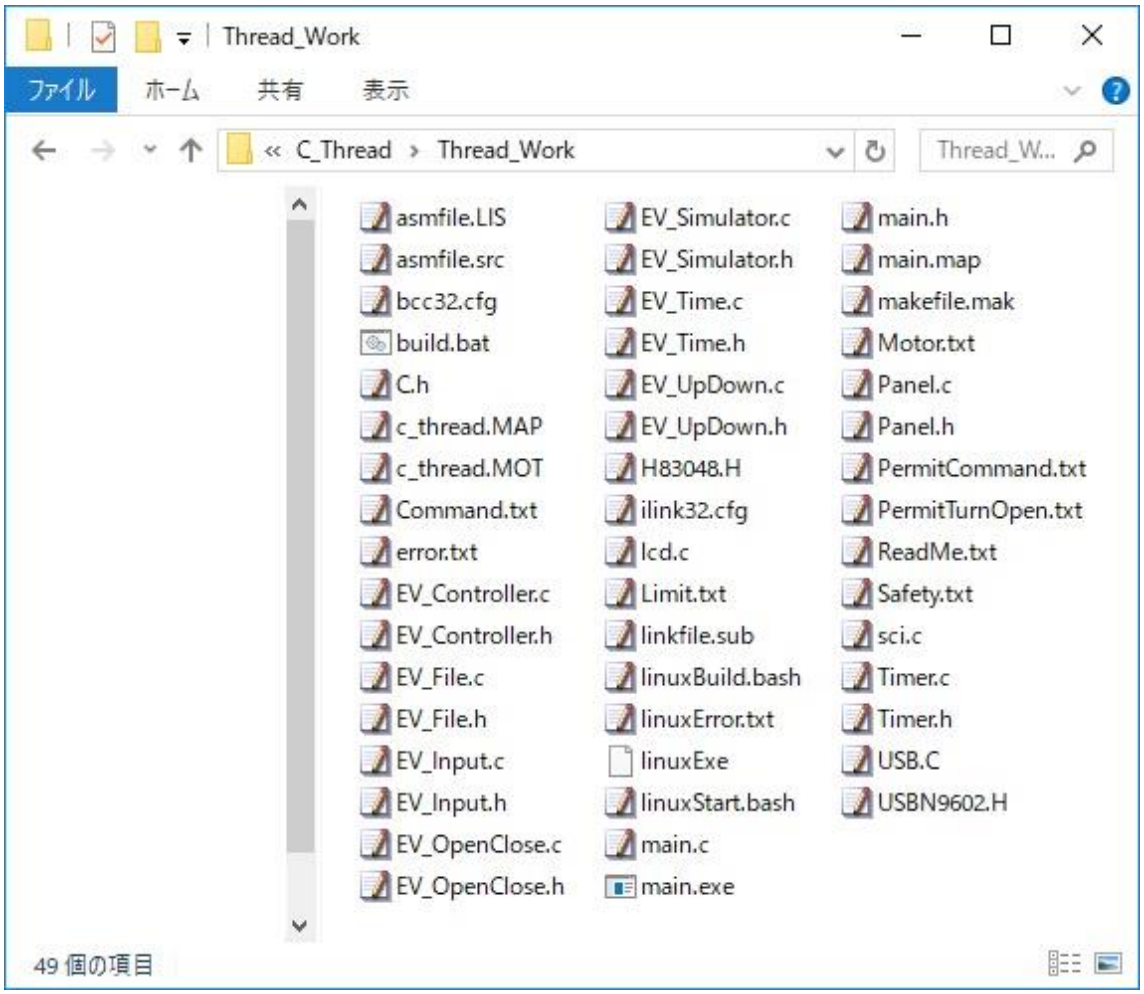
発明の巻

C 言語の疑似スレッド最新版(ライセンスフリー) のサポートパック(324,000 円)

スレッドとは、コンピュータープログラミング上の、並列処理の機能です。スレッドをサポートしているプログラミング言語と、スレッドをサポートしていないプログラミング言語があります。高度な機能のスレッドをわざとサポートしない言語があるのは、パソコン以外の環境で実行するために、低レベルマイコン対応のプログラミング言語でいるから(例えば C 言語)です。代わりにマイコンにはインターバルタイマがあります。今回、マイコンのインターバルタイマを使用して、並行処理タイプのスレッド(疑似スレッドと命名)を作成しました。C 言語のスレッドです。低レベル環境に移植可能です。(16bit 以上)サンプルに、エレベーターのプログラムが入っています。「コントローラ」「シミュレータ」の 2 つのプログラムを並行処理技術により連携しながら同時実行するように開発しました。プロセスが 1 個でスレッド(プログラム)が複数で動かせます。LINUX よりも前の世代のマイコンはプロ

セスが１個しか入らないでしょうから。C，Assembly，Batch Shell Script 使用。2018 年 3 月 11 日版プログラムです。初期デバッグ対応します。日本語で、日本国内で、初期サポート対応可能です。改造は自己責任でお願いします。324,000 円の中身は初期サポート代です。サンプルコードは開発終了品です。購入後、ご自由に、使用・改造・配布、O.K.です。

お問い合わせ先： info@hidemine.ciao.jp



発明アルゴリズムに疑似スレッドと名付けました。本物に偽物と名付けました。特許申請はしないで、無料公開をいたしました。発明という手段で人類としてのノルマを達成し、また、生きた証が発生いたしました。篠宮氏を逆賊に祭り上げようとする人種がいます。篠宮氏は辞退いたします。秋篠宮家様は本物の皇族ですが、篠宮氏は偽物です。

タイトル(title):

C 言語の疑似スレッド

サブタイトル(subtitle):

C 言語の偽物のスレッド

The thread at the imitation of the C language.

似ているが独創的な別物

The resembling but original singleton.

C 言語によるスレッドという概念の模倣

Copying a concept,

the thread, by the C language.

解説

C言語のプロジェクト Thread について、

このプロジェクトは予告なくデバッグ目的で更新されることがあります。

このプロジェクトは、お客様が改造して、よりお客様に使いやすい
プログラムにするために、提供されるサンプルプログラムであり、
お客様の好みに完成させてください。

==========

Borland BCC C/C++ のダウンロードとインストール
bcc コンパイラー で検索します
C++Builder のホームページを開きます
C++ Compiler 5.5 / Turbo Debugger (日本語) (コンパイラのみで軽い)
(テキストエディタと組み合わせて使用します)(フリーソフト)
(ユーザー登録が必要)(メールアドレスが必要)をダウンロードして
解凍します
freecommandlinetools2.exeをインストールします
freeturbodebugger.exeをインストールします

AKI-H8 3052F USB開発セット の購入
メーカー： ルネサスエレクトロニクスさん
販売者： 秋月電子通商さん
通販コード： K-00182
商品名： AKI-H8 3052F USB開発セット
商品価格： 税込7,000円 (2018年3月6日現在)
AKI-H8 3052F USB開発セット で検索します
AKI-H8 3052F USB開発セット を 秋月電子通商さん の通販サイトで購入

するか、それとも ご自宅の最寄りの電子パーツ専門店 で注文購入します

もしも、 AKI-H8 3052F USB開発セット に ACアダプター が

入っていなかったら(私は未確認です)、 ご自宅の最寄りの

電子パーツ専門店の人 に 電流・電圧 を聞いて、 ACアダプター も、

購入してください

RS-232Cケーブル と 延長USBコード を ご自宅の最寄りの

電子パーツ専門店 で注文購入します

RS-232C は、パソコンに端子がある必要があり、また、パソコンと

AKI-H8基板 の両方の コネクタ の オス端子・メス端子 を確認して

購入してください

延長USBコード も オス端子・メス端子 を確認してください

カラー短絡ソケット6mm 青 2228CG-BU で検索します

カラー短絡ソケット6mm 青 2228CG-BU のような 短絡コネクタ を、

ご自宅の最寄りの電子パーツ専門店 で 1個 注文購入します

(100円 か 200円 支払うと何個かまとめて購入できます)

USB開発セット のマニュアルに従い、 usbフォルダ の main.c を

コンパイルして、 H8WriteTurbo をインストールして、 AKI-H8基板

への書き込み時に、 短絡ソケット を使用して、マニュアルに従い

モードを調節して、 usbフォルダ の usbtest.MOT を AKI-H8基板

へ書き込み、走らせてみます

押しボタンを押すと、sw1 sw2 sw3 sw4 などと 液晶パネル に

表示されれば大丈夫です。

C_Threadフォルダ の中の、 Thread_Workフォルダ の中の、 c_thread.MOT

を、モードを調節しながら、 AKI-H8基板 へ書き込み、走らせてみます

液晶パネル ・ 押しボタン ・ LED などが機能していれば、成功です

Linux CentOS6 の利用

私は、 CentOS にしましたが、 linuxBuild.bash ・ linuxStart.bash

が読める方は、お好きな Linux で挑戦してみてください

==========

asmfile.src について。

リセットベクトル の 転送先ラベル が _start になっています。

ずっと下の方の _start の ラベル から処理を開始して、

jsr @_main

で C言語の関数main を呼び出しています。

C言語の関数main は、 void main(void); という形で、

main.c に記述があります。

その後、

int_error:

rte

で rte (returnと同じ意味) で終了しています。

リセットベクトル に続く1番から60番までの 割り込みベクトル について、

使用しない 割り込みベクトル は ラベルint_error に転送されます。

;26 OVI0

_INT_OVI0: .DATA.L _ITU_OVI_0 ;タイマ0割り込み

で、 タイマ0割り込み は、 ラベル_ITU_OVI_0 に転送されます。

ラベル_ITU_OVI_0 から開始して、 スタック 退避をして、

jsr @_InterruptITU0

で、 C言語の関数InterruptITU0 を呼び出しています。

C言語の関数InterruptITU0 は void InterruptITU0(void); という形で、
Timer.h Timer.c に記述があります。

戻ってくると、再び スタック を戻して、 rte です。

ファイルの先頭に、

```
 .IMPORT       _main
 .IMPORT _InterruptITU0
```

という記述があり、 C言語の関数 を参照しています。

```
 .EXPORT _EnableInterrupt,_DisableInterrupt
_EnableInterrupt:
 andc.b #H'3f,ccr
 rts
_DisableInterrupt:
 orc.b #H'c0,ccr
 rts
```

で、C言語から
_EnableInterrupt (割り込み許可)
_DisableInterrupt (割り込み禁止)
を呼び出せるようにしています。
C言語の Panel.h に 外部参照プロトタイプ宣言 があります。

```
extern void EnableInterrupt(void);
extern void DisableInterrupt(void);
```

C言語からの呼び出し名は、

```
EnableInterrupt();
DisableInterrupt();
```

です。

==========

main.c の 関数 Run の ID==31 を見てください。

Thread Ready GO! で開始して競馬のコースが8コースあります。

Thread Ready GO! There are 8 cources on a race.

ゴールまで14歩です。

There are 80 cells to a GOAL.

<1>コースは'r'ボタンが鞭で<2>コースは'l'ボタンが鞭です。

For the <1> cource, You click a 'R' button.

For the <2> cource, You click a 'L' button.

スレッドを使用しています。

Thread *th[8]; でオブジェクト宣言しています。

th[i] = new_Thread(i + 1); で初期値設定しています。

この2行は Java で次と同じ意味です。

```
Thread th[] = new Thread[8];
th[i] = new Thread(i + 1);

void Repaint(void)
{
    ...
}
void Run(Thread *This)
{
```

```
	...
}
void Init(Thread *This)
{
	...
}
void Destroy(Thread *This)
{
	...
}
```

はそれぞれ Java で次と同じ意味です。

```
public void paint(Graphics g)
{
	...
}
public void run()
{
	...
}
public void init()
{
	...
}
public void destroy()
{
	...
}
```

delete_(th[i]); でオブジェクトを消去しています。

この1行は C++ で次と同じ意味です。

delete th[i];

スレッド20が走り始めたら、

0以外の数字キーを押してみてください。

その数字に20を加えた番号のスレッドが、キーを押す度毎に、

起動・消去を繰り返します。

20を含めて、全部スレッドが消去されると、終了です。

これらのスレッドに関する仕様は Timer.c に記述しました。

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2階建エレベーターEVについて

使用方法

EV_Simulator にエレベーターが表示されます

EV_Controller にエレベーターの動作が表示されます

EV_Input の使用方法

u キーを押すとエレベーターが2階に上昇して扉が開きます

d キーを押すとエレベーターが1階に下降して扉が開きます

o キーを押すと扉が開きます

c キーを押すと扉が閉じます

s キーを押すと籠が非常停止します

r キーを押すと籠が非常停止から復帰します

Y キーを押すとエレベーターが2階に上昇して扉が開きます

H キーを押すと2階で扉が閉じます

y キーを押すとエレベーターが1階に下降して扉が開きます

h キーを押すと1階で扉が閉じます

籠が無い階で H h キーを押しても籠は動作しません

籠が無い階で Y y キーを押したとき籠の扉が開いていると籠は動作しません

開いた状態の扉は一定時間後自動で閉じます

EV_Time.h に #define OPENTIMEOUT 10 と書いてあるので 10秒 です

閉まりかけの時に開く動作をするキーを押すと扉が反転して開きます

動作説明

全体の動作説明

モーターの情報は Motor.txt にあります

エレベーター塔内のリミットスイッチの情報は Limit.txt にあります

EV_Simulator はエレベーターの次の位置を出力していて Safety.txt

Motor.txt Limit.txt を採取して Safety.txt Limit.txt に書き込んで

エレベーターの画面表示もしています

EV_Controller はエレベータを制御していて Command.txt Limit.txt

を採取して PermitCommand.txt Motor.txt に書き込んでいます

EV_Controllerの動作説明

エレベーターには現在位置情報(Limit.txt)があります

最簡形の2階建ての場合通常系には5個の位置状態があります

下の階の停止状態

下の階の低速区域

中間の高速区域

上の階の低速区域

上の階の停止状態

5個の区域の境界に合計4個のセンサーがあります

4個のセンサーがエレベーターの現在位置を取得しています

4個のセンサーからの信号はメンバ変数(Positionクラスの

*p_UnderSlow *p_UnderStop *p_UpperSlow *p_UpperStop)

に読み込みます

昇りのメソッド(UpMotorクラスのOnUpMotor)と降りのメソッド

(DownMotorクラスのOnDownMotor)で使って

モーターに出力(Motor.txtに出力)します

全く同じ様にドアも通常系で4個のセンサーがありドアの開閉では

エレベーターの昇降と全く同じクラス構造です

後はインスタンス(Position P UpMotor UPMT DownMotor DNMT

Door DR OpenMotor OPMT CloseMotor CLMT)

