifies how long, in us, to charge the capacitor on the ultra-low power wakeup pin (by outputting a high on PIN_B0).
Returns:	undefined
Function:	Charges the ultra-low power wake-up capacitor on PIN_B0 for time microseconds, and then puts the PIC to sleep. The PIC will then wake-up on an 'Interrupt-on-Change' after the charge on the cap is lost.
Availability:	Ultra Low Power Wake-Up support on the PIC (example, PIC124F32KA302)
Requires:	#USE DELAY
Examples:	see below
Example Files:	None
Also See:	#USE DELAY

```
while(TRUE)
{
    if (input(PIN_A1))
        //do something
    else
        sleep_ulpwu(10);  //cap will be charged for 10us,
                          //then goto sleep
}
```

smtx_read( )

Syntax:	**value_smt1_read(**which**);**
	value_smt2_read(which**);**

Parameters:	**which** - Specifies which SMT registers to read. The following defines have been made in the device's header file to select which registers are read: SMT_CAPTURED_PERIOD_REG SMT_CAPTURED_PULSE_WIDTH_REG SMT_TMR_REG SMT_PERIOD_REG
Returns:	32-bit value
Function:	To read the Capture Period Registers, Capture Pulse Width Registers, Timer Registers or Period Registers of the Signal Measurement Timer module.
Availability:	Only devices with a built-in SMT module.

Examples:	unsigned int32 Period;
	`Period = smt1_read(SMT_CAPTURED_PERIOD_REG);`

Example Files:	None
Also See:	smtx_status(), stmx_start(), smtx_stop(), smtx_update(), smtx_reset_timer(), setup_SMTx(), smtx_write()

smtx_reset_timer( )

Syntax:	**smt1_reset_timer();**
	smt2_reset_timer();

Parameters:	None
Returns:	Nothing
Function:	To manually reset the Timer Register of the Signal Measurement Timer module.
Availability:	Only devices with a built-in SMT module.
Examples:	`smt1_reset_timer();`
Example Files:	None
Also See:	setup_smtx(), stmx_start(), smtx_stop(), smtx_update(), smtx_status(), smtx_read(), smtx_write()

smtx_start( )

Syntax:	**smt1_start();**
	smt2_start();

Parameters:	None
Returns:	Nothing
Function:	To have the Signal Measurement Timer (SMT) module start acquiring data.
Availability:	Only devices with a built-in SMT module.
Examples:	`smt1_start();`
Example Files:	None
Also See:	smtx_status(), setup_smtx(), smtx_stop(), smtx_update(), smtx_reset_timer(), smtx_read(), smtx_write()

smtx_status( )

Syntax:	**value = smt1_status();**
	value = smt2_status();

Parameters:	None
Returns:	The status of the SMT module.
Function:	To return the status of the Signal Measurement Timer (SMT) module.
Availability:	Only devices with a built-in SMT module.
Examples:	`status = smt1_status();`
Example Files:	None
Also See:	setup_smtx(), stmx_start(), smtx_stop(), smtx_update(), smtx_reset_timer(), smtx_read(), smtx_write()

smtx_stop( )

Syntax:	**smt1_stop();**
	smt2_stop();

Parameters:	None
Returns:	Nothing

Function:	Configures the Signal Measurement Timer (SMT) module.
Availability:	Only devices with a built-in SMT module.
Examples:	`smt1_stop()`
Example Files:	None
Also See:	smtx_status(), stmx_start(), setup_smtx(), smtx_update(), smtx_reset_timer(), smtx_read(), smtx_write()

smtx_write( )

Syntax:	**smt1_write(**which,value**);**
	smt2_write(which,value**);**

Parameters:	**which -** Specifies which SMT registers to write. The following defines have been made in the device's header file to select which registers are written: SMT_TMR_REG SMT_PERIOD_REG **value** - The 24-bit value to set the specified registers.
Returns:	Nothing
Function:	To write the Timer Registers or Period Registers of the Signal Measurement Timer (SMT) module
Availability:	Only devices with a built-in SMT module.
Examples:	`smt1_write(SMT_PERIOD_REG, 0x100000000);`
Example Files:	None
Also See:	smtx_status(), stmx_start(), setup_smtx(), smtx_update(), smtx_reset_timer(), smtx_read(), setup_smtx()

smtx_update( )

Syntax:	**smt1_update(**which**);**
	smt2_update(which**);**

Parameters:	**which** - Specifies which capture registers to manually update. The following defines have been made in the device's header file to select which registers are updated: SMT_CAPTURED_PERIOD_REG SMT_CAPTURED_PULSE_WIDTH_REG
Returns:	Nothing

Function:	To manually update the Capture Period Registers or the Capture Pulse Width Registers of the Signal Measurement Timer module.
Availability:	Only devices with a built-in SMT module.
Examples:	`smt1_update(SMT_CAPTURED_PERIOD_REG);`
Example Files:	None
Also See:	setup_smtx(), stmx_start(), smtx_stop(), smtx_status(), smtx_reset_timer(), smtx_read(), smtx_write()

spi_data_is_in( ) spi_data_is_in2( )

Syntax:	**result = spi_data_is_in()** **result = spi_data_is_in2()**
Parameters:	None
Returns:	0 (FALSE) or 1 (TRUE)
Function:	Returns TRUE if data has been received over the SPI.
Availability:	This function is only available on devices with SPI hardware.
Requires:	Nothing

Examples:	`( !spi_data_is_in() && input(PIN_B2) );`
	`if( spi_data_is_in() )`
	`data = spi_read();`

Example Files:	None
Also See:	spi_read(), spi_write(), SPI Overview

spi_init()

Syntax:	**spi_init(baud);**
	spi_init(stream,baud);

Parameters:	**stream** – is the SPI stream to use as defined in the STREAM=name option in #USE SPI. **band**- the band rate to initialize the SPI module to. If FALSE it will disable the SPI module, if TRUE it will enable the SPI module to the band rate specified in #use SPI.
Returns:	Nothing.