を宣言して仕様に合わせてメソッドを呼び出すだけでO.K.です

終了方法

エレベーターが通常停止しているときに q キーを押します

メンテナンス

異常終了した場合、終了後、Thread_Work フォルダの次のファイルを

チェックしてください

Safety.txt

Safety.txt を開いて r にして上書き保存してください

r は通常動作を意味します

s は非常停止を意味します

h は復帰を意味します

Y はスターデルタのスター起動を意味します

Command.txt

Command.txt を開いて q にして上書き保存してください

q は終了を意味します

u は上昇を意味します

d は下降を意味します

o は開を意味します

c は閉を意味します

Y は上階呼びを意味します

y は下階呼びを意味します

H は上階閉を意味します

h は下階閉を意味します

N は信号無しを意味します

PermitCommand.txt

PermitCommand.txt を開いて c にして上書き保存してください

N は命令入力禁止を意味します

c は命令入力許可を意味します

PermitTurnOpen.txt

PermitTurnOpen.txtを開いて N にして上書き保存してください

N は反転開信号入力禁止を意味します

o は反転開信号入力許可を意味します

Motor.txt

Motor.txt を開いて s にして上書き保存してください

s はモーター停止を意味します

j はモーター上昇回転開始を意味します

u はモーター低速上昇回転を意味します

U はモーター高速上昇回転を意味します

k はモーター下降回転開始を意味します

d はモーター低速下降回転を意味します

D はモーター高速下降回転を意味します

h はモーター開回転開始を意味します

o はモーター低速開回転を意味します

O はモーター高速開回転を意味します

t はモーター閉回転開始を意味します

c はモーター低速閉回転を意味します

C はモーター高速閉回転を意味します

Limit.txt

Limit.txt を開いて yynnyynn にして上書き保存してください

yynnyynn は籠が下階停止状態で扉が閉停止状態であることを意味します

yynnnynn は籠が下階停止状態で扉が閉低速区域であることを意味します

yynnnnnn は籠が下階停止状態で扉が中間高速区域であることを意味します

yynnnnyn は籠が下階停止状態で扉が開低速区域であることを意味します

yynnnnyy は籠が下階停止状態で扉が開停止状態であることを意味します

nynnyynn は籠が下階低速区域で扉が閉停止状態であることを意味します

nnnnyynn は籠が中間高速区域で扉が閉停止状態であることを意味します

nnynyynn は籠が上階低速区域で扉が閉停止状態であることを意味します

nnyyyynn は籠が上階停止状態で扉が閉停止状態であることを意味します

nnyynynn は籠が上階停止状態で扉が閉低速区域であることを意味します

nnyynnnn は籠が上階停止状態で扉が中間高速区域であることを意味します

nnyynnyn は籠が上階停止状態で扉が開低速区域であることを意味します

nnyynnyy は籠が上階停止状態で扉が開停止状態であることを意味します

==========

Linux CentOS6 の GCC を使用するときは、文字コードを utf8 にして

改行コードを <LF>のみ(UNIX) にして名前を付けて保存してください

makefile.mak build.bat asmfile.src linkfile.sub linuxBuild.bash は

複数のファイルを1個のプロジェクトとして

コンパイルするためのファイルです。

error.txt linuxError.txt はコンパイルエラーを表示するファイルです。

main.exe をダブルクリックすると、BCC実行ソフトが起動します。

c_thread.MOT を AKI-H8 3052F USB に書き込みます。

linuxStart.bash をダブルクリックすると、

GCC実行ソフト linuxExe が起動します。

参照ライブラリ

```
/************************************************************************/
/*      H8/3048F Include File                                           */
/************************************************************************/
struct st_sam {                         /* struct DMAC  */
      void              *MAR;           /* MAR          */
      unsigned int      ETCR;           /* ETCR         */
      unsigned char     IOAR;           /* IOAR         */
      unsigned char     DTCR;           /* DTCR         */
};

struct st_fam {                         /* struct DMAC  */
      void              *MARA;          /* MARA         */
      unsigned int      ETCRA;          /* ETCRA        */
      unsigned char     IOARA;          /* IOAR         */
      unsigned char     DTCRA;          /* DTCRA        */
      void              *MARB;          /* MARB         */
      unsigned int      ETCRB;          /* ETCRB        */
      unsigned char     IOARB;          /* IOAR         */
      unsigned char     DTCRB;          /* DTCRB        */
};

struct st_itu {                         /* struct ITU   */
      unsigned char     TSTR;           /* TSTR         */
      unsigned char     TSNC;           /* TSNC         */
      unsigned char     TMDR;           /* TMDR         */
      unsigned char     TFCR;           /* TFCR         */
      char              wk[44];         /*              */
      unsigned char     TOER;           /* TOER         */
      unsigned char     TOCR;           /* TOCR         */
};

struct st_itu0 {                        /* struct ITU0  */
      unsigned char     TCR;            /* TCR          */
      unsigned char     TIOR;           /* TIOR         */
      unsigned char     TIER;           /* TIER         */
      unsigned char     TSR;            /* TSR          */
      unsigned int      TCNT;           /* TCNT         */
      unsigned int      GRA;            /* GRA          */
      unsigned int      GRB;            /* GRB          */
};

struct st_itu3 {                        /* struct ITU3  */
      unsigned char     TCR;            /* TCR          */
      unsigned char     TIOR;           /* TIOR         */
      unsigned char     TIER;           /* TIER         */
      unsigned char     TSR;            /* TSR          */
      unsigned int      TCNT;           /* TCNT         */
      unsigned int      GRA;            /* GRA          */
      unsigned int      GRB;            /* GRB          */
      unsigned int      BRA;            /* BRA          */
      unsigned int      BRB;            /* BRB          */
      char              wk[2];          /*              */
};

struct st_tpc {                         /* struct TPC   */
      unsigned char     TPMR;           /* TPMR         */
      unsigned char     TPCR;           /* TPCR         */
```

```
    unsigned char   NDERB;      /* NDERB            */
    unsigned char   NDERA;      /* NDERA            */
    unsigned char   NDRB1;      /* NDRB (H'A4)  */
    unsigned char   NDRA1;      /* NDRA (H'A5)  */
    unsigned char   NDRB2;      /* NDRB (H'A6)  */
    unsigned char   NDRA2;      /* NDRA (H'A7)  */
};

struct st_rfshc {                   /* struct RFSHC */
    unsigned char   RFSHCR;     /* RFSHCR           */
    unsigned char   RTMCSR;     /* RTMCSR           */
    unsigned char   RTCNT;      /* RTCNT            */
    unsigned char   RTCOR;      /* RTCOR            */
};

struct st_sci {                     /* struct SCI   */
    unsigned char   SMR;        /* SMR              */
    unsigned char   BRR;        /* BRR              */
    unsigned char   SCR;        /* SCR              */
    unsigned char   TDR;        /* TDR              */
    unsigned char   SSR;        /* SSR              */
    unsigned char   RDR;        /* RDR              */
    char            wk[2];      /*                  */
};

struct st_p1 {                      /* struct P1    */
    unsigned char   DDR;        /* P1DDR            */
    char            wk;         /*                  */
    unsigned char   DR;             /* P1DR         */
};

struct st_p2 {                      /* struct P2    */
    unsigned char   DDR;        /* P2DDR            */
    char            wk1;        /*                  */
    unsigned char   DR;             /* P2DR         */
    char            wk2[20];    /*                  */
    unsigned char   PCR;        /* P2PCR            */
};

struct st_p4 {                      /* struct P4    */
    unsigned char   DDR;        /* P4DDR            */
    char            wk1;        /*                  */
    unsigned char   DR;             /* P4DR         */
    char            wk2[18];    /*                  */
    unsigned char   PCR;        /* P4PCR            */
};

struct st_p5 {                      /* struct P5    */
    unsigned char   DDR;        /* P5DDR            */
    char            wk1;        /*                  */
    unsigned char   DR;             /* P5DR         */
    char            wk2[16];    /*                  */
    unsigned char   PCR;        /* P5PCR            */
};

struct st_p6 {                      /* struct P6    */
    unsigned char   DDR;        /* P6DDR            */
```

```
	char		wk;		/*			*/
	unsigned char	DR;		/* P6DR		*/
};

struct st_p7 {			/* struct P7	*/
	unsigned char	DR;		/* P7DR		*/
};

struct st_p8 {			/* struct P8	*/
	unsigned char	DDR;		/* P8DDR		*/
	char		wk;		/*			*/
	unsigned char	DR;		/* P8DR		*/
};

struct st_p9 {			/* struct P9	*/
	unsigned char	DDR;		/* P9DDR		*/
	char		wk;		/*			*/
	unsigned char	DR;		/* P9DR		*/
};

struct st_da {			/* struct D/A	*/
	unsigned char	STCR;		/* DASTCR		*/
	char		wk[127];	/*			*/
	unsigned char	DR0;		/* DADR0		*/
	unsigned char	DR1;		/* DADR1		*/
	unsigned char	CR;		/* DACR		*/
};

struct st_ad {			/* struct A/D	*/
	unsigned int	DRA;		/* ADDRA		*/
	unsigned int	DRB;		/* ADDRB		*/
	unsigned int	DRC;		/* ADDRC		*/
	unsigned int	DRD;		/* ADDRD		*/
	unsigned char	CSR;		/* ADCSR		*/
	unsigned char	CR;		/* ADCR		*/
};

struct st_bsc {			/* struct BSC	*/
	unsigned char	CSCR;		/* CSCR		*/
	char		wk1[140];	/*			*/
	unsigned char	ABWCR;		/* ABWCR		*/
	unsigned char	ASTCR;		/* ASTCR		*/
	unsigned char	WCR;		/* WCR		*/
	unsigned char	WCER;		/* WCER		*/
	char		wk2[3];		/*			*/
	unsigned char	BRCR;		/* BRCR		*/
};

struct st_intc {		/* struct INTC	*/
	unsigned char	ISCR;		/* ISCR		*/
	unsigned char	IER;		/* IER		*/
	unsigned char	ISR;		/* ISR		*/
	char		wk;		/*			*/
	unsigned char	IPRA;		/* IPRA		*/
	unsigned char	IPRB;		/* IPRB		*/
};
```

```
#define DMAC0A  (*(volatile struct st_sam      *)0xFFFF20) /* DMAC 0A Addr */
#define DMAC0B  (*(volatile struct st_sam      *)0xFFFF28) /* DMAC 0B Addr */
#define DMAC1A  (*(volatile struct st_sam      *)0xFFFF30) /* DMAC 1A Addr */
#define DMAC1B  (*(volatile struct st_sam      *)0xFFFF38) /* DMAC 1B Addr */
#define DMAC0   (*(volatile struct st_fam      *)0xFFFF20) /* DMAC 0  Addr */
#define DMAC1   (*(volatile struct st_fam      *)0xFFFF30) /* DMAC 1  Addr */
#define ITU     (*(volatile struct st_itu      *)0xFFFF60) /* ITU       Address*/
#define ITU0    (*(volatile struct st_itu0     *)0xFFFF64) /* ITU0  Address*/
#define ITU1    (*(volatile struct st_itu0     *)0xFFFF6E) /* ITU1  Address*/
#define ITU2    (*(volatile struct st_itu0     *)0xFFFF78) /* ITU2  Address*/
#define ITU3    (*(volatile struct st_itu3     *)0xFFFF82) /* ITU3  Address*/
#define ITU4    (*(volatile struct st_itu3     *)0xFFFF92) /* ITU4  Address*/
#define TPC     (*(volatile struct st_tpc      *)0xFFFFA0) /* TPC       Address*/
#define RFSHC   (*(volatile struct st_rfshc *)0xFFFFAC) /* RFSHC Address*/
#define SCI0    (*(volatile struct st_sci      *)0xFFFFB0) /* SCI0  Address*/
#define SCI1    (*(volatile struct st_sci      *)0xFFFFB8) /* SCI1  Address*/
#define P1          (*(volatile struct st_p1       *)0xFFFFC0) /* P1        Address*/
#define P2          (*(volatile struct st_p2       *)0xFFFFC1) /* P2        Address*/
#define P3          (*(volatile struct st_p1       *)0xFFFFC4) /* P3        Address*/
#define P4          (*(volatile struct st_p4       *)0xFFFFC5) /* P4        Address*/
#define P5          (*(volatile struct st_p5       *)0xFFFFC8) /* P5        Address*/
#define P6          (*(volatile struct st_p6       *)0xFFFFC9) /* P6        Address*/
#define P7          (*(volatile struct st_p7       *)0xFFFFCE) /* P7        Address*/
#define P8          (*(volatile struct st_p8       *)0xFFFFCD) /* P8        Address*/
#define P9          (*(volatile struct st_p9       *)0xFFFFD0) /* P9        Address*/
#define PA          (*(volatile struct st_p1       *)0xFFFFD1) /* PA        Address*/
#define PB          (*(volatile struct st_p1       *)0xFFFFD4) /* PB        Address*/
#define DA          (*(volatile struct st_da       *)0xFFFF5C) /* D/A       Address*/
#define AD          (*(volatile struct st_ad       *)0xFFFFE0) /* A/D       Address*/
#define BSC     (*(volatile struct st_bsc      *)0xFFFF5F) /* BSC       Address*/
#define FLMCR   (*(volatile unsigned char  *)0xFFFF40) /* FLMCR Address*/
#define EBR1    (*(volatile unsigned char      *)0xFFFF42) /* EBR1  Address*/
#define EBR2    (*(volatile unsigned char      *)0xFFFF43) /* EBR2  Address*/
#define RAMCR   (*(volatile unsigned char  *)0xFFFF48) /* RAMCR Address*/
#define DIVCR   (*(volatile unsigned char  *)0xFFFF5D) /* DIVCR Address*/
#define MSTCR   (*(volatile unsigned char  *)0xFFFF5E) /* MSTCR Address*/
#define MDCR    (*(volatile unsigned char      *)0xFFFFF1) /* MDCR  Address*/
#define SYSCR   (*(volatile unsigned char *)0xFFFFF2) /* SYSCR Address*/
#define INTC    (*(volatile struct st_intc     *)0xFFFFF4) /* INTC  Address*/
#define st_itu1 st_itu0                                 /* Change Struct ITU1   */
#define st_itu2 st_itu0                                 /* Change Struct ITU2   */
#define st_itu4 st_itu3                                 /* Change Struct ITU4   */
#define st_p3   st_p1                                   /* Change Struct P3->P1 */
#define st_pa   st_p1                                   /* Change Struct PA->P1 */
#define st_pb   st_p1                                   /* Change Struct PB->P1 */
```

```
/*===============================================================
                        N9604 Address
===============================================================*/
#define     USB9602R        (*(volatile unsigned char *)0x400003)
#define     USB9602D        (*(volatile unsigned char *)0x400001)

/*===============================================================
                        N9604 Define
===============================================================*/
#define     USB_CLKDIV      0x04    /* CLKOUT = 48MHz/4 = 12MHz */


/* USB1.0リクエスト */
#define     USB_GET_STATUS          0
#define     USB_CLEAR_FEATURE       1
#define     USB_SET_FEATURE         3
#define     USB_SET_ADDRESS         5
#define     USB_GET_DESCRIPTOR      6
#define     USB_SET_DESCRIPTOR      7
#define     USB_GET_CONFIGURATION   8
#define     USB_SET_CONFIGURATION   9
#define     USB_GET_INTERFACE       10
#define     USB_SET_INTERFACE       11
#define     USB_SYNCH_FRAME         12

/* ディスクリプタ名 */
#define     USB_DEVICE              1
#define     USB_CONFIGURATION       2
```

```
#define     USB_XSTRING                 3
#define     USB_INTERFACE               4
#define     USB_ENDPOINT                5
#define     USB_HID                     0x21
#define     USB_HIDREPORT               0x22
#define     USB_HIDPHYSICAL             0x23

/* HIDリクエスト */
#define     USB_GET_REPORT              0x01
#define     USB_GET_IDLE                0x02
#define     USB_GET_PROTOCOL            0x03
#define     USB_SET_REPORT              0x09
#define     USB_SET_IDLE                0x0A
#define     USB_SET_PROTOCOL            0x0B


/*============================================================
                        N9604 Register
============================================================*/
#define     USB_MCNTRL              0x00    /*Main control register   */
#define     USB_CCONF               0x01    /*Clk. config. register   */
#define     USB_TCR                 0x02    /*Xcvr config. register   */
#define     USB_RID                 0x03    /*Rev. ID     register   */
#define     USB_FAR                 0x04    /*Func address register   */
#define     USB_NFSR                0x05    /*Node func st register   */
#define     USB_MAEV                0x06    /*Main event   register   */
#define     USB_MAMSK               0x07    /*Main mask    register   */
#define     USB_ALTEV               0x08    /*Alt. event   register   */
#define     USB_ALTMSK              0x09    /*ALT  mask    register   */
```

```
#define     USB_TXEV            0x0A   /*TX  event  register  */
#define     USB_TXMSK           0x0B   /*TX  mask   register  */
#define     USB_RXEV            0x0C   /*RX  event  register  */
#define     USB_RXMSK           0x0D   /*RX  mask   register  */
#define     USB_NAKEV           0x0E   /*NAK event  register  */
#define     USB_NAKMSK          0x0F   /*NAK mask   register  */
#define     USB_FWEV            0x10   /*FIFO warning register  */
#define     USB_FWMSK           0x11   /*FIFO warning mask     */
#define     USB_FNH             0x12   /*Frame nbr hi register  */
#define     USB_FNL             0x13   /*Frame nbr lo register  */
#define     USB_DMACNTRL        0x14   /*DMA  control register  */

#define     USB_EPC0            0x20   /*Endpoint0   register  */
#define     USB_TXD0            0x21   /*TX  data   register 0 */
#define     USB_TXS0            0x22   /*TX  status  register 0 */
#define     USB_TXC0            0x23   /*TX  command register 0 */

#define     USB_RXD0            0x25   /*RX  data   register 0 */
#define     USB_RXS0            0x26   /*RX  status  register 0 */
#define     USB_RXC0            0x27   /*RX  command register 0 */

#define     USB_EPC1            0x28   /*Endpoint1   register  */
#define     USB_TXD1            0x29   /*TX  data   register 1 */
#define     USB_TXS1            0x2A   /*TX  status  register 1 */
#define     USB_TXC1            0x2B   /*TX  command register 1 */

#define     USB_EPC2            0x2C   /*Endpoint2   register  */
#define     USB_RXD1            0x2D   /*RX  data   register 1 */
#define     USB_RXS1            0x2E   /*RX  status  register 1 */
```

```
#define     USB_RXC1                0x2F    /*RX   command register 1 */

#define     USB_EPC3                0x30    /*Endpoint3    register   */
#define     USB_TXD2                0x31    /*TX   data    register 2 */
#define     USB_TXS2                0x32    /*TX   status  register 2 */
#define     USB_TXC2                0x33    /*TX   command register 2 */

#define     USB_EPC4                0x34    /*Endpoint4    register   */
#define     USB_RXD2                0x35    /*RX   data    register 2 */
#define     USB_RXS2                0x36    /*RX   status  register 2 */
#define     USB_RXC2                0x37    /*RX   command register 2 */

#define     USB_EPC5                0x38    /*Endpoint5    register   */
#define     USB_TXD3                0x39    /*TX   data    register 3 */
#define     USB_TXS3                0x3A    /*TX   status  register 3 */
#define     USB_TXC3                0x3B    /*TX   command register 3 */

#define     USB_EPC6                0x3C    /*Endpoint6    register   */
#define     USB_RXD3                0x3D    /*RX   data    register 3 */
#define     USB_RXS3                0x3E    /*RX   status  register 3 */
#define     USB_RXC3                0x3F    /*RX   command register 3 */

/*---------- MCNTRL bits -------------*/
#define     USB_SRST                0x01    /*software reset        */
#define     USB_DBG                 0x02    /*debug mode            */
#define     USB_VGE                 0x04    /*voltage regulator enable*/
#define     USB_NAT                 0x08    /*node attached         */
#define     USB_INT_DIS             0x00    /*interrupts disabled    */
#define     USB_INT_L_O             0x40    /*act lo ints, open drain */
```

```
#define       USB_INT_H_P              0x80    /*act hi ints, push pull  */
#define       USB_INT_L_P              0xC0    /*act lo ints, push pull  */

/*------------ FAR bits --------------*/
#define       USB_AD_EN                0x80    /*address enable        */

/*------------ NFSR bits -------------*/
#define       USB_RST_ST               0x00    /*reset      state      */
#define       USB_RSM_ST               0x01    /*resume     state      */
#define       USB_OPR_ST               0x02    /*operational state      */
#define       USB_SUS_ST               0x03    /*suspend    state      */

/*-------- MAEV, MAMSK bits ---------*/
#define       USB_WARN                 0x01    /*warning bit has been set*/
#define       USB_ALT                  0x02    /*alternate event        */
#define       USB_TX_EV                0x04    /*transmit event         */
#define       USB_FRAME                0x08    /*SOF packet received    */
#define       USB_NAK                  0x10    /*NAK event              */