Function:	Initializes the SPI module to the settings specified in #USE SPI.
Availability:	This function is only available on devices with SPI hardware.
Requires:	#USE SPI

Examples:	`#use spi(MATER, SPI1, baud=1000000, mode=0, stream=SPI1_MODE0)`
	
	`spi_init(SPI1_MODE0, TRUE);  //initialize and enable SPI1 to setting in #USE SPI`
	`spi_init(FALSE); //disable SPI1`
	`spi_init(250000);//initialize and enable SPI1 to a baud rate of 250K`

Example Files:	None
Also See:	#USE SPI, spi_xfer(), spi_xfer_in(), spi_prewrite(), spi_speed()

spi_prewrite(data);

Syntax:	**spi_prewrite(**data**);**
	spi_prewrite(stream**,** data**);**

Parameters:	**stream** – is the SPI stream to use as defined in the STREAM=name option in #USE SPI. **data**- the variable or constant to transfer via SPI
Returns:	Nothing.
Function:	Writes data into the SPI buffer without waiting for transfer to be completed. Can be used in conjunction with spi_xfer() with no parameters to transfer more then 8 bits for PCM and PCH device, or more then 8 bits or 16 bits (XFER16 option) for PCD. Function is useful when using the SSP or SSP2 interrupt service routines for PCM and PCH device, or the SPIx interrupt service routines for PCD device.
Availability:	This function is only available on devices with SPI hardware.
Requires:	#USE SPI, and the option SLAVE is used in #USE SPI to setup PIC as a SPI slave device
Examples:	spi_prewrite(data_out);
Example Files:	ex_spi_slave.c
Also See:	#USE SPI, spi_xfer(), spi_xfer_in(), spi_init(), spi_speed()

spi_read( )   spi_read2( )

Syntax:	**value = spi_read ([***data***])** **value = spi_read2 ([***data***])**
Parameters:	data – optional parameter and if included is an 8 bit int.
Returns:	An 8 bit int

Function:	Return a value read by the SPI. If a value is passed to the spi_read() the data will be clocked out and the data received will be returned. If no data is ready, spi_read() will wait for the data is a SLAVE or return the last DATA clocked in from spi_write(). If this device is the MASTER then either do a spi_write(data) followed by a spi_read() or do a spi_read(data). These both do the same thing and will generate a clock. If there is no data to send just do a spi_read(0) to get the clock. If this device is a SLAVE then either call spi_read() to wait for the clock and data or use_spi_data_is_in() to determine if data is ready.
Availability:	This function is only available on devices with SPI hardware.
Requires:	Nothing
Examples:	`data_in = spi_read(out_data);`
Example Files:	ex_spi.c
Also See:	spi_write(), , , spi_data_is_in(), SPI Overview

spi_read_16() spi_read2_16() spi_read3_16() spi_read4_16()

Syntax:	**value = spi_read_16([data]);**
	value = spi_read2_16([data]);
	value = spi_read3_16([data]);
	value = spi_read4_16([data]);

Parameters:	data – optional parameter and if included is a 16 bit int
Returns:	A 16 bit int
Function:	Return a value read by the SPI. If a value is passed to the spi_read_16() the data will be clocked out and the data received will be returned. If no data is ready, spi_read_16() will wait for the data is a SLAVE or return the last DATA clocked in from spi_write_16(). If this device is the MASTER then either do a spi_write_16(data) followed by a spi_read_16() or do a spi_read_16(data). These both do the same thing and will generate a clock. If there is no data to send just do a spi_read_16(0) to get the clock. If this device is a slave then either call spi_read_16() to wait for the clock and data or use_spi_data_is_in() to determine if data is ready.
Availability:	This function is only available on devices with SPI hardware.
Requires:	NThat the option SPI_MODE_16B be used in setup_spi() function, or that the option XFER16 be used in #use SPI(
Examples:	`data_in = spi_read_16(out_data);`

Example Files:	None
Also See:	spi_read(), spi_write(), spi_write_16(), spi_data_is_in(), SPI Overview

spi_speed

Syntax:	**spi_speed(**baud**);**
	spi_speed(stream**,**baud**);**
	spi_speed(stream**,**baud**,**clock**);**

Parameters:	**stream** – is the SPI stream to use as defined in the STREAM=name option in #USE SPI. **band**- the band rate to set the SPI module to **clock**- the current clock rate to calculate the band rate with. If not specified it uses the value specified in #use delay ().
Returns:	Nothing.
Function:	Sets the SPI module's baud rate to the specified value.
Availability:	This function is only available on devices with SPI hardware.
Requires:	#USE SPI

Examples:	spi_speed(250000);
	spi_speed(SPI1_MODE0, 250000);
	spi_speed(SPI1_MODE0, 125000, 8000000);

Example Files:	None
Also See:	#USE SPI, spi_xfer(), spi_xfer_in(), spi_prewrite(), spi_init()

spi_write( ) spi_write2( )

Syntax:	**spi_write([**wait**],***value***);**
	spi_write2([wait]**,***value***);**

Parameters:	***value*** is an 8 bit int **wait**- an optional parameter specifying whether the function will wait for the SPI transfer to complete before exiting. Default is TRUE if not specified.
Returns:	Nothing
Function:	Sends a byte out the SPI interface. This will cause 8 clocks to be generated. This function will write the value out to the SPI. At the same time data is clocked out data is clocked in and stored in a receive buffer. spi_read() may be used to read the buffer.
Availability:	This function is only available on devices with SPI hardware.