#define       USB_ULD                  0x20    /*unlock locked detected  */
#define       USB_RX_EV                0x40    /*receive event          */
#define       USB_INTR_E               0x80    /*master interrupt enable */

/*-------- ALTEV, ALTMSK bits --------*/
#define       USB_EOP                  0x08    /*end of packet          */
#define       USB_SD3                  0x10    /*3 ms suspend           */
#define       USB_SD5                  0x20    /*5 ms suspend           */
#define       USB_RESET_A              0x40    /*reset  detected        */
#define       USB_RESUME_A             0x80    /*resume detected        */
```

```
/*--------- TXEV, TXMSK bits ---------*/
#define     USB_TXFIFO0             0x01    /*TX_DONE, FIFO 0      */
#define     USB_TXFIFO1             0x02    /*TX_DONE, FIFO 1      */
#define     USB_TXFIFO2             0x04    /*TX_DONE, FIFO 2      */
#define     USB_TXFIFO3             0x08    /*TX_DONE, FIFO 3      */
#define     USB_TXUDRN0             0x10    /*TX_URUN, FIFO 0      */
#define     USB_TXUDRN1             0x20    /*TX_URUN, FIFO 1      */
#define     USB_TXUDRN2             0x40    /*TX_URUN, FIFO 2      */
#define     USB_TXUDRN3             0x80    /*TX_URUN, FIFO 3      */

/*--------- RXEV, RXMSK bits ---------*/
#define     USB_RXFIFO0             0x01    /*RX_DONE, FIFO 0      */
#define     USB_RXFIFO1             0x02    /*RX_DONE, FIFO 1      */
#define     USB_RXFIFO2             0x04    /*RX_DONE, FIFO 2      */
#define     USB_RXFIFO3             0x08    /*RX_DONE, FIFO 3      */
#define     USB_RXOVRN0             0x10    /*RX_OVRN, FIFO 0      */
#define     USB_RXOVRN1             0x20    /*RX_OVRN, FIFO 1      */
#define     USB_RXOVRN2             0x40    /*RX_OVRN, FIFO 2      */
#define     USB_RXOVRN3             0x80    /*RX_OVRN, FIFO 3      */

/*------- NAKEV, NAKMSK bits ---------*/
#define     USB_NAK_I0              0x01    /*IN  NAK, FIFO 0      */
#define     USB_NAK_I1              0x02    /*IN  NAK, FIFO 1      */
#define     USB_NAK_I2              0x04    /*IN  NAK, FIFO 2      */
#define     USB_NAK_I3              0x08    /*IN  NAK, FIFO 3      */
#define     USB_NAK_O0              0x10    /*OUT NAK, FIFO 0      */
#define     USB_NAK_O1              0x20    /*OUT NAK, FIFO 1      */
```

```
#define       USB_NAK_O2              0x40    /*OUT NAK, FIFO 2       */
#define       USB_NAK_O3              0x80    /*OUT NAK, FIFO 3       */

/*--------- EPCX bits ----------------*/
#define       USB_EP_EN               0x10    /*enables endpt.  (1-6)   */
#define       USB_ISO                 0x20    /*set for isochr. (1-6)   */
#define       USB_DEF                 0x40    /*force def. adr (0 only) */
#define       USB_STALL               0x80    /*force stall handshakes  */

/*---------- TXCx bits ---------------*/
#define       USB_TX_EN               0x01    /*transmit enable       */
#define       USB_TX_LAST             0x02    /*last data in FIFO     */
#define       USB_TX_TOGL             0x04    /*specifies PID used    */
#define       USB_FLUSH               0x08    /*flushes all FIFO data   */
#define       USB_IGNIOS              0x80    /*      */

/*----------- TXSx bits --------------*/
#define       USB_TX_DONE             0x20    /*transmit done         */
#define       USB_ACK_STAT            0x40    /*ack status of xmission  */

/*------------ RXCx bits -------------*/
#define       USB_RX_EN               0x01    /*receive  enable       */
#define       USB_IGN_OUT             0x02    /*ignore out tokens     */
#define       USB_IGN_SETUP           0x04    /*ignore setup tokens    */

/*------------- RXS0 bits ------------*/
#define       USB_RX_LAST             0x10    /*indicates RCOUNT valid  */
#define       USB_RX_TOGL             0x20    /*last pkt was DATA1 PID  */
#define       USB_SETUP_RX            0x40    /*setup packet received   */
```

```
#define	USB_RX_ERR		0x80	/*last packet had an error*/
```

```
/*

      USB N9604 コントロール

                                                    (C)2002 C.I.M

*/

#include      <stdio.h>
#include      <string.h>
#include      "usbn9602.h"
#include      "h83048.h"

extern  void PrintSCI(const char *fmt, ...);          /* sci.c */

static void RegisterSet();
static void ResetUSB();
static void WakeupUSB();

static void rx0();
static void rx1();
static void tx0();
static void tx1();
static void nako0();
static void nako1();
static void naki0();
static void naki1();

static void clrfeature();
```

```
static void setfeature();
static void getdescriptor();
static void send_desc_sub(void *ptr,int size);
static void send_desc();
static void getstatus();
static void setconfiguration();

static void SetStallUSB(int adr);
static void ClearStallUSB(int adr);
static void FlushRXC(int no);
static void FlushTXC(int no);
static void TxTogle(int no);

static void WriteUSB(int adr,int data);
static unsigned char ReadUSB(int adr);
static int ReadUSBBurst(int adr,int adr2,char *buff,int cnt);
static int WriteUSBBurst(int adr,int adr2,char *buff,int cnt);

/*---------------------------------*/
static int SendTX1();

/*---------------------------------*/
int get_inbufflen(void);
void init_usbbuff(void);
int write_inbuff(char *p,int size);
int get_outbufflen(void);
int write_buff(char *p,int size);
int read_outbuff(char *p,int size);
/*---------------------------------*/
```

```
static  unsigned char   usbevent;           /* USB割り込みイベント        */
static  unsigned char   SETADDR;            /* アドレスセット             */
static  unsigned char   configno;           /* コンフィグレーションNO */
static  unsigned char   usbbuff[64];    /* 読み込みバッファ               */
static  unsigned char   rx1buff[64];
static  unsigned char   rx2buff[64];
static  unsigned char   STALLD;             /* ECPの状態                  */
static  unsigned char   DATA0_1;            /* USB_TXTGLのフラグ          */
static  char            senddesc;           /* 1 = ディスクリプタ送信中   */
static  int             desc_size;          /* ディスクリプタ送信サイズ */
static  char            *desc_ptr;          /* ディスクリプタポインタ  */


static  const unsigned char     epctbl[8] =
{USB_EPC0,USB_EPC1,USB_EPC2,USB_EPC3,USB_EPC4,USB_EPC5,USB_EPC6,USB_EPC0};
static int      txcreg[4] = {USB_TXC0,USB_TXC1,USB_TXC2,USB_TXC3};
static int rxcreg[4] = {USB_RXC0,USB_RXC1,USB_RXC2,USB_RXC3};

/*-----------------------------------------------------------*/
/*-----------------------------------------------------------*/
static const unsigned char dev_desc[] = {
    0x12,               /* length of this desc.                   */
    0x01,               /* デバイス・ディスクリプタ 1             */
    0x00,0x01,              /* USB Version 1.0                        */
    0x00,               /* device class クラス無し                */
    0x00,               /* device subclass                        */
    0x00,               /* device protocol                        */
    0x08,               /* EP0の最大パケットサイズ                */
```

```
    0xfe,0xff,              /* vendor ID    サンプルなのでとりあえず        */
    0x10,0x00,              /* product ID                                   */
    0x01,0x00,              /* revision ID                                  */
    0x01,                   /* index of manuf. string                       */
    0x01,                   /* index of prod.  string                       */
    0x02,                   /* index of ser. # string                       */
    0x01                    /* bNumConfigurations                           */
};


/* コンフィグレーションディスクリプタ */
static const unsigned char cfg_desc[] = {
    0x09,                   /* length of this desc.                         */
    0x02,                   /* コンフィグレーション・ディスクリプタ         */
    9+9+7*3,                /* インターフェース／エンドポイントディスクリプタ等の合計長 CFG + IF +
EP*3 */
    0x00,                   /*                                              */
    0x01,                   /* インターフェース数 1                         */
    0x01,                   /* コンフィグレーションは 1                     */
    0x00,                   /* index of config. string                      */
    0xc0,                   /* attr.: self powered  D6=自己電源             */
    100,                    /*     ;max power (100 mA)                      */
/*},*/
/*static const unsigned char if_desc[] = {*/
    0x09,                   /* length of this desc.                         */
    0x04,                   /* INTERFACE descriptor                         */
    0x00,                   /* interface number                             */
    0x00,                   /* alternate setting                            */
    0x03,                   /* # of (non 0) endpoints                       */
    0x00,                   /* interface class                              */
```

```
    0x00,               /* interface subclass                   */
    0x00,               /* interface protocol                   */
    0x03,               /* index of intf. string                */
/*};*/
/*static const unsigned char endp_desc[] = {*/
    /* pipe 0 */
    7,                  /* length of this desc.                 */
    5,                  /* ENDPOINT descriptor                  */
    0x81,               /* address (IN)                         */
    0x02,               /* attributes  (BULK)                   */
    0x40,0x00,          /* max packet size (64)                 */
    255,                /* interval (ms)                        */
    /* pipe 1 */
    7,                  /* length of this desc.                 */
    5,                  /* ENDPOINT descriptor                  */
    0x02,               /* address (OUT)                        */
    0x02,               /* attributes  (BULK)                   */
    0x40,0x00,          /* max packet size (64)                 */
    255,                /* interval (ms)                        */

    /* pipe 2 (not use) */
    7,                  /* length of this desc.                 */
    5,                  /* ENDPOINT descriptor                  */
    0x83,               /* address (IN)                         */
    0x02,               /* attributes  (BULK)                   */
    0x40,0x00,          /* max packet size (64)                 */
    255,                /* interval (ms)                        */
};
```

```
static const char lang_data[] = {
        4,3,9,4             /* LANGID (English)                                    */
};

static const char mfg_str[] = {
        18,3,
        'U',0,'S',0,'B',0,' ',0,'T',0,'E',0,'S',0,'T',0,
};



static const char nbr_str[] = {
    8,3,
    '1',0,'.',0,'0',0,
};

static const char int_str[] = {
    34,3,
    'U',0,'S',0,'B',0,' ',0,
    'T',0,'E',0,'S',0,'T',0,' ',0,'P',0,'R',0,'O',0,'G',0,'R',0,'A',0,'M',0,
};

static void wait(int c)
{
    int         i,j;
    for(j=0;j<c;j++)
    {
        for(i=0;i<0x682;i++)
```

```
            {
            }
        }
    }

    /*-----------------------------------------------------------*/
    /* USB初期化 */
    void InitUSB()
    {
        init_usbbuff();
        ResetUSB();
        RegisterSet();
        WakeupUSB();
    /*     PrintSCI(" REV = %d¥n",ReadUSB(USB_RID)); */
    /*     PrintSCI(" CLOCK = %02X¥n",ReadUSB(USB_CCONF)); */

    }

    static void RegisterSet()
    {
        STALLD = 0;
        senddesc = 0;
        DATA0_1 = 0;
        SETADDR = 0;

        WriteUSB(USB_FAR,USB_AD_EN+0);                  /* アドレス初期化     */
        WriteUSB(USB_EPC0,USB_EP_EN);                   /* EP0をｲﾈｰﾌﾞﾙ         */
        WriteUSB(USB_NAKMSK,USB_NAK_O0);                /* NAK MASKをｾｯﾄ */
        WriteUSB(USB_TXMSK,USB_TXFIFO0+USB_TXFIFO1+USB_TXFIFO2+USB_TXFIFO3);    /* TX MASK
```

```
をｾｯﾄ */
    WriteUSB(USB_RXMSK,USB_RXFIFO0+USB_RXFIFO1+USB_RXFIFO2+USB_RXFIFO3);  /* RX MASK
をｾｯﾄ */
    WriteUSB(USB_ALTMSK,USB_SD3+USB_RESET_A);          /* ALT MASKをｾｯﾄ */
    WriteUSB(USB_MAMSK,USB_INTR_E+USB_RX_EV+USB_NAK+USB_TX_EV+USB_ALT);          /*
MAIN MASKをｾｯﾄ */
    FlushTXC(0);
    FlushRXC(1);
    FlushTXC(1);
    WriteUSB(USB_TXC1,0);
    WriteUSB(USB_RXC1,0);
    WriteUSB(USB_RXC0,USB_RX_EN);                  /* RX0をｲﾈｰﾌﾞﾙ        */
}

static void ResetUSB()
{
    WriteUSB(USB_MCNTRL,USB_SRST+USB_VGE);                /* USBリセット 3.3V供給 */
    wait(100);                                          /* 100msec */
    WriteUSB(USB_MCNTRL,USB_INT_L_P+USB_VGE);             /* 割込みはactive low push pull */
    WriteUSB(USB_CCONF,USB_CLKDIV-1);                     /* 48MHz/4 = 12MHz */
}

static void WakeupUSB()
{
    WriteUSB(USB_NFSR,USB_OPR_ST);                        /* 動作可にする */
    WriteUSB(USB_MCNTRL,USB_INT_L_P+USB_NAT+USB_VGE);     /* USBのﾉｰﾄﾞを動作可にする */
}

/* USBポートデータ表示 */
```

```
/* ※リードすると、ステータスが変わるレジスタもあるので注意 */
void DispUSBPort()
{
        int         i,j;
        PrintSCI("00 01 02 03 04 05 06 07 08 09 0A 0B 0C 0D 0E 0F¥n");
        for(j=0;j<4;j++)
        {
            for(i=0;i<16;i++)
                PrintSCI("%02X ",ReadUSB(i+j*16));
            PrintSCI("¥n");
        }
}

/*-----------------------------------------------------------*/
/* USB割り込み */
#ifdef  __GNUC__
void usb_int()  __attribute__ ((interrupt_handler));
#endif
void usb_int()
{
    unsigned char   nakevent,rxevent,txevent,altevent;
    char    reg;


    usbevent = ReadUSB(USB_MAEV);

    if( usbevent & USB_NAK )
    {
```

```
        nakevent = ReadUSB(USB_NAKEV);
        if( nakevent & USB_NAK_O0 )
        {
            nako0();
        }
        if( nakevent & USB_NAK_O1 )
        {
            nako1();
        }
        else if( nakevent & USB_NAK_I0 )
        {
            naki0();
        }
        else if( nakevent & USB_NAK_I1 )
        {
            naki1();
        }
    }
    else if( usbevent & USB_RX_EV )
    {
        rxevent = ReadUSB(USB_RXEV);
        if( rxevent & USB_RXFIFO0 )
        {
            rx0();
        }
        else if( rxevent & USB_RXFIFO1 )
        {
            rx1();
        }
```

```
}
else if( usbevent & USB_TX_EV )
{
    txevent = ReadUSB(USB_TXEV);
    if( txevent & USB_TXFIFO0 )
    {
        tx0();
    }
    else if( txevent & USB_TXFIFO1 )
    {
        tx1();
    }
}
else if( usbevent & USB_ALT )
{
    altevent = ReadUSB(USB_ALTEV);
    if( altevent & USB_RESET_A )
    {
        /* リセット */
        RegisterSet();
        WakeupUSB();
    }
    else if( altevent & USB_SD3 )
    {
        /* サスペンド */
        /* ALTMSKをｾｯﾄ          */
        WriteUSB(USB_ALTMSK,USB_RESUME_A+USB_RESET_A);
        /* ﾉｰﾄﾞをｻｽﾍﾟﾝﾄﾞ */
        WriteUSB(USB_NFSR,USB_SUS_ST);
```

```
        }
        else if( altevent & USB_RESUME_A )
        {
            /* リジューム */
            /* ALTMSKをｾｯﾄ                */
            WriteUSB(USB_ALTMSK,USB_SD3+USB_RESET_A);
            /* ﾉｰﾄﾞを動作可能にする */
            WriteUSB(USB_NFSR,USB_OPR_ST);
        }
    }
}

/*================================================================
                        RXイベントの処理
================================================================*/
/* RX0(system) */
/*
 リクエストコードの取得
        0 byte
            D7 ... データ方向 0=ホスト->デバイス , 1=デバイス->ホスト
            D6-D5 ... タイプ
                    0:標準 , 1:クラス , 2:ベンダ , 3:予約
            D4-D0 ... 受信側
                    0:デバイス , 1:インターフェイス , 2:エンドポイント , 3:その他
        1 byte
            特定のリクエスト
        2 byte
            value
```

```
        2 byte
            index
        2 byte
            length
*/
static void rx0()
{
    unsigned char   rxstat;
    rxstat = ReadUSB(USB_RXS0);
    if( rxstat & USB_SETUP_RX )
    {
        ReadUSBBurst(USB_RXD0,USB_RXS0,(char*)usbbuff,8);
        FlushRXC(0);
        FlushTXC(0);
        ClearStallUSB(USB_EPC0);
        if( (usbbuff[0] & 0x60) == 0 )
        {
            /* 標準リクエスト */
            switch( usbbuff[1] )
            {
                case    USB_CLEAR_FEATURE :
                    clrfeature();
                    break;
                case    USB_GET_CONFIGURATION :
                    WriteUSB(USB_TXD0,configno);
                    break;
                case    USB_GET_DESCRIPTOR :
                    getdescriptor();
```

```
                break;
            case    USB_GET_STATUS :
                getstatus();
                break;
            case    USB_GET_INTERFACE :
                WriteUSB(USB_TXD0,0);
                break;
            case    USB_SET_ADDRESS :
                WriteUSB(USB_EPC0,USB_DEF);
                SETADDR = usbbuff[2]¦USB_AD_EN;
                WriteUSB(USB_FAR,SETADDR);
                break;
            case    USB_SET_CONFIGURATION :
                setconfiguration();
                break;
            case    USB_SET_FEATURE :
                setfeature();
                break;
            case    USB_SET_INTERFACE :
                if( usbbuff[2] != 0 )
                    SetStallUSB(USB_EPC0);
                break;
            default :
                /* 未定義 */
                SetStallUSB(USB_EPC0);
                break;
        }
    }
    else if( (usbbuff[0] &0x60 ) ==  0x20 )
```

```
        {
            /* クラスリクエスト */
            SetStallUSB(USB_EPC0);
        }
        else if( (usbbuff[0] &0x60 ) ==  0x40 )
        {
            /* ベンダリクエスト */
            SetStallUSB(USB_EPC0);
        }
        else
        {
            /* 未定義 */
            SetStallUSB(USB_EPC0);
        }
        /* SETUPなのﾃﾞｰﾀの有無に関係無くDATA1として送信 */
        DATA0_1 ¦= 1;
        TxTogle(0);
    }
    else
    {
        if( senddesc )
        {
            senddesc = 0;
        }
        FlushTXC(0);
        WriteUSB(USB_RXC0,USB_RX_EN);
    }
}
```

```
/*-----------------------------------------------------------*/
/* RX1 受信 */
static void rx1()
{
    int             cnt;
    unsigned char   rxstat;
    rxstat = ReadUSB(USB_RXS1);             /* RX1ステータス取得 */
    /* SETUP,ERRORパケットでない */
    if( !(rxstat & (USB_SETUP_RX¦USB_RX_ERR)) )
    {
        /* ホストからデータの受信 */
        /* FIFOからデータ取得 */
        cnt = ReadUSBBurst(USB_RXD1,USB_RXS1,(char*)rx1buff,64);
        /* リングバッファに書き込み */
        write_inbuff((char*)rx1buff,cnt);
    }
    FlushRXC(1);                            /* バッファをフラッシュ */
    WriteUSB(USB_RXC1,USB_RX_EN);       /* 受信可に設定                 */
}

/*-----------------------------------------------------------*/
/* RX2 受信(not use) */
static void rx2()
{
    unsigned char   rxstat;
    rxstat = ReadUSB(USB_RXS2);
}

/*===========================================================
```

```
                                TXイベントの処理
==========================================================================*/
/* TX0 送信終了 */
static void tx0()
{
    unsigned char   txstat;
    txstat = ReadUSB(USB_TXS0);
    if( (txstat & USB_ACK_STAT) && (txstat & USB_TX_DONE) )
    {
        /* ok */
        FlushTXC(0);
        if( senddesc )
        {
            send_desc();
            TxTogle(0);                         /* TX0送信可 */
        }
        else
        {
            WriteUSB(USB_RXC0,USB_RX_EN);   /* RX0受信可 */
        }
    }
    else
    {
        /* error ? */
    }
}

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