Requires:	Nothing

Examples:	`spi_write( data_out );`
	`data_in = spi_read();`

Example Files:	ex_spi.c
Also See:	spi_read(), spi_data_is_in(), SPI Overview, spi_write_16(), spi_read_16()

spi_xfer( )

Syntax:	**spi_xfer(data)**
	spi_xfer(stream, data)
	spi_xfer(stream, data, bits)
	result = spi_xfer(data)
	result = spi_xfer(stream, data)
	result = spi_xfer(stream, data, bits)

Parameters:	***data*** is the variable or constant to transfer via SPI. The pin used to transfer *data* is defined in the DO=pin option in #use spi. ***stream*** is the SPI stream to use as defined in the STREAM=name option in #USE SPI. ***bits*** is how many bits of data will be transferred.
Returns:	The data read in from the SPI. The pin used to transfer result is defined in the DI=pin option in #USE SPI.
Function:	Transfers data to and reads data from an SPI device.
Availability:	All devices with SPI support.
Requires:	#USE SPI

Examples:	`int i = 34;`
	`spi_xfer(i);`
	`// transfers the number 34 via SPI`
	`int trans = 34, res;`
	`res = spi_xfer(trans);`
	`// transfers the number 34 via SPI`
	`// also reads the number coming in from SPI`

Example Files:	None
Also See:	#USE SPI

SPI_XFER_IN()

Syntax:	**value = spi_xfer_in();**
	value = spi_xfer_in(bits);
	value = spi_xfer_in(stream,bits);

Parameters:	stream – is the SPI stream to use as defined in the STREAM=name option in #USE SPI. bits – is how many bits of data to be received.
Returns:	The data read in from the SPI
Function:	Reads data from the SPI, without writing data into the transmit buffer first.
Availability:	This function is only available on devices with SPI hardware.
Requires:	#USE SPI, and the option SLAVE is used in #USE SPI to setup PIC as a SPI slave device.
Examples:	`data_in = spi_xfer_in();`
Example Files:	ex_spi_slave.c
Also See:	#USE SPI, spi_xfer(), spi_prewrite(), spi_init(), spi_speed()

sprintf( )

Syntax:	**sprintf(***string***,** *cstring***,** *values***...);** **bytes=sprintf(***string***,** *cstring***,** *values***...)**
Parameters:	***string*** is an array of characters. ***cstring*** is a constant string or an array of characters null terminated. ***Values*** are a list of variables separated by commas. Note that format specifies do not work in ram band strings.
Returns:	Bytes is the number of bytes written to string.
Function:	This function operates like printf() except that the output is placed into the specified string. The output string will be terminated with a null. No checking is done to ensure the string is large enough for the data. See printf() for details on formatting.
Availability:	All devices.
Requires:	Nothing

Examples:	`char mystring[20];`
	`long mylong;`
	
	`mylong=1234;`
	`sprintf(mystring,"<%lu>",mylong);`
	`// mystring now has:`
	`//      < 1 2 3 4 > \0`

Example Files:	None
Also See:	printf()

sqrt( )

Syntax:	**result = sqrt (*value*)**
Parameters:	***value*** is a float
Returns:	A float
Function:	Computes the non-negative square root of the float value x. If the argument is negative, the behavior is undefined. Note on error handling: If "errno.h" is included then the domain and range errors are stored in the errno variable. The user can check the errno to see if an error has occurred and print the error using the perror function. Domain error occurs in the following cases: sqrt: when the argument is negative
Availability:	All devices.
Requires:	#INCLUDE <math.h>
Examples:	`distance = sqrt( pow((x1-x2),2)+pow((y1-y2),2) );`
Example Files:	None
Also See:	None

srand( )

Syntax:	**srand(*n*)**
Parameters:	***n*** is the seed for a new sequence of pseudo-random numbers to be returned by subsequent calls to rand.
Returns:	No value.
Function:	The srand() function uses the argument as a seed for a new sequence of pseudo-random numbers to be returned by subsequent calls to rand. If srand() is then called with same seed

	value, the sequence of random numbers shall be repeated. If rand is called before any call to srand() have been made, the same sequence shall be generated as when srand() is first called with a seed value of 1.
Availability:	All devices.
Requires:	#INCLUDE <STDLIB.H>

Examples:	`srand(10);`
	`I=rand();`

Example Files:	None
Also See:	rand()

STANDARD STRING FUNCTIONS( )

memchr( )	memcmp( )	strcat( )	strchr( )
strcmp( )	strcoll( )	strcspn( )	strerror( )
stricmp( )	strlen( )	strlwr( )	strncat( )
strncmp( )	strncpy( )	strpbrk( )	strrchr( )
strspn( )	strstr( )	strxfrm( )	

Syntax:

ptr=strcat (*s1*, *s2*)	**Concatenate s2 onto s1**
ptr=strchr (*s1*, *c*)	Find c in s1 and return &s1[i]
ptr=strrchr (*s1*, *c*)	Same but search in reverse
cresult=strcmp (*s1*, *s2*)	Compare s1 to s2
iresult=strncmp (*s1*, *s2*, *n*)	Compare s1 to s2 (n bytes)
iresult=stricmp (*s1*, *s2*)	Compare and ignore case
ptr=strncpy (*s1*, *s2*, *n*)	Copy up to n characters s2->s1
iresult=strcspn (*s1*, *s2*)	Count of initial chars in s1 not in s2
iresult=strspn (*s1*, *s2*)	Count of initial chars in s1 also in s2
iresult=strlen (*s1*)	Number of characters in s1
ptr=strlwr (*s1*)	Convert string to lower case
ptr=strpbrk (*s1*, *s2*)	Search s1 for first char also in s2
ptr=strstr (*s1*, *s2*)	Search for s2 in s1
ptr=strncat(*s1*,*s2, n*)	Concatenates up to n bytes of s2 onto s1
iresult=strcoll(*s1*,*s2*)	Compares s1 to s2, both interpreted as appropriate to the current locale.
res=strxfrm(*s1*,*s2*,*n*)	Transforms maximum of n characters of s2 and places them in s1, such that strcmp(s1,s2) will give the same result as strcoll(s1,s2)
iresult=memcmp(*m1*,*m2*,*n*)	Compare m1 to m2 (n bytes)
ptr=memchr(*m1*,*c*,*n*)	Find c in first n characters of m1 and return &m1[i]
ptr=strerror(errnum)	Maps the error number in errnum to an error message string. The parameters 'errnum' is an unsigned 8 bit int. Returns a pointer to the string.

Parameters: ***s1*** and ***s2*** are pointers to an array of characters (or the name of an array). Note that s1 and s2 MAY NOT BE A CONSTANT (like "hi").

	n is a count of the maximum number of character to operate on. ***c*** is a 8 bit character ***m1*** and ***m2*** are pointers to memory.
Returns:	ptr is a copy of the s1 pointer iresult is an 8 bit int result is -1 (less than), 0 (equal) or 1 (greater than) res is an integer.
Function:	Functions are identified above.
Availability:	All devices.
Requires:	#include <string.h>

Examples:	`char string1[10], string2[10];`
	
	`strcpy(string1,"hi ");`
	`strcpy(string2,"there");`
	`strcat(string1,string2);`
	
	`printf("Length is %u\r\n", strlen(string1));`
	`          // Will print 8`

Example Files:	ex_str.c
Also See:	strcpy(), strtok()

strcpy( ) strcopy( )

Syntax:	**strcpy (*dest*, *src*)** **strcopy (*dest*, *src*)**
Parameters:	***dest*** is a pointer to a RAM array of characters. ***src*** may be either a pointer to a RAM array of characters or it may be a constant string.
Returns:	undefined
Function:	Copies a constant or RAM string to a RAM string. Strings are terminated with a 0.
Availability:	All devices.
Requires:	Nothing

Examples:	`char string[10], string2[10];`
	`.`
	`.`
	`.`
	`strcpy (string, "Hi There");`
	
	`strcpy(string2,string);`

Example Files:	ex_str.c
Also See:	strxxxx()

strtod( )

Syntax:	**result=strtod(*nptr*,& *endptr*)**
Parameters:	***nptr*** and ***endptr*** are strings
Returns:	result is a float. returns the converted value in result, if any. If no conversion could be performed, zero is returned.
Function:	The strtod function converts the initial portion of the string pointed to by nptr to a float representation. The part of the string after conversion is stored in the object pointed to endptr, provided that endptr is not a null pointer. If nptr is empty or does not have the expected form, no conversion is performed and the value of nptr is stored in the object pointed to by endptr, provided endptr is not a null pointer.
Availability:	All devices.
Requires:	#INCLUDE <stdlib.h>

Examples:	`float result;`
	`char str[12]="123.45hello";`
	`char *ptr;`
	`result=strtod(str,&ptr);`
	`//result is 123.45 and ptr is "hello"`

Example Files:	None
Also See:	strtol(), strtoul()

strtok( )

Syntax:	**ptr = strtok(*s1*, *s2*)**

Parameters:	***s1*** and ***s2*** are pointers to an array of characters (or the name of an array). Note that s1 and s2 MAY NOT BE A CONSTANT (like "hi"). s1 may be 0 to indicate a continue operation.
Returns:	ptr points to a character in s1 or is 0
Function:	Finds next token in s1 delimited by a character from separator string s2 (which can be different from call to call), and returns pointer to it. First call starts at beginning of s1 searching for the first character NOT contained in s2 and returns null if there is none are found. If none are found, it is the start of first token (return value). Function then searches from there for a character contained in s2. If none are found, current token extends to the end of s1, and subsequent searches for a token will return null. If one is found, it is overwritten by '\0', which terminates current token. Function saves pointer to following character from which next search will start. Each subsequent call, with 0 as first argument, starts searching from the saved pointer.
Availability:	All devices.
Requires:	#INCLUDE <string.h>
Examples:	see below
Example Files:	ex_str.c
Also See:	strxxxx(), strcpy()

```
char string[30], term[3], *ptr;

strcpy(string,"one,two,three;");
strcpy(term,",;");

ptr = strtok(string, term);
while(ptr!=0) {
   puts(ptr);
   ptr = strtok(0, term);
   }
          // Prints:
             one
             two
             three
```

strtol( )