```
/* TX1送信終了 */
static void tx1()
{
    unsigned char   txstat;
    txstat = ReadUSB(USB_TXS1);
    if( (txstat & USB_ACK_STAT) && (txstat & USB_TX_DONE) )
    {
        /*
            送信終了後に次の送信データを送信するようにする
            送信データが無い場合、HOSTには0バイトで送る
        */
        SendTX1();
    }
    else
    {
        /*
            送ったサイズより小さい読み込みが行われた場合、こちらにくる場合がある
        */
    }
}

/*==========================================================================
                                NAKイベントの処理
==========================================================================*/
/*
    NAKイベントは、エラーが発生した場合など再送信する場合処理する
    NAK0しかENABLEにしていないので、それ以外は処理無し
*/
static void nako0()
```

```
{
}
static void nako1()
{
}
static void naki0()
{
}

static void naki1()
{
}



/*=============================================================
                        標準リクエストの処理
=============================================================*/
/* 選択機器 */
static void clrfeature()
{
    if( (usbbuff[0] & 3) == 2 )
    {
        /* エンドポイントデータ */
        if((usbbuff[3]&7) != 0 )
            ClearStallUSB(epctbl[usbbuff[3]&7]);
        STALLD &= -1 ^ (1<<(usbbuff[3]&7));
    }
}
static void setfeature()
```

```
{
    if( (usbbuff[0]&3) == 2 )           /* ENDPOINT */
    {
        /* エンドポイントデータ */
        if((usbbuff[3]&7) != 0 )
            SetStallUSB(epctbl[usbbuff[3]&7]);
        STALLD |= (1<<(usbbuff[3]&7));
    }
}

/*-------------------------------------------------------------*/
/* ディスクリプタを返す */
static void getdescriptor()
{
    DATA0_1 &= 0xfe;
    switch( usbbuff[3] )
    {
        case   USB_DEVICE :
            send_desc_sub((void*)dev_desc,dev_desc[0]);
            break;
        case   USB_CONFIGURATION :
        {
            send_desc_sub((void *)cfg_desc,cfg_desc[2]);
            break;
        }
        case   USB_XSTRING :
        {
            switch( usbbuff[2] )
            {
```

```
                case  0 :
                    send_desc_sub((void *)lang_data,lang_data[0]);
                    break;
                case  1 :
                    send_desc_sub((void *)mfg_str,mfg_str[0]);
                    break;
                case  2 :
                    send_desc_sub((void *)nbr_str,nbr_str[0]);
                    break;
                case  3 :
                    send_desc_sub((void *)int_str,int_str[0]);
                    break;
            }
            break;
        }
        default :
        {
        }
    }
}

static void send_desc_sub(void *ptr,int size)
{
    desc_size = (usbbuff[7] << 8) + usbbuff[6];
    /* 受信要求バッファ以上はデータを送らない */
    if( desc_size > size )  desc_size = size;
    desc_ptr = ptr;
    senddesc = 1;   /* ディスクリプタ送信中フラグを立てる */
```

```
    send_desc();
}

static void send_desc()
{
    int         sz;
    sz = 8;
    if( desc_size == 0 )    return;
    if( desc_size <= 8 )    sz = desc_size;
    sz = WriteUSBBurst(USB_TXD0,USB_TXS0,desc_ptr,sz);
    desc_size -= sz;
    desc_ptr += sz;
    if( desc_size == 0 )    senddesc = 0;
}
/*-------------------------------------------------------------*/
/* ステータス */
static void getstatus()
{
    int         data,ep;
    data = usbbuff[0]&3;
    if( (data == 0) || (data == 1) )       /* DEVICE,INTERFACE */
    {
        WriteUSB(USB_TXD0,0);
        WriteUSB(USB_TXD0,0);
    }
    else if( data== 2)                          /* エンドポイント */
    {
        ep = usbbuff[3]&7;
        /* epのSTALL状態を送信 */
```

```
        if( STALLD & (1<<ep) )  WriteUSB(USB_TXD0,1);
        else                    WriteUSB(USB_TXD0,0);
    }
    else
    {
        WriteUSB(USB_TXD0,0);
    }
}

/*-------------------------------------------------------*/
static void setconfiguration()
{
    configno = usbbuff[2];
    if( configno == 0 )
    {
        WriteUSB(USB_EPC1,0);           /* EPC1を使用不可 */
        WriteUSB(USB_EPC2,0);           /* EPC2を使用不可 */
        WriteUSB(USB_EPC3,0);           /* EPC3を使用不可 */
        WriteUSB(USB_EPC4,0);           /* EPC4を使用不可 */
        WriteUSB(USB_EPC5,0);           /* EPC5を使用不可 */
        WriteUSB(USB_EPC6,0);           /* EPC6を使用不可 */
    }
    else
    {
        STALLD = 0;
        FlushTXC(1);
        /* EPC1をｱﾄﾞﾚｽ1としてｲﾈｰﾌﾞﾙ */
        WriteUSB(USB_EPC1,USB_EP_EN+01);
        /* TX1送信可 */
```

```
        WriteUSB(USB_TXC1,USB_TX_EN¦USB_TX_LAST);


        FlushRXC(1);
        /* EPC2をｱﾄﾞﾚｽ2としてｲﾈｰﾌﾞﾙ */
        WriteUSB(USB_EPC2,USB_EP_EN+02);
        /* RX1受信可 */
        WriteUSB(USB_RXC1,USB_RX_EN);
        /*
            USB_TX_LASTを立てると、READ時ストールしなくなる。
            ただし、データを送る前の最初のREADは0byteになります。
            host側は複数のリクエストを同時発行できないので、
            リクエストがストールするのはまずいの回避。
        */
    }
}

/*============================================================
                        汎用ルーチン
============================================================*/
/* STALLのセットとクリア */
static void SetStallUSB(int adr)
{
    WriteUSB(adr,ReadUSB(adr) ¦ 0x80);
}

static void ClearStallUSB(int adr)
{
    WriteUSB(adr,ReadUSB(adr)&0x7f);
}
```

```
/* FIFOのフラッシュ */
static void FlushRXC(int no)
{
	WriteUSB(rxcreg[no],USB_FLUSH);
}

static void FlushTXC(int no)
{
	int		d;
	d = ReadUSB(txcreg[no]);
	d ¦= USB_FLUSH;
	WriteUSB(txcreg[no],d);
}

/* 送信終了フラグセット */
/* reg = USB_TXC0～6	*/
static void TxTogle(int no)
{
	unsigned char	d;
	d = USB_TX_EN;
	if( DATA0_1 & (1<<no) ) d ¦= USB_TX_TOGL;
	else			d &= ˜USB_TX_TOGL;
	d ¦= USB_TX_LAST;
	WriteUSB(txcreg[no],d);
	DATA0_1 ^= (1<<no);
}
```

```
/*-----------------------------------------------------------*/
/* USBのアドレスから読み込み */
static unsigned char ReadUSB(int adr)
{
	USB9602R = (unsigned char)adr;
	return( USB9602D );
}
/* USBのアドレスへ書き込み */
static void WriteUSB(int adr,int data)
{
	USB9602R = (unsigned char)adr;
	USB9602D = (unsigned char)data;
}


/* バーストト転送 */
static int ReadUSBBurst(int adr,int adr2,char *buff,int cnt)
{
	int		i;
	int		rcnt;
	USB9602R = (unsigned char)adr;
	for(rcnt=0,i=0;i<cnt;i++)
	{
		if( (ReadUSB(adr2) & 0xf) == 0 )	break;

		USB9602R = (unsigned char)adr;
		*buff = USB9602D;
		buff++;
		rcnt++;
```

```
	}
	return(rcnt);
}

static int WriteUSBBurst(int adr,int adr2,char *buff,int cnt)
{
	int		i,scnt;
	for(scnt=0,i=0;i<cnt;i++)
	{
		if( (ReadUSB(adr2) & 0x1f) == 0 )	break;

		USB9602R = (unsigned char)adr;
		USB9602D = *buff;
		buff++;
		scnt++;
	}
	return(scnt);
}

/*==========================================================================
				サンプルプログラム
==========================================================================*/
/* TX1送信ルーチン */
/*
	USBから一方的に送信できないため、今回は、
	TX1送信終了時にバッファ(outbuff)にあるデータを送信します。
	よって、HOSTからは定期的にREADを行う。
	それ以外のタイミングではEPC1のFIFOバッファのサイズに注意する。
*/
```