Syntax:	**result=strtol(***nptr***,&** *endptr***,** *base***)**
Parameters:	***nptr*** and ***endptr*** are strings and ***base*** is an integer
Returns:	result is a signed long int. returns the converted value in result , if any. If no conversion could be performed, zero is returned.
Function:	The strtol function converts the initial portion of the string pointed to by nptr to a signed long int representation in some radix determined by the value of base. The part of the string after conversion is stored in the object pointed to endptr, provided that endptr is not a null pointer. If nptr is empty or does not have the expected form, no conversion is performed and the value of nptr is stored in the object pointed to by endptr, provided endptr is not a null pointer.
Availability:	All devices.
Requires:	#INCLUDE <stdlib.h>

Examples:	`signed long result;`
	`char str[9]="123hello";`
	`char *ptr;`
	`result=strtol(str,&ptr,10);`
	`//result is 123 and ptr is "hello"`

Example Files:	None
Also See:	strtod(), strtoul()

strtoul( )

Syntax:	**result=strtoul(***nptr***,***endptr***,** *base***)**
Parameters:	***nptr*** and ***endptr*** are strings pointers and ***base*** is an integer 2-36.
Returns:	result is an unsigned long int. returns the converted value in result , if any. If no conversion could be performed, zero is returned.
Function:	The strtoul function converts the initial portion of the string pointed to by nptr to a long int representation in some radix determined by the value of base. The part of the string after conversion is stored in the object pointed to endptr, provided that endptr is not a null pointer. If nptr is empty or does not have the expected form, no conversion is performed and the value of nptr is stored in the object pointed to by endptr, provided endptr is not a null pointer.

Availability:	All devices.
Requires:	STDLIB.H must be included

Examples:	`long result;`
	`char str[9]="123hello";`
	`char *ptr;`
	`result=strtoul(str,&ptr,10);`
	`//result is 123 and ptr is "hello"`

Example Files:	None
Also See:	strtol(), strtod()

swap( )

Syntax:	**swap (*lvalue*)**
Parameters:	***lvalue*** is a byte variable
Returns:	undefined - WARNING: this function does not return the result
Function:	Swaps the upper nibble with the lower nibble of the specified byte. This is the same as: byte = (byte << 4) | (byte >> 4);
Availability:	All devices.
Requires:	Nothing

Examples:	`x=0x45;`
	`swap(x);`
	`//x now is 0x54`

Example Files:	None
Also See:	rotate_right(), rotate_left()

tolower( ) toupper( )

Syntax:	**result = tolower (*cvalue*)** **result = toupper (*cvalue*)**
Parameters:	***cvalue*** is a character

Returns:	An 8 bit character
Function:	These functions change the case of letters in the alphabet. TOLOWER(X) will return 'a'..'z' for X in 'A'..'Z' and all other characters are unchanged. TOUPPER(X) will return 'A'..'Z' for X in 'a'..'z' and all other characters are unchanged.
Availability:	All devices.
Requires:	Nothing

Examples:	`switch( toupper(getc()) ) {`
	`   case 'R' : read_cmd();  break;`
	`   case 'W' : write_cmd(); break;`
	`   case 'Q' : done=TRUE;   break;`
	`}`

Example Files:	ex_str.c
Also See:	None

touchpad_getc( )

Syntax:	**input = TOUCHPAD_GETC( );**
Parameters:	None
Returns:	char (returns corresponding ASCII number is “input” declared as int)
Function:	Actively waits for firmware to signal that a pre-declared Capacitive Sensing Module (CSM) or charge time measurement unit (CTMU) pin is active, then stores the pre-declared character value of that pin in “input”. Note: Until a CSM or CTMU pin is read by firmware as active, this instruction will cause the microcontroller to stall.
Availability:	All PIC's with a CSM or CTMU Module
Requires:	#USE TOUCHPAD (options)

Examples:	`//When the pad connected to PIN_B0 is activated, store the letter 'A'`
	
	`#USE TOUCHPAD (PIN_B0='A')`
	`void main(void){`
	`     char c;`
	`     enable_interrupts(GLOBAL);`

```
          c = TOUCHPAD_GETC();
             //will wait until one of declared pins is detected
             //if PIN_B0 is pressed, c will get value 'A'
     }
```

Example Files:	None
Also See:	#USE TOUCHPAD, touchpad_state( )

touchpad_hit( )

Syntax:	**value = TOUCHPAD_HIT( )**
Parameters:	None
Returns:	TRUE or FALSE
Function:	Returns TRUE if a Capacitive Sensing Module (CSM) or Charge Time Measurement Unit (CTMU) key has been pressed. If TRUE, then a call to touchpad_getc() will not cause the program to wait for a key press.
Availability:	All PIC's with a CSM or CTMU Module
Requires:	#USE TOUCHPAD (options)
Examples:	see below

```
// When the pad connected to PIN_B0 is activated, store the letter 'A'

#USE TOUCHPAD (PIN_B0='A')
void main(void){
     char c;
     enable_interrupts(GLOBAL);

     while (TRUE) {
     if ( TOUCHPAD_HIT() )
           //wait until key on PIN_B0 is pressed
     c = TOUCHPAD_GETC();       //get key that was pressed
     }                          //c will get value 'A'
}
```

Example Files:	None
Also See:	#USE TOUCHPAD ( ), touchpad_state( ), touchpad_getc( )

touchpad_state( )