```
static int SendTX1()
{
	int		c,cnt,sz,i;

	cnt = 0;
	/* FIFOは最大64byte */
	sz = read_outbuff((char*)rx2buff,64);
	FlushTXC(1);	/* 送信バッファをフラッシュ */
	if( sz != 0 )
	{
		/* バースト転送 */
		cnt = WriteUSBBurst(USB_TXD1,USB_TXS1,(char*)rx2buff,sz);
	}
	TxTogle(1);		/* 送信終了処理 */
	return( cnt );	/* 送信データ数を返す sz==cntのはず */
}

/*-------------------------------------------------------------*/
/*
 送受信バッファ
	inbuffがHOSTから送られてきたデータのバッファ
	outbuffがHOSTへ送るデータ用
	このサンプルではリングバッファを超えた分は捨てられます。
	今回は、256バイト確保しています。バッファがあふれないように
	メイン側で処理してください。
*/
#define	USBBUFFLEN	256		/* バッファのサイズ */
static int	inpos,inlen;		/* 入力バッファ位置、サイズ */
static int	outpos,outlen;		/* 出力バッファ位置、サイズ */
```

```
static char    inbuff[USBBUFFLEN];          /* 入力リングバッファ */
static char    outbuff[USBBUFFLEN];   /* 出力リングバッファ */

/*-------------------------------------------------------------*/
/*                              バッファの初期化                                */
/*-------------------------------------------------------------*/
void init_usbbuff()
{
      inpos = inlen = 0;
      outpos = outlen = 0;
}

/*-------------------------------------------------------------*/
/*                    HOSTからの受信バッファへ書き込み                    */
/*     char        *p          バッファポインタ                              */
/*     int              size   書き込みサイズ                                */
/*     戻り値                   書き込んだサイズ                              */
/*-------------------------------------------------------------*/
int write_inbuff(char *p,int size)
{
      int          i;
      INTC.IER &= (-1^0x20);                  /* IRQ5 Disable */
      for(i=0;i<size;i++)
      {
      if( inlen >= USBBUFFLEN )      break;
      inbuff[inpos] = *p;
      inpos = (inpos + 1)%USBBUFFLEN;
      inlen++;
```

```
        p++;
    }
        INTC.IER |= 0x20;                       /* IRQ5 Enable */
        return(i);
}
/*-------------------------------------------------------------*/
/*                      送信バッファへ書き込み                 */
/*    char      *p        バッファポインタ                     */
/*    int           size   書き込みサイズ                      */
/*    戻り値              書き込んだサイズ                     */
/*-------------------------------------------------------------*/
int write_buff(char *p,int size)
{
        int         i;
        INTC.IER &= (-1^0x20);                  /* IRQ5 Disable */
        for(i=0;i<size;i++)
        {
        if( outlen >= USBBUFFLEN )    break;
        outbuff[outpos%USBBUFFLEN] = *p;
        outpos = (outpos + 1)%USBBUFFLEN;
        outlen++;
        p++;
    }
        INTC.IER |= 0x20;                       /* IRQ5 Enable */
        return(i);
}

/*-------------------------------------------------------------*/
/*                      送信バッファから読み込み               */
```

```
/*     char        *p          バッファポインタ                          */
/*     int             size    バッファ最大サイズ                        */
/*     戻り値                  読み込んだサイズ                          */
/*--------------------------------------------------------------*/
int read_outbuff(char *p,int size)
{
    int    i;
    INTC.IER &= (-1^0x20);                  /* IRQ5 Disable */
    for(i=0;outlen>0;i++)
    {
        if( i >= size ) break;
        p[i] = outbuff[ (USBBUFFLEN+outpos-outlen)%USBBUFFLEN ];
        outlen--;
    }
    INTC.IER |= 0x20;                       /* IRQ5 Enable */
    return(i);
}
/*--------------------------------------------------------------*/
/*                      受信バッファから読み込み                */
/*     char        *p          バッファポインタ                          */
/*     int             size    バッファ最大サイズ                        */
/*     戻り値                  読み込んだサイズ                          */
/*--------------------------------------------------------------*/
int read_buff(char *p,int size)
{
    int    i;
    INTC.IER &= (-1^0x20);                  /* IRQ5 Disable */
    for(i=0;inlen>0;i++)
    {
```

```
        if( i >= size ) break;
        p[i] = inbuff[ (USBBUFFLEN+inpos-inlen)%USBBUFFLEN ];
        inlen--;
    }
    INTC.IER |= 0x20;                   /* IRQ5 Enable */
    return(i);
}
/*-------------------------------------------------------------*/
/*                      受信バッファのサイズ取得                    */
/*-------------------------------------------------------------*/
int get_inbufflen()
{
    return( inlen%USBBUFFLEN );
}

/*-------------------------------------------------------------*/
/*                      送信バッファのサイズ取得                    */
/*-------------------------------------------------------------*/
int get_outbufflen()
{
    return( outlen%USBBUFFLEN );
}
```

```
/*

                    SCI処理

                                                    (C)2002 C.I.M

*/

#include    <stdio.h>
#include    <stdarg.h>
#include    "h83048.h"


static  char buff[80]; /* 文字列展開用バッファ(必要なら増やす) */


/*=================================================================
                                SCI初期化
-----------------------------------------------------------------
    9600bps ﾊﾟﾘﾃｨ無し STOP1
=================================================================*/
void InitSCI()
{
    int         i;
    SCI1.SCR = 0;
    SCI1.SMR = 0;                   /* ﾊﾟﾘﾃｨ無し STOP1                  */
    SCI1.BRR = 80;                  /* 9600bps     3052                */
    for(i=0;i<280;i++)    {}        /* wait                            */
    SCI1.SCR = 0x30;                /* TE = 1 , RE = 1                 */
    i = SCI1.SSR;
    SCI1.SSR = 0x80;                /* Clear Error Flag (TDRE=1)    */
```

```
}

/*================================================================
                        SCI出力
----------------------------------------------------------------
================================================================*/
void PutSCI(char c)
{
    unsigned char   i;
    while( 1 )
    {
        i = SCI1.SSR;
        if( i & 0x80 )      break;
    }
    SCI1.TDR = c;
    SCI1.SSR = i&0x7f;
}

/*================================================================
                        SCI入力
----------------------------------------------------------------
    データを受信するまで待ちつづけます。
================================================================*/
char GetSCI()
{
    unsigned char   i;
    char            c;
    while( 1 )
    {
```

```
        i = SCI1.SSR;
        if( i & 0x40 )      break;
    }
    c = SCI1.RDR;
    SCI1.SSR = i&0xbf;
    return(c);
}

/*=============================================================
                        SCI入力データチェック
-------------------------------------------------------------
    SCIにデータがあるかチェックします。
    戻り値          1 = データあり、0 = データなし
=============================================================*/
int ScanSCI()
{
    if( SCI1.SSR & 0x40 )   return(1);
    return(0);
}

/*=============================================================
                        SCI文字列出力
-------------------------------------------------------------
書式はprintf()と同じです。バッファは80文字分しか取っていないので、
必要ならば、増やしてください。
=============================================================*/
void PrintSCI(char *fmt, ...)
{
    int         i;
```

```
    va_list arg;
    va_start(arg, fmt);
    *buff = '¥0';
    vsprintf(buff,fmt,arg);
    va_end(arg);

    for(i=0;;i++)
    {
        if( buff[i] == 0 )      break;
        /* 改行コードは2バイトにして送信 */
        if( buff[i] == '¥n' )   PutSCI('¥r');
        PutSCI(buff[i]);
    }
}
```

```
/*

        LCD処理

                                                (C)2002 C.I.M
*/



#include      <stdio.h>
#include      <stdarg.h>
#include      "h83048.h"

void ClearLCD();

/* PortB (write) b0..3 = LCD(LED) out , bit4 = LCD RS , bit7 = LCD E */
#define       LCD_RS              0x10
#define       LCD_E               0x80
#define       LCDMASK             0x60

static void wait(int c)
{
    int         i,j;
    for(j=0;j<c;j++)
    {
        for(i=0;i<0x682;i++)    {}
    }
}
```

```
/*====================================================================
                                LCD BYTE 出力
====================================================================*/
/*
    今回の基板は4bit接続なので、下位4bitのみ出力
*/
static void LCDOut8(short rs,short code)
{
    int         stat;
    int         pb;

    pb = PB.DR;                         /* 現在のPBDを退避 */

    if( rs )    stat = (pb & LCDMASK) ¦ LCD_RS;
    else        stat = (pb & LCDMASK);
    PB.DR = code ¦ stat ¦ LCD_E;
    PB.DR = code ¦ stat;
    PB.DR = pb;                         /* 元のPBDに復帰 */
    wait(4);
}

/*====================================================================
                                LCD BYTE 出力(4bit)
====================================================================*/
void LCDOut4(int rs,int code)
{
    int         stat;
    int         pb;
    char    lb,hb;
```

```
    pb = PB.DR;                         /* 現在のPBDを退避 */

    if( rs )        stat = (pb & LCDMASK) ¦ LCD_RS;
    else            stat = (pb & LCDMASK);

    hb = ((code>>4)&0xf) ¦ stat;
    lb = (code&0xf) ¦ stat;

    PB.DR = hb ¦ LCD_E;
    PB.DR = hb;

    PB.DR = lb ¦ LCD_E;
    PB.DR = lb;

    PB.DR = pb;                         /* 元のPBDに復帰 */
    wait(4);
}

/*================================================================
                        LCD コントロール
----------------------------------------------------------------
    LCD初期化、表示、クリア
================================================================*/

void InitLCD()
{
    int         i;
    wait(15);
```

```
    for(i=0;i<3;i++)
    {
        LCDOut8(0,0x3);
    }
    LCDOut8(0,0x2);


    LCDOut4(0,0x28); /* bit4=8/4bit , bit3=1/2line , bit2=large/small */
    LCDOut4(0,0x10); /* bit3=Display/Cursor , bit2=Right/Left */
    LCDOut4(0,0x0e); /* bit2=display , bit1=coursor , bit0=blink */
    LCDOut4(0,0x06);

    LCDOut4(0,0x01); /* クリア */
    LCDOut4(0,0x02); /* カーソルホーム */

}


/*================================================================
                                LCD クリア
----------------------------------------------------------------
    LCD初期化、表示、クリア
================================================================*/
void ClearLCD()
{
    LCDOut4(0,0x01);      /* クリア */
    LCDOut4(0,0x02);      /* カーソルホーム */
}
```

```
/*================================================================
                        LCDキャラクタ表示
----------------------------------------------------------------
    '¥n','¥r','¥f'はLCDクリア処理を行います。
================================================================*/
void PutLCD(char c)
{
    if( c == '¥f' ) ClearLCD();
    else if( c == '¥n' )   ClearLCD();
    else if( c == '¥r' )   ClearLCD();
    else LCDOut4(1,c);
}

/*================================================================
                        LCDカーソル移動
----------------------------------------------------------------
    x = 0～15
    y = 0,1
================================================================*/
void LocateLCD(int x,int y)
{
    LCDOut4(0,0x80 + y*0x40 + x);
}

/*================================================================
                        LCD文字列表示
----------------------------------------------------------------
    パラメータはprintf()と同じです。64文字を超えないように設定してく
```

```
      ださい。'¥f'はLCDクリア、'¥n'は改行。
==========================================================================*/
void PrintLCD(char *fmt,...)
{
      int           i;
      static  char    buff[64];
      va_list arg;
      va_start(arg, fmt);
      *buff = '¥0';
      vsprintf(buff,fmt,arg);
      va_end(arg);
      for(i=0;;i++)
      {
            if( buff[i] == 0 ) break;
            else if( buff[i] == '¥n' ) LocateLCD(0,1); /* 改行 */
            else if( buff[i] == '¥r' ) LCDOut4(0,0x2); /* カーソルホーム */
            else if( buff[i] == '¥f' ) ClearLCD(); /* LCDクリア */
            else LCDOut4(1,buff[i]); /* データ出力 */
      }
}
```

本文

```
/* C.h */

#define USE_THREAD
/* #define USE_BCC */
/* #define USE_LINUX */
#ifdef USE_LINUX
#define USE_BCC
#endif
#include <stdio.h> /* printf() */
#include <string.h> /* strcmp(), strlen() */
#include <stdlib.h> /* calloc(), free(), rand() */
#ifndef USE_BCC
#include "h83048.h"
#define SLEEP_PER_SEC 16000.0
#define NOTUSE_FILES
#else
#include <time.h> /* time_t, tm, time(), clock(), CLOCKS_PER_SEC */
#ifdef USE_LINUX
#include <termios.h> /* kbhit() */
#include <unistd.h> /* kbhit() */
#include <fcntl.h> /* kbhit() */
#else
#include <conio.h> /* kbhit(), getche() */
#endif
#define SLEEP_PER_SEC 100000000.0
#endif
#ifdef USE_LINUX
#define CLEAR system("clear")
#else
#define CLEAR system("cls")
#endif
#define OK 0
#define NG 1
#define ONE_MORE_TIME 2
#define ON 1
#define OFF 0
```

```
/* Panel.h */

#ifndef USE_BCC
/*=============================================================
                        外部参照
=============================================================*/
/* asmfile.src 内に定義 */
extern  void EnableInterrupt(void);
extern  void DisableInterrupt(void);
/* lcd.c */
extern  void InitLCD(void);
extern  void PrintLCD(char *fmt,...);
extern  void PutLCD(char c);
/* usb.c */
extern  void InitUSB(void);
extern  void DispUSBPort(void);
/* バッファ処理 */
extern  int get_inbufflen(void);
extern  int write_buff(char *p,int size);
extern  int read_buff(char *p,int size);
/* sci.c */
extern  void InitSCI(void);
extern  void PrintSCI(char *fmt, ...);
extern  int ScanSCI(void);
extern  char GetSCI(void);
/* main.c内定義 */
void H8init(void);
int SetLED(int no,int onoff);
```

```
int GetSW(int no);
#endif
/* 表示を表す列挙体宣言 */
enum PrintF
{
 Panel,
 ClsPnl,
 InputCommand,
 Monitor
};
/* 画面クリア */
void Clear(void);
/* 表示を表す関数のプロトタイプ宣言 */
void PrintF(int mode, char *str);
#ifdef USE_LINUX
int kbhit(void);
#endif
```

```
/* Panel.c */

#include "C.h"
#include "Panel.h"

/* 画面クリア */
void Clear(void)
{
#ifndef USE_BCC
 static char buff[64];
 sprintf(buff,"¥f");
 PrintLCD(buff);
#else
 CLEAR;
#endif
}

/* 表示のための関数 */
void PrintF(int mode, char *str)
{
#ifndef USE_BCC
 static char buff[64];
#endif
 switch(mode)
 {
 case ClsPnl:
#ifndef USE_BCC
  Clear();
```

```
  if(strcmp(str, "¥n¥0") == 0)
  {
      sprintf(str, "%s", "¥n¥f");
  }
  sprintf(buff,"%s", str);
  PrintSCI("%s",buff);
  PrintLCD(str);
#endif
  break;
 case Panel:
#ifndef USE_BCC
  if(strcmp(str, "¥n¥0") == 0)
  {
      sprintf(str, "%s", "¥n¥f");
  }
  sprintf(buff,"%s", str);
  PrintSCI("%s",buff);
  PrintLCD(str);
#else
  printf("%s", str);
#endif
  break;
 case InputCommand:
#ifdef USE_BCC
  printf("%s", str);
#endif
  break;
 case Monitor:
#ifndef USE_BCC
```

```
  sprintf(buff,"%s", str);
  PrintSCI("%s",buff);
  write_buff(buff,strlen(buff)+1);
#else
  printf("%s", str);
#endif
  break;
 default:
  break;
 }
 return;
}

#ifdef USE_LINUX
int kbhit(void)
{
    struct termios oldt, newt;
    int ch;
    int oldf;

    tcgetattr(STDIN_FILENO, &oldt);
    newt = oldt;
    newt.c_lflag &= ~(ICANON | ECHO);
    tcsetattr(STDIN_FILENO, TCSANOW, &newt);
    oldf = fcntl(STDIN_FILENO, F_GETFL, 0);
    fcntl(STDIN_FILENO, F_SETFL, oldf | O_NONBLOCK);

    ch = getchar();
```

```
    tcsetattr(STDIN_FILENO, TCSANOW, &oldt);
    fcntl(STDIN_FILENO, F_SETFL, oldf);

    if (ch != EOF) {
        ungetc(ch, stdin);
        return 1;
    }

    return 0;
}
#endif
```

```
/* Timer.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

/* 疑似スレッド定義 */
#ifdef USE_THREAD
/* 疑似スレッドに使用する定数の宣言 */
#define INITCLOCKNO -1
#define STOPCLOCKNO -2

/* 構造体宣言 */
typedef struct tag_Thread
{
	/* 疑似スレッドID */
	int ID;
	/* 指定開始時 */
	double preClock;
	/* woviClockがpreClockからsetClock秒増えたらRunを呼ぶ */
	double setClock;
	/* Runが呼ばれた回数を調べるために使用(countUpNextRunが呼ばれた回数) */
	long count;
	/* List機能 */
	struct tag_Thread *previous;
	struct tag_Thread *next;
}Thread;
```

```
/* 疑似メソッドとwovi用関数のプロトタイプ宣言 */
/* 宣言の順番は以下の通り */
#endif
double getClock(void);
void SleepMSec(long ms); /* ミリ秒待ち関数 */
#ifdef USE_THREAD
void nextRun(Thread *This, long ms);
void countUpNextRun(Thread *This, long ms);
void Run(Thread *This); /* main.cで内容を定義します */
void Init(Thread *This); /* main.cで内容を定義します */
void Destroy(Thread *This); /* main.cで内容を定義します */
Thread *new_Thread(int id);
void delete_(Thread *This);
void Start(Thread *This);
void Stop(Thread *This);
int Thread_checkAllDelete(void);
int Thread_checkStayAnother(void);
Thread *Thread_getThread(int id);
Thread *Thread_Start(int id);
void Thread_Toggle(int id);
/* タイマ関数 */
void woviRun(void); /* Runを呼ぶタイミング */
void woviInit(void); /* タイマ初期化関数 */
#ifndef USE_BCC
void InitITU(void); /* タイマ割り込み用 */
void InterruptITU0(void); /* タイマ割り込み用 */
#endif
void wovi(double threadPerSec); /* タイマ関数 */
```

```
void initWOVI(void); /* タイマ初期化関数 */
#endif
#ifdef USE_BCC
void PrintCurrentTime(void); /* 現在日時表示 */
#endif
```

```
/* Timer.c */

#include "C.h"
#include "Timer.h"

/* 時間を表す外部変数宣言 */
double woviClock;

/* 疑似スレッド定義 */
#ifdef USE_THREAD
/* wovi用疑似インスタンス宣言 */
Thread woviThreadFirst;
Thread woviThreadLast;
#endif

/* 時刻取得 */
double getClock(void)
{
	return woviClock;
}

/* ミリ秒待ち関数 */
void SleepMSec(long ms)
{
#ifndef USE_BCC
	double start;
	double set;
	double end;
```

```
	start = getClock();
	set = ((double) ms) / 1000;
	end = start;
	while(end < start + set)
	{
		end = getClock();
	}
#else
	double cnt;
	double set;
	cnt = 0.0;
	set = ((double) ms) / 1000;
	while(cnt < set)
	{
		cnt += 1.0 / SLEEP_PER_SEC;
	}
#endif
	return;
}

#ifdef USE_THREAD
/* スレッドのvoid Sleep(int ms)の代用 */
void nextRun(Thread *This, long ms)
{
	This->preClock = getClock();
	This->setClock = (((double) ms) / 1000);
	return;
}
```

```
/* スレッドのvoid Sleep(int ms)の代用 */
void countUpNextRun(Thread *This, long ms)
{
	nextRun(This, ms);
	This->count++;
}

#ifndef USE_BCC
Thread th101;
Thread th102;
Thread th111;
Thread th112;
Thread th113;
Thread th114;
Thread th119;
Thread th120;
Thread th121;
Thread th122;
Thread th123;
Thread th130;
Thread th131;
Thread th141;
Thread th142;
Thread th143;
#endif

/* スレッドのコンストラクタの代用 */
Thread *new_Thread(int id)
{
```

```
    Thread *List;
    Thread *new_List;
    List = &woviThreadFirst;
    while(List->next->next != NULL)
    {
        List = List->next;
    }
#ifndef USE_BCC
    if(id == 1)
    {
        new_List = &th101;
    }
    else if(id == 2)
    {
        new_List = &th102;
    }
    else if(id == 11)
    {
        new_List = &th111;
    }
    else if(id == 12)
    {
        new_List = &th112;
    }
    else if(id == 13)
    {
        new_List = &th113;
    }
    else if(id == 14)
```

```
{
	new_List = &th114;
}
else if(id == 19)
{
	new_List = &th119;
}
else if(id == 20)
{
	new_List = &th120;
}
else if(id == 21)
{
	new_List = &th121;
}
else if(id == 22)
{
	new_List = &th122;
}
else if(id == 23)
{
	new_List = &th123;
}
else if(id == 30)
{
	new_List = &th130;
}
else if(id == 31)
```

```
    {
        new_List = &th131;
    }
    else if(id == 41)
    {
        new_List = &th141;
    }
    else if(id == 42)
    {
        new_List = &th142;
    }
    else if(id == 43)
    {
        new_List = &th143;
    }
#endif
#ifdef USE_BCC
    new_List = (Thread *)calloc(1, sizeof(Thread));
#endif
    if(new_List == NULL)
    {
        PrintF(Panel, "¥n");
        PrintF(Panel, "calloc failed");
        return NULL;
    }
    new_List->previous = List;
    new_List->next = List->next;
    new_List->next->previous = new_List;
    List->next = new_List;
```

```
	new_List->preClock = INITCLOCKNO;
	new_List->setClock = 0;
	new_List->ID = id;
	new_List->count = 0;
	/* スレッドのvoid init(void)の代用 */
	Init(new_List);
	return new_List;
}

/* スレッドのデストラクタの代用 */
void delete_(Thread *This)
{
	Destroy(This);
	This->previous->next = This->next;
	This->next->previous = This->previous;
#ifdef USE_BCC
	free(This);
#endif
	return;
}

/* スレッドのvoid start(void)の代用 */
void Start(Thread *This)
{
	woviClock = getClock();
	This->preClock = woviClock;
	return;
}
```

```
/* スレッドのvoid stop(void)の代用 */
void Stop(Thread *This)
{
	This->preClock = STOPCLOCKNO;
	return;
}

int Thread_checkAllDelete(void)
{
	if(woviThreadFirst.next->next == NULL)
	{
		return OK;
	}
	else
	{
		return NG;
	}
}

int Thread_checkStayAnother(void)
{
	Thread *checkthread = woviThreadFirst.next->next;
	int i = 0;
	while(checkthread != NULL)
	{
		checkthread = checkthread->next;
		i = i + 1;
	}
	return i;
```

```
}

Thread *Thread_getThread(int id)
{
    Thread *th;

    if(woviThreadFirst.next->next == NULL)
    {
        return NULL;
    }
    else
    {
        th = woviThreadFirst.next;
        do
        {
            if(th->ID == id)
            {
                return th;
            }
            else
            {
                th = th->next;
            }
        }while(th->next != NULL);
    }
    return NULL;
}
```

```
Thread *Thread_Start(int id)
{
	Thread *th;

	th = Thread_getThread(id);
	if(th == NULL)
	{
		th = new_Thread(id);
		Start(th);
	}
	else if(th->preClock == STOPCLOCKNO)
	{
		Start(th);
	}
	return th;
}

void Thread_Toggle(int id)
{
	Thread *th;

	th = Thread_getThread(id);
	if(th == NULL)
	{
		th = new_Thread(id);
		Start(th);
	}
	else if(th->preClock == STOPCLOCKNO)
	{
```

```
            Start(th);
        }
        else
        {
            delete_(th);
        }
        return;
    }

    /* タイマ関数 */
    /* Runを呼ぶタイミング */
    void woviRun(void)
    {
        Thread *List;
        Thread *next_List;
        List = &woviThreadFirst;
        List = List->next;
        while(List->next != NULL)
        {
            next_List = List->next;
            if((List->preClock != INITCLOCKNO) && (List->preClock != STOPCLOCKNO))
            {
                if(woviClock >= List->preClock + List->setClock)
                {
                    List->preClock = woviClock;
                    /* スレッドのvoid run(void)の代用 */
                    Run(List);
                }
            }
```

```
            List = next_List;
        }
        return;
}

/* タイマ初期化関数 */
/* 関数main の冒頭で、 */
/* スレッド構造体リスト の 両端 を初期化します。 */
void woviInit(void)
{
        woviThreadFirst.previous = NULL;
        woviThreadFirst.next = &woviThreadLast;
        woviThreadLast.previous = &woviThreadFirst;
        woviThreadLast.next = NULL;
        return;
}

#ifndef USE_BCC
/* タイマ割り込み用 */
/* 関数main の冒頭で、 */
/* タイマ割り込み の専用設定をして、 */
/* タイマ0割り込み を立ち上げます。 */
void InitITU(void)
{
        ITU.TSTR = 0x01; /* timer 0 enable */
        ITU.TSNC = 0;
        ITU.TMDR = 0x0;
        ITU.TFCR = 0x0;
        ITU.TOER = 0x0;
```

```
    ITU.TOCR = 0xff;
    ITU0.TCR = 0x00; /* 分周なし */
    ITU0.TIOR = 0x88;
    ITU0.TIER = 0x04; /* オーバーフロー割り込み許可 */
    /* AKI-H8 3052F USB の演算速度は 25MHz なので、 */
    /* 25Kカウント すると、 1ms です。 */
    ITU0.TCNT = 0xffff - 25000; /* 1 msec interval */
    ITU0.GRA = 0;
    ITU0.GRB = 0;
}

/* タイマ割り込み用 */
/* 周りの関数が 関数main から呼び出されているのに、 */
/* この関数だけは、 asmfile.src の タイマ0割り込み から */
/* 直接呼び出されています。 */
void InterruptITU0(void)
{
    ITU0.TSR &= 0xfb;
    /* AKI-H8 3052F USB の演算速度は 25MHz なので、 */
    /* 25Kカウント すると、 1ms です。 */
    ITU0.TCNT = 0xffff - 25000; /* 1 msec interval */
    /* woviClock はシステムリセット時からの秒数時計です。 */
    woviClock += 0.001;
    return;
}
#endif

/* タイマ関数 */
```

```
void wovi(double threadPerSec)
{
#ifdef USE_BCC
    /* woviClock は秒数時計 */
#ifdef USE_LINUX
    /* threadPerSec で受け取る数値が1に近づく程、 */
    /* スピードが上がります。 */
    /* threadPerSec で受け取る数値が大きくなる程、 */
    /* スピードが下がります。 */
    /* タイマ割り込み を使用できない時に */
    /* threadPerSec を使用します。 */
    woviClock += 1.0 / threadPerSec;
#else
    /* もしくは、 <time.h> の clock() を使用します。 */
    woviClock = (double) (clock() / CLOCKS_PER_SEC);
#endif
#endif
    woviRun(); /* スレッドのためのRunを呼ぶタイミング */
    return;
}

/* タイマ初期化関数 */
void initWOVI(void)
{
    /* 関数main の冒頭で、 */
    /* 秒数時計woviClock を */
    /* 0.0秒 で初期化します。 */
    woviClock = 0.0;
    /* タイマ割り込み用 */
```

```
#ifndef USE_BCC
    /* タイマ0割り込み を立ち上げます。 */
    InitITU();
    /* asmfile.src の 割り込み許可ラベル を呼びます。 */
    EnableInterrupt();
#endif
    /* スレッド構造体リスト の 両端 を初期化します。 */
    wovilnit();
    return;
}
#endif

#ifdef USE_BCC
/* 現在日時表示 */
void PrintCurrentTime(void)
{
    time_t timer;
    struct tm *t_st;

    /* 現在時刻の取得 */
    time(&timer);

    /* 現在時刻を構造体に変換 */
    t_st = localtime(&timer);

    printf("%d",t_st->tm_year+1900);
    if(t_st->tm_mon+1 < 10)
    {
        printf("0%d",t_st->tm_mon+1);
```

```
}
else
{
    printf("%d",t_st->tm_mon+1);
}
if(t_st->tm_mday < 10)
{
    printf("0%d",t_st->tm_mday);
}
else
{
    printf("%d",t_st->tm_mday);
}
printf(" ");
if(t_st->tm_hour < 10)
{
    printf("0%d",t_st->tm_hour);
}
else
{
    printf("%d",t_st->tm_hour);
}
if(t_st->tm_min < 10)
{
    printf("0%d",t_st->tm_min);
}
else
{
    printf("%d",t_st->tm_min);
```

```
        }
        if(t_st->tm_sec < 10)
        {
            printf("0%d",t_st->tm_sec);
        }
        else
        {
            printf("%d",t_st->tm_sec);
        }

        return;
    }
    #endif
```

```
/* EV_Time.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#define OPENTIMEOUT 10

/*==============================================================
 時間を表す構造体
==============================================================*/
struct EV_Time{
	double TimeTemp;
	double *p_TimeTemp;
	int Permit;
	int *p_Permit;
	int tmpTimeSafety;
	Thread *th;
};

/*==============================================================
 時間を表すプロトタイプ宣言
```

```
==========================================================*/
void EV_Time(struct EV_Time *This, Thread *th);
void SetCurrentTime(struct EV_Time *This);
int GetCurrentTime(struct EV_Time *This);
void WaitSecond(struct EV_Time *This, int num_Second);
void SetPermit(struct EV_Time *This, int P);
int GetPermit(struct EV_Time *This);
void Checkfmove(int *p_check, int *p_fmove, int tmp);
void Wait_ms(struct EV_Time *This, int num);
```

```
/* EV_Time.c */

#include "C.h"
#include "EV_Time.h"

/*==========================================================================
  時間を表す関数
==========================================================================*/
void EV_Time(struct EV_Time *This, Thread *th)
{
	This->TimeTemp = 0;
	This->p_TimeTemp = &This->TimeTemp;
	SetCurrentTime(This);
	This->p_Permit = &This->Permit;
	This->Permit = OFF;
	This->tmpTimeSafety = 0;
	This->th = th;

	/* 戻る */
	return;
}

void SetCurrentTime(struct EV_Time *This)
{
	This->p_TimeTemp = &This->TimeTemp;
	*This->p_TimeTemp = getClock();

	/* 戻る */
```

```
	return;
}

int GetCurrentTime(struct EV_Time *This)
{
	This->p_TimeTemp = &This->TimeTemp;
	return (int) (getClock() - *This->p_TimeTemp);
}

void WaitSecond(struct EV_Time *This, int num_Second)
{
	nextRun(This->th, (num_Second * 1000));
	/* 戻る */
	return;
}

void SetPermit(struct EV_Time *This, int P)
{
	This->p_Permit = &This->Permit;
	if(P == ON) This->Permit = ON;
	else if(P == OFF) This->Permit = OFF;

	/* 戻る */
	return;
}

int GetPermit(struct EV_Time *This)
{
	This->p_Permit = &This->Permit;
```

```
	return This->Permit;
}

void Checkfmove(int *p_check, int *p_fmove, int tmp)
{
	if(*p_check != tmp){
		*p_fmove = OFF;
		*p_check = tmp;
	}

	/* 戻る */
	return;
}

void Wait_ms(struct EV_Time *This, int num){

	nextRun(This->th, num);
	/* 戻る */
	return;
}
```

```
/* EV_File.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

/*============================================================
  ファイルを表す構造体
============================================================*/
#ifdef NOTUSE_FILES
typedef struct tag_Handle_EV_Status
{
	char safety;
	char *p_limit;
	char limit[9];
	char motor;
	char command;
	char permitcommand;
	char permitturnopen;
}Handle_EV_Status;

typedef struct tag_EV_Status
{
	Handle_EV_Status *p_status;
}EV_Status;
#endif
```

```
/* ファイルストリーム */
struct EV_File
{
	FILE *fp;
};