Syntax:	**TOUCHPAD_STATE** *(state)***;**
Parameters:	***state*** is a literal 0, 1, or 2.
Returns:	None
Function:	Sets the current state of the touchpad connected to the Capacitive Sensing Module (CSM). The state can be one of the following three values: 0 : Normal state 1 : Calibrates, then enters normal state 2 : Test mode, data from each key is collected in the int16 array TOUCHDATA Note: If the state is set to 1 while a key is being pressed, the touchpad will not calibrate properly.
Availability:	All PIC's with a CSM Module
Requires:	#USE TOUCHPAD (options)
Examples:	see below
Example Files:	None
Also See:	#USE TOUCHPAD, touchpad_getc( ), touchpad_hit( )

```
#USE TOUCHPAD (THRESHOLD=5, PIN_D5='5', PIN_B0='C')
void main(void){
     char c;
     TOUCHPAD_STATE(1);     //calibrates, then enters normal state
     enable_interrupts(GLOBAL);
     while(1){
           c = TOUCHPAD_GETC();
                //will wait until one of declared pins is detected
     }
                //if PIN_B0 is pressed, c will get value 'C'
}               //if PIN_D5 is pressed, c will get value '5'
```

tx_buffer_available()

Syntax:	**value = tx_buffer_available([**stream]**);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE RS232.
Returns:	Number of bytes that can still be put into transmit buffer
Function:	Function to determine the number of bytes that can still be put into transmit buffer before it

	overflows. Transmit buffer is implemented has a circular buffer, so be sure to check to make sure there is room for at least one more then what is actually needed.
Availability:	All devices
Requires:	#USE RS232

Examples:	`#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50)`
	`void main(void) {`
	`   unsigned int8 Count = 0;`
	
	`   while(TRUE){`
	`      if(tx_buffer_available()>13)`
	`         printf("/r/nCount=%3u",Count++);`
	`   }`
	`}`

Example Files:	None
Also See:	_USE_RS232( ), rcv( ), TX_BUFFER_FULL( ), RCV_BUFFER_BYTES( ), GET( ), PUTC( ) ,PRINTF( ), SETUP_UART( ), PUTC_SEND( )

tx_buffer_bytes()

Syntax:	**value = tx_buffer_bytes([**stream**]);**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE RS232.
Returns:	Number of bytes in transmit buffer that still need to be sent.
Function:	Function to determine the number of bytes in transmit buffer that still need to be sent.
Availability:	All devices
Requires:	#USE RS232

Examples:	#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50)
	void main(void) {
	   char string[] = “Hello”;
	   if(tx_buffer_bytes() <= 45)
	   printf(“%s”,string);
	}

Example Files:	None
Also See:	_USE_RS232( ), RCV_BUFFER_FULL( ), TX_BUFFER_FULL( ), RCV_BUFFER_BYTES( ), GET( ), PUTC( ) ,PRINTF( ), SETUP_UART( ), PUTC_SEND( )

tx_buffer_full( )

Syntax:	**value = tx_buffer_full([stream])**
Parameters:	**stream** – optional parameter specifying the stream defined in #USE RS232
Returns:	TRUE if transmit buffer is full, FALSE otherwise.
Function:	Function to determine if there is room in transmit buffer for another character.
Availability:	All devices
Requires:	#USE RS232

Examples:	#USE_RS232(UART1,BAUD=9600,TRANSMIT_BUFFER=50)
	void main(void) {
	   char c;
	
	   if(!tx_buffer_full())
	   putc(c);
	}

Example Files:	None
Also See:	_USE_RS232( ), RCV_BUFFER_FULL( ), TX_BUFFER_FULL( )., RCV_BUFFER_BYTES( ), GETC( ), PUTC( ), PRINTF( ), SETUP_UART( )., PUTC_SEND( )

va_arg( )

Syntax:	**va_arg(**argptr**,** type)
Parameters:	**argptr** is a special argument pointer of type va_list **type** – This is data type like int or char.
Returns:	The first call to va_arg after va_start return the value of the parameters after that specified by the last parameter. Successive invocations return the values of the remaining arguments in succession.
Function:	The function will return the next argument every time it is called.
Availability:	All devices.
Requires:	#INCLUDE <stdarg.h>

Examples:	`int foo(int num, ...)`
	`{`
	`int sum = 0;`
	`int i;`
	`va_list argptr;  // create special argument pointer`
	`va_start(argptr,num);  // initialize argptr`
	`for(i=0; i<num; i++)`
	`   sum = sum + va_arg(argptr, int);`

```
va_end(argptr);  // end variable processing
return sum;
}
```

Example Files:	None
Also See:	nargs(), va_end(), va_start()

va_end( )

Syntax:	**va_end(**argptr**)**
Parameters:	**argptr** is a special argument pointer of type va_list.
Returns:	None
Function:	A call to the macro will end variable processing. This will facillitate a normal return from the function whose variable argument list was referred to by the expansion of va_start().
Availability:	All devices.
Requires:	#INCLUDE <stdarg.h>

Examples:

```
int foo(int num, ...)
{
int sum = 0;
int i;
va_list argptr;  // create special argument pointer
va_start(argptr,num);  // initialize argptr
for(i=0; i<num; i++)
   sum = sum + va_arg(argptr, int);
va_end(argptr);  // end variable processing
return sum;
}
```

Example Files:	None
Also See:	nargs(), va_start(), va_arg()

va_start

Syntax:	**va_start(**argptr**,** variable**)**
Parameters:	**argpt**r is a special argument pointer of type va_list

	variable – The second parameter to va_start() is the name of the last parameter before the variable-argument list.
Returns:	None
Function:	The function will initialize the argptr using a call to the macro va_start().
Availability:	All devices.
Requires:	#INCLUDE <stdarg.h>
Examples:	see below
Example Files:	None
Also See:	nargs(), va_start(), va_arg()

```
int foo(int num, ...)
{
int sum = 0;
int i;
va_list argptr;  // create special argument pointer
va_start(argptr,num);  // initialize argptr
for(i=0; i<num; i++)
   sum = sum + va_arg(argptr, int);
va_end(argptr);  // end variable processing
return sum;
}
```

write_bank( )