/*==========================================================
  ファイルを表すプロトタイプ宣言
==========================================================*/
#ifdef NOTUSE_FILES
void new_EV_Status(EV_Status *This);
#endif

void EV_File(struct EV_File *This);
int Write(struct EV_File *This, char *filename, char ch);
int WriteString(struct EV_File *This, char *filename, char *str);
int Read(struct EV_File *This, char *filename, char *p_ch);
int ReadString(struct EV_File *This, char *filename, char *str, int strlength);
int PermitCommand_Read(struct EV_File *This, char *p_PermitCommand);
int PermitCommand_Write(struct EV_File *This, char PermitCommand);
int Command_Read(struct EV_File *This, char *p_Command);
int Command_Write(struct EV_File *This, char Command);
int PermitTurnOpen_Read(struct EV_File *This, char *p_PermitTurnOpen);
int PermitTurnOpen_Write(struct EV_File *This, char PermitTurnOpen);
void Motor_Write(struct EV_File *This, char Motor);
char Motor_Read(struct EV_File *This);
void Limit_Read(struct EV_File *This, char *str);
```

```
/* EV_File.c */

#include "C.h"
#include "EV_File.h"

/*==========================================================================
  ファイル不使用時大域オブジェクト宣言
==========================================================================*/
#ifdef NOTUSE_FILES
Handle_EV_Status status;
#endif

/*==========================================================================
  ファイルを表す関数
==========================================================================*/
#ifdef NOTUSE_FILES
void new_EV_Status(EV_Status *This)
{
	This->p_status = &status;
	status.safety = 'r';
	status.p_limit = &status.limit[0];
	strcpy(status.p_limit, "yynnyynn¥0");
	status.motor = 's';
	status.command = 'N';
	status.permitcommand = 'N';
	status.permitturnopen = 'N';
}
#endif
```

```
void EV_File(struct EV_File *This)
{
	/* 初期値 */
	This->fp = NULL;

	/* 戻る */
	return;
}

#ifdef NOTUSE_FILES
int Write(struct EV_File *This, char *filename, char ch)
{
	switch(filename[0])
	{
	case 'S':
		status.safety = ch;
		break;
	case 'M':
		status.motor = ch;
		break;
	case 'C':
		status.command = ch;
		break;
	case 'P':
		switch(filename[6])
		{
		case 'C':
			status.permitcommand = ch;
```

```
                break;
            case 'T':
                status.permitturnopen = ch;
                break;
            default:
                break;
            }
            break;
        default:
            break;
        }
        return OK;
    }
    #else
    int Write(struct EV_File *This, char *filename, char ch)
    {
        int Ret = OK;
        if((This->fp = fopen(filename, "w")) == NULL){
            Ret = NG;
        }
        else if(fputc((int) ch, This->fp) == ch){
            fclose(This->fp);
            Ret = OK;
        }
        else{
            fclose(This->fp);
            Ret = NG;
        }
        return Ret;
```

```
}
#endif

#ifdef NOTUSE_FILES
int WriteString(struct EV_File *This, char *filename, char *str)
{
	switch(filename[0])
	{
	case 'L':
		status.p_limit = &status.limit[0];
		strcpy(status.p_limit, str);
		break;
	default:
		break;
	}
	return OK;
}
#else
/* 文字列書き込み */
int WriteString(struct EV_File *This, char *filename, char *str)
{
	int Ret = OK;
	if((This->fp = fopen(filename, "w")) == NULL){
		Ret = NG;
	}
	/* ¥nは追記されない */
	else if(fputs(str, This->fp) >= 0){
		fclose(This->fp);
		/* 書き込み成功 */
```

```
        Ret = OK;
    }
    else{
        fclose(This->fp);
        /* 書き込み失敗 */
        Ret = NG;
    }
    return Ret;
}
#endif

#ifdef NOTUSE_FILES
int Read(struct EV_File *This, char *filename, char *p_ch)
{
    switch(filename[0])
    {
    case 'S':
        *p_ch = status.safety;
        break;
    case 'M':
        *p_ch = status.motor;
        break;
    case 'C':
        *p_ch = status.command;
        break;
    case 'P':
        switch(filename[6])
        {
```

```
            case 'C':
                *p_ch = status.permitcommand;
                break;
            case 'T':
                *p_ch = status.permitturnopen;
                break;
            default:
                break;
            }
            break;
        default:
            break;
        }
        return OK;
}
#else
int Read(struct EV_File *This, char *filename, char *p_ch)
{
        int Ret = OK;
        if((This->fp = fopen(filename, "r")) == NULL){
            Ret = NG;
        }
        else if((*p_ch = fgetc(This->fp)) == EOF){
            fclose(This->fp);
            Ret = ONE_MORE_TIME;
        }
        else if(*p_ch == '¥n'){
            fclose(This->fp);
            Ret = ONE_MORE_TIME;
```

```
        }
        else if(*p_ch == 'N'){
            fclose(This->fp);
            Ret = ONE_MORE_TIME;
        }
        else{
            fclose(This->fp);
            Ret = OK;
        }
        return Ret;
    }
    #endif

    #ifdef NOTUSE_FILES
    int ReadString(struct EV_File *This, char *filename, char *str, int strlength)
    {
        switch(filename[0])
        {
        case 'L':
            status.p_limit = &status.limit[0];
            strcpy(str, status.p_limit);
            break;
        default:
            break;
        }
        return OK;
    }
    #else
    int ReadString(struct EV_File *This, char *filename, char *str, int strlength)
```

```
{
	int Ret = OK;
	if((This->fp = fopen(filename, "r")) == NULL){
		Ret = NG;
	}
	else if(fgets(str, strlength, This->fp) == NULL){
		fclose(This->fp);
		Ret = ONE_MORE_TIME;
	}
	else if(str[0] == '¥n'){
		fclose(This->fp);
		Ret = ONE_MORE_TIME;
	}
	else if(str[0] == 'N'){
		fclose(This->fp);
		Ret = ONE_MORE_TIME;
	}
	else{
		fclose(This->fp);
		Ret = OK;
	}
	return Ret;
}
#endif

int PermitCommand_Read(struct EV_File *This, char *p_PermitCommand)
{
	int Ret = OK;
	switch(Read(This, "PermitCommand.txt¥0", p_PermitCommand)){
```

```
	case NG:
		PrintF(ClsPnl, "¥nReading Error");
		Ret = NG;
		break;
	case ONE_MORE_TIME:
		Ret = ONE_MORE_TIME;
		break;
	default:
		Ret = OK;
		break;
	}
	return Ret;
}

int PermitCommand_Write(struct EV_File *This, char PermitCommand)
{
	int Ret = OK;
	switch(Write(This, "PermitCommand.txt¥0", PermitCommand)){
	case NG:
		PrintF(ClsPnl, "¥nWriting Error");
		Ret = NG;
		break;
	case OK:
		Ret = OK;
		break;
	default:
		Ret = NG;
		break;
```

```
	}
	return Ret;
}

int Command_Read(struct EV_File *This, char *p_Command)
{
	int Ret = OK;
	switch(Read(This, "Command.txt¥0", p_Command)){
	case NG:
		PrintF(ClsPnl, "¥nReading Error");
		Ret = NG;
		break;
	case ONE_MORE_TIME:
		Ret = ONE_MORE_TIME;
		break;
	default:
		Ret = OK;
		break;
	}
	return Ret;
}

int Command_Write(struct EV_File *This, char Command)
{
	int Ret = OK;
	switch(Write(This, "Command.txt¥0", Command)){
	case NG:
		PrintF(ClsPnl, "¥nWriting Error");
		Ret = NG;
```

```
        break;
    case OK:
        Ret = OK;
        break;
    default:
        Ret = NG;
        break;
    }
    return Ret;
}

int PermitTurnOpen_Read(struct EV_File *This, char *p_PermitTurnOpen)
{
    int Ret = OK;
    switch(Read(This, "PermitTurnOpen.txt¥0", p_PermitTurnOpen)){
    case NG:
        PrintF(ClsPnl, "¥nReading Error");
        Ret = NG;
        break;
    case ONE_MORE_TIME:
        Ret = ONE_MORE_TIME;
        break;
    default:
        Ret = OK;
        break;
    }
    return Ret;
}
```

```
int PermitTurnOpen_Write(struct EV_File *This, char PermitTurnOpen)
{
	int Ret = OK;
	switch(Write(This, "PermitTurnOpen.txt¥0", PermitTurnOpen)){
	case NG:
		PrintF(ClsPnl, "¥nWriting Error");
		Ret = NG;
		break;
	case OK:
		Ret = OK;
		break;
	default:
		Ret = NG;
		break;
	}
	return Ret;
}

void Motor_Write(struct EV_File *This, char Motor)
{
	switch(Write(This, "Motor.txt¥0", Motor)){
	case NG:
		PrintF(ClsPnl, "¥nWriting Error");
		break;
	case OK:
		return;
		break;
	default:
		break;
```

```
	}

	/* 戻る */
	return;
}

char Motor_Read(struct EV_File *This)
{
	char ch;
	char *p_ch;
	ch = '¥0';
	p_ch = &ch;

	switch(Read(This, "Motor.txt¥0", p_ch)){
	case NG:
		break;
	case ONE_MORE_TIME:
		return '¥0';
		break;
	case OK:
		return ch;
		break;
	default:
		break;
	}
	return '¥0';
}
```

```
void Limit_Read(struct EV_File *This, char *str)
{
	switch(ReadString(This, "Limit.txt¥0", str, 9)){
	case NG:
		PrintF(ClsPnl, "¥nReading Error");
		break;
	case ONE_MORE_TIME:
		return;
		break;
	default:
		return;
		break;
	}

	/* 戻る */
	return;
}
```

```
/* EV_UpDown.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

/*==========================================================================
  上昇下降を表す構造体
==========================================================================*/
struct Position
{
    int m_UNSL;
```

```
    int m_UNST;
    int m_UPSL;
    int m_UPST;
    /* 下降減速位置 */
    int *p_UnderSlow;
    /* 下降停止位置 */
    int *p_UnderStop;
    /* 上昇減速位置 */
    int *p_UpperSlow;
    /* 上昇停止位置 */
    int *p_UpperStop;
    /* Sleep用 */
    int fstop;
    int *p_fstop;
    int fmove;
    int *p_fmove;
};

/* 上昇 */
struct UpMotor
{
    struct EV_File SF;
    struct EV_File MF;
};

/* 下降 */
struct DownMotor
{
    struct EV_File SF;
```

```
	struct EV_File MF;
};

/* エレベーターの位置仮想ログ */
struct WaitPositionChangeLog
{
	struct EV_File LF;
	char strLimit[9];
	char *p_strLimit;
	/* Sleep用 */
	int tmp;
};

/*==========================================================
  上昇下降を表すプロトタイプ宣言
==========================================================*/
void Position(struct Position *This);
/* 上昇 */
void UpMotor(struct UpMotor *This);
void OnUpMotor(struct UpMotor *This, struct Position *P, char *p_Safety);
/* 下降 */
void DownMotor(struct DownMotor *This);
void OnDownMotor(struct DownMotor *This, struct Position *P, char *p_Safety);
/* 経過時間 */
void WaitPositionChangeLog(struct WaitPositionChangeLog *This);
void OnInitWaitPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P);
void OnWaitUpPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P);
void OnWaitDownPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P);
/* 上昇 */
```

```
void Up(struct Position *P, struct UpMotor UPMT, struct WaitPositionChangeLog WPCL, char
*p_Safety);
/* 下降 */
void Down(struct Position *P, struct DownMotor DNMT, struct WaitPositionChangeLog WPCL, char
*p_Safety);
```

```
/* EV_UpDown.c */

#include "C.h"
#include "EV_UpDown.h"

/*==========================================================================
  上昇下降を表す関数
==========================================================================*/
/*
 * Position
 */
void Position(struct Position *This)
{
	/* 初期値 */
	This->m_UNSL = OFF;
	This->m_UNST = OFF;
	This->m_UPSL = OFF;
	This->m_UPST = OFF;
	This->p_UnderSlow = &This->m_UNSL;
	This->p_UnderStop = &This->m_UNST;
	This->p_UpperSlow = &This->m_UPSL;
	This->p_UpperStop = &This->m_UPST;
	/* Sleep用 */
	This->fstop = OFF;
	This->p_fstop = &This->fstop;
	This->fmove = OFF;
	This->p_fmove = &This->fmove;
```

```
	/* 戻る */
	return;
}

/*
 * UpMotor
 */
void UpMotor(struct UpMotor *This)
{
	EV_File(&This->SF);
	EV_File(&This->MF);

	/* 戻る */
	return;
}

/*
 * OnUpMotor
 */
/* 上昇 */
void OnUpMotor(struct UpMotor *This, struct Position *P, char *p_Safety)
{
	if(*P->p_UpperStop == ON){
		/* Sleep用 */
		if(*P->p_fstop == OFF){
			*P->p_fstop = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 's');
			PrintF(ClsPnl, "STOP");
```

```
        }
        if(*p_Safety == 'Y'){
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*P->p_UpperSlow == ON){
        /* Sleep用 */
        *P->p_fstop = OFF;
        if(*P->p_fmove == OFF){
            *P->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'u');
            PrintF(ClsPnl, "UP");
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'j');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*P->p_UnderSlow == OFF){
        /* Sleep用 */
        *P->p_fstop = OFF;
        if(*P->p_fmove == OFF){
            *P->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'U');
            PrintF(ClsPnl, "UP Speedy");
```

```
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'j');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*P->p_UnderStop == OFF){
        /* Sleep用 */
        *P->p_fstop = OFF;
        if(*P->p_fmove == OFF){
            *P->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'u');
            PrintF(ClsPnl, "UP");
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'j');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*P->p_UnderStop == ON){
        /* Sleep用 */
        *P->p_fstop = OFF;
        if(*P->p_fmove == OFF){
            *P->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'j');
```

```
            PrintF(ClsPnl, "UP Start");
        }
        if(*p_Safety == 'Y'){
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }

    /* 戻る */
    return;
}

/*
 * DownMotor
 */
void DownMotor(struct DownMotor *This)
{
    EV_File(&This->SF);
    EV_File(&This->MF);

    /* 戻る */
    return;
}

/*
 * OnDownMotor
 */
/* 下降 */
```

```
void OnDownMotor(struct DownMotor *This, struct Position *P, char *p_Safety)
{
	if(*P->p_UnderStop == ON){
		/* Sleep用 */
		if(*P->p_fstop == OFF){
			*P->p_fstop = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 's');
			PrintF(ClsPnl, "STOP");
		}
		if(*p_Safety == 'Y'){
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
		}
	}
	else if(*P->p_UnderSlow == ON){
		/* Sleep用 */
		*P->p_fstop = OFF;
		if(*P->p_fmove == OFF){
			*P->p_fmove = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 'd');
			PrintF(ClsPnl, "DOWN");
		}
		else if(*p_Safety == 'Y'){
			Motor_Write(&This->MF, 'k');
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
		}
```

```
}
else if(*P->p_UpperSlow == OFF){
	/* Sleep用 */
	*P->p_fstop = OFF;
	if(*P->p_fmove == OFF){
		*P->p_fmove = ON;
		/* 現在実行中の命令を外部に報告 */
		Motor_Write(&This->MF, 'D');
		PrintF(ClsPnl, "DOWN Speedy");
	}
	else if(*p_Safety == 'Y'){
		Motor_Write(&This->MF, 'k');
		*p_Safety = 'r';
		Write(&This->SF, "Safety.txt¥0", 'r');
	}
}
else if(*P->p_UpperStop == OFF){
	/* Sleep用 */
	*P->p_fstop = OFF;
	if(*P->p_fmove == OFF){
		*P->p_fmove = ON;
		/* 現在実行中の命令を外部に報告 */
		Motor_Write(&This->MF, 'd');
		PrintF(ClsPnl, "DOWN");
	}
	else if(*p_Safety == 'Y'){
		Motor_Write(&This->MF, 'k');
		*p_Safety = 'r';
		Write(&This->SF, "Safety.txt¥0", 'r');
```