Syntax:	**write_bank (***bank***,** *offset***,** *value***)**
Parameters:	***bank*** is the physical RAM bank 1-3 (depending on the device) ***offset*** is the offset into user RAM for that bank (starts at 0) ***value*** is the 8 bit data to write
Returns:	undefined
Function:	Write a data byte to the user RAM area of the specified memory bank. This function may be used on some devices where full RAM access by auto variables is not efficient. For example on the PIC16C57 chip setting the pointer size to 5 bits will generate the most efficient ROM code however auto variables can not be above 1Fh. Instead of going to 8 bit pointers you can save ROM by using this function to write to the hard to reach banks. In this case the bank may be 1-3 and the offset may be 0-15.
Availability:	All devices but only useful on PCB parts with memory over 1Fh and PCM parts with memory over FFh.
Requires:	Nothing

Examples:	`i=0;       // Uses bank 1 as a RS232 buffer`
	`do {`
	`   c=getc();`
	`   write_bank(1,i++,c);`
	`} while (c!=0x13);`

Example Files:	ex_psp.c
Also See:	See the "Common Questions and Answers" section for more information.

write_configuration_memory( )

Syntax:	**write_configuration_memory (**[offset], dataptr,count**)**
Parameters:	***dataptr***: pointer to one or more bytes ***count***: a 8 bit integer **offset** is an optional parameter specifying the offset into configuration memory to start writing to, offset defaults to zero if not used.
Returns:	undefined
Function:	For PIC18 devices-Erases all fuses and writes count bytes from the dataptr to the configuration memory. For Enhanced16 devices - erases and write User ID memory.
Availability:	All PIC18 Flash and Enhanced16 devices
Requires:	Nothing

Examples:	`int data[6];`
	`write_configuration_memory(data,6)`

Example Files:	None
Also See:	WRITE_PROGRAM_MEMORY(), Configuration Memory Overview

write_eeprom( )

Syntax:	**write_eeprom (***address*, *value***)**
Parameters:	***address*** is a (8 bit or 16 bit depending on the part) int, the range is device dependent ***value*** is an 8 bit int

Returns:	undefined
Function:	Write a byte to the specified data EEPROM address. This function may take several milliseconds to execute. This works only on devices with EEPROM built into the core of the device. For devices with external EEPROM or with a separate EEPROM in the same package (like the 12CE671) see EX_EXTEE.c with CE51X.c, CE61X.c or CE67X.c. In order to allow interrupts to occur while using the write operation, use the #DEVICE option WRITE_EEPROM = NOINT. This will allow interrupts to occur while the write_eeprom() operations is polling the done bit to check if the write operations has completed. Can be used as long as no EEPROM operations are performed during an ISR.
Availability:	This function is only available on devices with supporting hardware on chip.
Requires:	Nothing

Examples:	`#define LAST_VOLUME  10    // Location in EEPROM`
	
	`volume++;`
	`write_eeprom(LAST_VOLUME,volume);`

Example Files:	ex_intee.c, ex_extee.c, ce51x.c, ce62x.c, ce67x.c
Also See:	read_eeprom(), write_program_eeprom(), read_program_eeprom(), data Eeprom Overview

write_external_memory( )

Syntax:	**write_external_memory(** *address*, *dataptr*, *count* **)**
Parameters:	**address** is 16 bits on PCM parts and 32 bits on PCH parts **dataptr** is a pointer to one or more bytes **count** is a 8 bit integer
Returns:	undefined
Function:	Writes count bytes to program memory from dataptr to address. Unlike write_program_eeprom() and read_program_eeprom() this function does not use any special EEPROM/FLASH write algorithm. The data is simply copied from register address space to program memory address space. This is useful for external RAM or to implement an algorithm for external flash.
Availability:	Only PCH devices.
Requires:	Nothing

Examples:	`for(i=0x1000;i<=0x1fff;i++) {`
	`   value=read_adc();`
	`   write_external_memory(i, value, 2);`
	`   delay_ms(1000);`
	`}`

Example Files:	ex_load.c, loader.c
Also See:	write_program_eeprom(), erase_program eeprom(), Program Eeprom Overview

write_extended_ram( )

Syntax:	**write_extended_ram (**page,address,data,count**);**
Parameters:	**page** – the page in extended RAM to write to **address** – the address on the selected page to start writing to **data –** pointer to the data to be written **count** – the number of bytes to write (0-32768)
Returns:	undefined
Function:	To write data to the extended RAM of the PIC.
Availability:	On devices with more then 30K of RAM.
Requires:	Nothing

Examples:	`unsigned int8 data[8] = {0x01,0x02,0x03,0x04,0x05,0x06,0x07,0x08};`
	
	`write_extended_ram(1,0x0000,data,8);`

Example Files:	None
Also See:	read_extended_ram(), Extended RAM Overview

write_program_eeprom( )

Syntax:	**write_program_eeprom (***address*, *data***)**
Parameters:	***address*** is 16 bits on PCM parts and 32 bits on PCH parts, ***data*** is 16 bits. The least significant bit should always be 0 in PCH.
Returns:	undefined
Function:	Writes to the specified program EEPROM area. See our write_program_memory() for more information on this function.
Availability:	Only devices that allow writes to program memory.

Requires:	Nothing
Examples:	`write_program_eeprom(0,0x2800);     //disables program`
Example Files:	ex_load.c, loader.c
Also See:	read_program_eeprom(), read_eeprom(), write_eeprom(), write_program_memory(), erase_program_eeprom(), Program Eeprom Overview

zdc_status( )

Syntax:	**value=zcd_status()**
Parameters:	*None*
Returns:	value - the status of the ZCD module. The following defines are made in the device's header file and are as follows: • ZCD_IS_SINKING • ZCD_IS_SOURCING
Function:	To determine if the Zero-Cross Detection (ZCD) module is currently sinking or sourcing current. If the ZCD module is setup to have the output polarity inverted, the value return will be reversed.
Availability:	All devices with a ZCD module.
Examples:	`value=zcd_status():`
Example Files:	None
Also See:	setup_zcd()

STANDARD C INCLUDE FILES

errno.h

errno.h	
EDOM	Domain error value
ERANGE	Range error value
errno	error value

float.h

float.h	
FLT_RADIX:	Radix of the exponent representation
FLT_MANT_DIG:	Number of base digits in the floating point significant
FLT_DIG:	Number of decimal digits, q, such that any floating point number with q decimal digits can be rounded into a floating point number with p radix b digits and back again without change to the q decimal digits.
FLT_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating-point number.
FLT_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating-point numbers.
FLT_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating-point number.
FLT_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range representable finite floating-point numbers.
FLT_MAX:	Maximum representable finite floating point number.
FLT_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
FLT_MIN:	Minimum normalized positive floating point number
DBL_MANT_DIG:	Number of base digits in the floating point significant
DBL_DIG:	Number of decimal digits, q, such that any floating point number with q decimal digits can be rounded into a floating point number with p radix b digits and back again without change to the q decimal digits.
DBL_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating point number.
DBL_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating point numbers.
DBL_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating point number.
DBL_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range of representable finite floating point numbers.
DBL_MAX:	Maximum representable finite floating point number.
DBL_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
DBL_MIN:	Minimum normalized positive floating point number.
LDBL_MANT_DIG:	Number of base digits in the floating point significant
LDBL_DIG:	Number of decimal digits, q, such that any floating point number with q decimal digits can be rounded into a floating point number with p radix b digits and back again without change to the q decimal digits.

LDBL_MIN_EXP:	Minimum negative integer such that FLT_RADIX raised to that power minus 1 is a normalized floating-point number.
LDBL_MIN_10_EXP:	Minimum negative integer such that 10 raised to that power is in the range of normalized floating-point numbers.
LDBL_MAX_EXP:	Maximum negative integer such that FLT_RADIX raised to that power minus 1 is a representable finite floating-point number.
LDBL_MAX_10_EXP:	Maximum negative integer such that 10 raised to that power is in the range of representable finite floating-point numbers.
LDBL_MAX:	Maximum representable finite floating point number.
LDBL_EPSILON:	The difference between 1 and the least value greater than 1 that is representable in the given floating point type.
LDBL_MIN:	Minimum normalized positive floating point number.

limits.h

limits.h	
CHAR_BIT:	Number of bits for the smallest object that is not a bit_field.
SCHAR_MIN:	Minimum value for an object of type signed char
SCHAR_MAX:	Maximum value for an object of type signed char
UCHAR_MAX:	Maximum value for an object of type unsigned char
CHAR_MIN:	Minimum value for an object of type char(unsigned)
CHAR_MAX:	Maximum value for an object of type char(unsigned)
MB_LEN_MAX:	Maximum number of bytes in a multibyte character.
SHRT_MIN:	Minimum value for an object of type short int
SHRT_MAX:	Maximum value for an object of type short int
USHRT_MAX:	Maximum value for an object of type unsigned short int
INT_MIN:	Minimum value for an object of type signed int
INT_MAX:	Maximum value for an object of type signed int
UINT_MAX:	Maximum value for an object of type unsigned int
LONG_MIN:	Minimum value for an object of type signed long int
LONG_MAX:	Maximum value for an object of type signed long int
ULONG_MAX:	Maximum value for an object of type unsigned long int

locale.h

locale.h	
locale.h	(Localization not supported)
lconv	localization structure
SETLOCALE()	returns null
LOCALCONV()	returns clocale

setjmp.h

setjmp.h	
jmp_buf:	An array used by the following functions
setjmp:	Marks a return point for the next longjmp
longjmp:	Jumps to the last marked point

stddef.h

stddef.h	
ptrdiff_t:	The basic type of a pointer
size_t:	The type of the sizeof operator (int)
wchar_t	The type of the largest character set supported (char) (8 bits)
NULL	A null pointer (0)

stdio.h

stdio.h	
stderr	The standard error s stream (USE RS232 specified as stream or the first USE RS232)
stdout	The standard output stream (USE RS232 specified as stream last USE RS232)
stdin	The standard input s stream (USE RS232 specified as stream last USE RS232)

stdlib.h

stdlib.h	
div_t	structure type that contains two signed integers (quot and rem).
ldiv_t	structure type that contains two signed longs (quot and rem
EXIT_FAILURE	returns 1
EXIT_SUCCESS	returns 0
RAND_MAX-	
MBCUR_MAX-	1
SYSTEM()	Returns 0(not supported)
Multibyte character and string functions:	Multibyte characters not supported
MBLEN()	Returns the length of the string.
MBTOWC()	Returns 1.
WCTOMB()	Returns 1.
MBSTOWCS()	Returns length of string.
WBSTOMBS()	Returns length of string.

Stdlib.h functions included just for compliance with ANSI C.

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