```
            }
        }
        else if(*P->p_UpperStop == ON){
            /* Sleep用 */
            *P->p_fstop = OFF;
            if(*P->p_fmove == OFF){
                *P->p_fmove = ON;
                /* 現在実行中の命令を外部に報告 */
                Motor_Write(&This->MF, 'k');
                PrintF(ClsPnl, "DOWN Start");
            }
            if(*p_Safety == 'Y'){
                *p_Safety = 'r';
                Write(&This->SF, "Safety.txt¥0", 'r');
            }
        }

        /* 戻る */
        return;
    }

    /*
     * WaitPositionChangeLog
     */
    /* エレベーターの位置仮想ログ */
    void WaitPositionChangeLog(struct WaitPositionChangeLog *This)
    {
        This->p_strLimit = &This->strLimit[0];
```

```
	/* 戻る */
	return;
}

/*
 * OnInitWaitPositionChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnInitWaitPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P)
{
	/* センサ初期値 */
	/* リミットスイッチの読み込み */
	This->p_strLimit = &This->strLimit[0];
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = ((This->strLimit[0] == 'y') ? ON : OFF);
	Checkfmove(P->p_UnderStop, P->p_fmove, This->tmp);
	This->tmp = ((This->strLimit[1] == 'y') ? ON : OFF);
	Checkfmove(P->p_UnderSlow, P->p_fmove, This->tmp);
	This->tmp = ((This->strLimit[2] == 'y') ? ON : OFF);
	Checkfmove(P->p_UpperSlow, P->p_fmove, This->tmp);
	This->tmp = ((This->strLimit[3] == 'y') ? ON : OFF);
	Checkfmove(P->p_UpperStop, P->p_fmove, This->tmp);

	/* 戻る */
	return;
}

/*
```

```
 * OnWaitUpPositionChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnWaitUpPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P)
{
	/* リミットスイッチの読み込み */
	This->p_strLimit = &This->strLimit[0];
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = (This->strLimit[0] == 'y') ? ON : OFF;
	Checkfmove(P->p_UnderStop, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[1] == 'y') ? ON : OFF;
	Checkfmove(P->p_UnderSlow, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[2] == 'y') ? ON : OFF;
	Checkfmove(P->p_UpperSlow, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[3] == 'y') ? ON : OFF;
	Checkfmove(P->p_UpperStop, P->p_fmove, This->tmp);

	/* 戻る */
	return;
}

/*
 * OnWaitDownPositionChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnWaitDownPositionChangeLog(struct WaitPositionChangeLog *This, struct Position *P)
{
	/* リミットスイッチの読み込み */
	This->p_strLimit = &This->strLimit[0];
```

```
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = (This->strLimit[0] == 'y') ? ON : OFF;
	Checkfmove(P->p_UnderStop, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[1] == 'y') ? ON : OFF;
	Checkfmove(P->p_UnderSlow, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[2] == 'y') ? ON : OFF;
	Checkfmove(P->p_UpperSlow, P->p_fmove, This->tmp);
	This->tmp = (This->strLimit[3] == 'y') ? ON : OFF;
	Checkfmove(P->p_UpperStop, P->p_fmove, This->tmp);

	/* 戻る */
	return;
}

/*
 * Up
 */
/* 上昇 */
void Up(struct Position *P, struct UpMotor UPMT, struct WaitPositionChangeLog WPCL, char
*p_Safety)
{
	/* 到着まで */
	if(*P->p_UpperStop == OFF){
		/* エレベーターの位置仮想ログ */
		OnWaitUpPositionChangeLog(&WPCL, P);

		/* 上昇 */
		OnUpMotor(&UPMT, P, p_Safety);
```

```
        /* エレベーターの位置仮想ログ */
        OnWaitUpPositionChangeLog(&WPCL, P);
    }

    /* 戻る */
    return;
}

/*
 * Down
 */
/* 下降 */
void Down(struct Position *P, struct DownMotor DNMT, struct WaitPositionChangeLog WPCL, char
*p_Safety)
{
    /* 到着まで */
    if(*P->p_UnderStop == OFF){
        /* エレベーターの位置仮想ログ */
        OnWaitDownPositionChangeLog(&WPCL, P);

        /* 下降 */
        OnDownMotor(&DNMT, P, p_Safety);

        /* エレベーターの位置仮想ログ */
        OnWaitDownPositionChangeLog(&WPCL, P);
    }

    /* 戻る */
    return;
```

```
}
```

```
/* EV_OpenClose.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

#ifndef EV_UpDown_h
#define EV_UpDown_h
#include "EV_UpDown.h"
#endif

/*==============================================================
```

```
 開閉を表す構造体
==========================================================================*/
struct Door
{
	int m_CLSL;
	int m_CLST;
	int m_OPSL;
	int m_OPST;
	/* 閉減速位置 */
	int *p_CloserSlow;
	/* 閉停止位置 */
	int *p_CloserStop;
	/* 開減速位置 */
	int *p_OpennerSlow;
	/* 開停止位置 */
	int *p_OpennerStop;
	/* Sleep用 */
	int fstop;
	int *p_fstop;
	int fmove;
	int *p_fmove;
};

/* 開 */
struct OpenMotor
{
	struct EV_File SF;
	struct EV_File MF;
};
```

```
/* 閉 */
struct CloseMotor
{
	struct EV_File  SF;
	struct EV_File  MF;
};

/* エレベーターの位置仮想ログ */
struct WaitDoorChangeLog
{
	struct EV_File TOF;
	char chTurnOpen;
	char *p_chTurnOpen;
	struct EV_File LF;
	char strLimit[9];
	char *p_strLimit;
	/* Sleep用 */
	int tmp;
};

/*==========================================================
  開閉を表すプロトタイプ宣言
==========================================================*/
void Door(struct Door *This);
/* 開 */
void OpenMotor(struct OpenMotor *This);
void OnOpenMotor(struct OpenMotor *This, struct Door *DR, char *p_Safety);
/* 閉 */
```

```
void CloseMotor(struct CloseMotor *This);
void OnCloseMotor(struct CloseMotor *This, struct Door *DR, char *p_Safety);
/* 経過時間 */
void WaitDoorChangeLog(struct WaitDoorChangeLog *This);
void OnInitWaitDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR);
void OnWaitOpenDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR);
void OnWaitCloseDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR);
/* 開 */
void Open(struct Door *DR, struct OpenMotor OPMT, struct WaitDoorChangeLog WDCL, char
*p_Safety);
/* 閉 */
void Close(struct Door *DR, struct CloseMotor CLMT, struct WaitDoorChangeLog WDCL, char
*p_Safety);
```

```
/* EV_OpenClose.c */

#include "C.h"
#include "EV_OpenClose.h"

/*==========================================================================
 開閉を表す関数
==========================================================================*/
/*
 * Door
 */
void Door(struct Door *This)
{
	/* 初期値 */
	This->m_CLSL = OFF;
	This->m_CLST = OFF;
	This->m_OPSL = OFF;
	This->m_OPST = OFF;
	This->p_CloserSlow = &This->m_CLSL;
	This->p_CloserStop = &This->m_CLST;
	This->p_OpennerSlow = &This->m_OPSL;
	This->p_OpennerStop = &This->m_OPST;
	/* Sleep用 */
	This->fstop = OFF;
	This->p_fstop = &This->fstop;
	This->fmove = OFF;
	This->p_fmove = &This->fmove;
```

```
	/* 戻る */
	return;
}

/*
 * OpenMotor
 */
void OpenMotor(struct OpenMotor *This)
{
	EV_File(&This->SF);
	EV_File(&This->MF);

	/* 戻る */
	return;
}

/*
 * OnOpenMotor
 */
/* 開 */
void OnOpenMotor(struct OpenMotor *This, struct Door *DR, char *p_Safety)
{
	if(*DR->p_OpennerStop == ON){
		/* Sleep用 */
		if(*DR->p_fstop == OFF){
			*DR->p_fstop = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 's');
			PrintF(ClsPnl, "STOP");
```

```
        }
        if(*p_Safety == 'Y'){
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*DR->p_OpennerSlow == ON){
        /* Sleep用 */
        *DR->p_fstop = OFF;
        if(*DR->p_fmove == OFF){
            *DR->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'o');
            PrintF(ClsPnl, "OPEN");
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'h');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*DR->p_CloserSlow == OFF){
        /* Sleep用 */
        *DR->p_fstop = OFF;
        if(*DR->p_fmove == OFF){
            *DR->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'O');
            PrintF(ClsPnl, "OPEN Speedy");
```

```
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'h');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*DR->p_CloserStop == OFF){
        /* Sleep用 */
        *DR->p_fstop = OFF;
        if(*DR->p_fmove == OFF){
            *DR->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'o');
            PrintF(ClsPnl, "OPEN");
        }
        else if(*p_Safety == 'Y'){
            Motor_Write(&This->MF, 'h');
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }
    else if(*DR->p_CloserStop == ON){
        /* Sleep用 */
        *DR->p_fstop = OFF;
        if(*DR->p_fmove == OFF){
            *DR->p_fmove = ON;
            /* 現在実行中の命令を外部に報告 */
            Motor_Write(&This->MF, 'h');
```

```
            PrintF(ClsPnl, "OPEN Start");
        }
        if(*p_Safety == 'Y'){
            *p_Safety = 'r';
            Write(&This->SF, "Safety.txt¥0", 'r');
        }
    }

    /* 戻る */
    return;
}

/*
 * CloseMotor
 */
void CloseMotor(struct CloseMotor *This)
{
    EV_File(&This->SF);
    EV_File(&This->MF);

    /* 戻る */
    return;
}

/*
 * OnCloseMotor
 */
/* 閉 */
```

```
void OnCloseMotor(struct CloseMotor *This, struct Door *DR, char *p_Safety)
{
	if(*DR->p_CloserStop == ON){
		/* Sleep用 */
		if(*DR->p_fstop == OFF){
			*DR->p_fstop = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 's');
			PrintF(ClsPnl, "STOP");
		}
		if(*p_Safety == 'Y'){
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
		}
	}
	else if(*DR->p_CloserSlow == ON){
		/* Sleep用 */
		*DR->p_fstop = OFF;
		if(*DR->p_fmove == OFF){
			*DR->p_fmove = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 'c');
			PrintF(ClsPnl, "CLOSE");
		}
		else if(*p_Safety == 'Y'){
			Motor_Write(&This->MF, 't');
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
		}
```

```
	}
	else if(*DR->p_OpennerSlow == OFF){
		/* Sleep用 */
		*DR->p_fstop = OFF;
		if(*DR->p_fmove == OFF){
			*DR->p_fmove = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 'C');
			PrintF(ClsPnl, "CLOSE Speedy");
		}
		else if(*p_Safety == 'Y'){
			Motor_Write(&This->MF, 't');
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
		}
	}
	else if(*DR->p_OpennerStop == OFF){
		/* Sleep用 */
		*DR->p_fstop = OFF;
		if(*DR->p_fmove == OFF){
			*DR->p_fmove = ON;
			/* 現在実行中の命令を外部に報告 */
			Motor_Write(&This->MF, 'c');
			PrintF(ClsPnl, "CLOSE");
		}
		else if(*p_Safety == 'Y'){
			Motor_Write(&This->MF, 't');
			*p_Safety = 'r';
			Write(&This->SF, "Safety.txt¥0", 'r');
```

```
            }
        }
        else if(*DR->p_OpennerStop == ON){
            /* Sleep用 */
            *DR->p_fstop = OFF;
            if(*DR->p_fmove == OFF){
                *DR->p_fmove = ON;
                /* 現在実行中の命令を外部に報告 */
                Motor_Write(&This->MF, 't');
                PrintF(ClsPnl, "CLOSE Start");
            }
            if(*p_Safety == 'Y'){
                *p_Safety = 'r';
                Write(&This->SF, "Safety.txt¥0", 'r');
            }
        }

        /* 戻る */
        return;
    }

    /*
     * WaitDoorChangeLog
     */
    /* エレベーターの位置仮想ログ */
    void WaitDoorChangeLog(struct WaitDoorChangeLog *This)
    {
        This->p_chTurnOpen = &This->chTurnOpen;
        This->p_strLimit = &This->strLimit[0];
```

```
	/* 戻る */
	return;
}

/*
 * OnInitWaitDoorChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnInitWaitDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR)
{
	/* センサ初期値 */
	/* リミットスイッチの読み込み */
	This->p_strLimit = &This->strLimit[0];
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = (This->strLimit[4] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserStop, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[5] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[6] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[7] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerStop, DR->p_fmove, This->tmp);

	/* 戻る */
	return;
}
```

```
/*
 * OnWaitOpenDoorChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnWaitOpenDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR)
{
	/* リミットスイッチの読み込み */
	This->p_strLimit = &This->strLimit[0];
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = (This->strLimit[4] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserStop, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[5] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[6] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[7] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerStop, DR->p_fmove, This->tmp);

	/* 戻る */
	return;
}

/*
 * OnWaitCloseDoorChangeLog
 */
/* エレベーターの位置仮想ログ */
void OnWaitCloseDoorChangeLog(struct WaitDoorChangeLog *This, struct Door *DR)
{
	/* リミットスイッチの読み込み */
```

```
	This->p_strLimit = &This->strLimit[0];
	Limit_Read(&This->LF, This->p_strLimit);
	This->tmp = (This->strLimit[4] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserStop, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[5] == 'y') ? ON : OFF;
	Checkfmove(DR->p_CloserSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[6] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerSlow, DR->p_fmove, This->tmp);
	This->tmp = (This->strLimit[7] == 'y') ? ON : OFF;
	Checkfmove(DR->p_OpennerStop, DR->p_fmove, This->tmp);

	/* 戻る */
	return;
}

/*
 * Open
 */
/* 開 */
void Open(struct Door *DR, struct OpenMotor OPMT, struct WaitDoorChangeLog WDCL, char
*p_Safety)
{
	/* 到着まで */
	if(*DR->p_OpennerStop == OFF)
	{
		/* エレベーターの位置仮想ログ */
		OnWaitOpenDoorChangeLog(&WDCL, DR);

		/* 開 */
```

```
        OnOpenMotor(&OPMT, DR, p_Safety);

        /* エレベーターの位置仮想ログ */
        OnWaitOpenDoorChangeLog(&WDCL, DR);
    }

    /* 戻る */
    return;
}

/*
 * Close
 */
/* 閉 */
void Close(struct Door *DR, struct CloseMotor CLMT, struct WaitDoorChangeLog WDCL, char
*p_Safety)
{
    /* 到着まで */
    if(*DR->p_CloserStop == OFF)
    {
        /* エレベーターの位置仮想ログ */
        OnWaitCloseDoorChangeLog(&WDCL, DR);

        /* 閉 */
        OnCloseMotor(&CLMT, DR, p_Safety);

        /* エレベーターの位置仮想ログ */
        OnWaitCloseDoorChangeLog(&WDCL, DR);
    }
```

```
	/* 戻る */
	return;
}
```

```
/* EV_Input.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

#ifndef EV_UpDown_h
#define EV_UpDown_h
#include "EV_UpDown.h"
#endif

#ifndef EV_OpenClose_h
```

```
#define EV_OpenClose_h
#include "EV_OpenClose.h"
#endif

/*==========================================================================
 入力を表す関数のプロトタイプ宣言
==========================================================================*/
char GetChar(char Ret);

/*==========================================================================
 入力を表す構造体
==========================================================================*/
struct EV_Input
{
    /* 安全 */
    char Safety;
    char *p_Safety;
    char Command;
    char PermitCommand;
    char *p_PermitCommand;
    char PermitTurnOpen;
    char *p_PermitTurnOpen;
    char ch;
    char *p_ch;
    char str[9];
    char *p_str;

    /* ファイルストリーム */
    struct EV_File SF;
```

```
    struct EV_File CF;
    struct EV_File PCF;
    struct EV_File PTOF;
    struct EV_File LF;
    struct EV_File MF;
};

/*==========================================================================
  入力を表すコンストラクタとメソッドのプロトタイプ宣言
==========================================================================*/
void EV_Input(struct EV_Input *This);
void OnInput(struct EV_Input *This, Thread *th);
```

```
/* EV_Input.c */

#include "C.h"
#include "EV_Input.h"

/*==========================================================================
  入力を表す関数
==========================================================================*/
char GetChar(char Ret)
{
#ifndef USE_BCC
	char sw[4];
	int i;
	int j;
	/* スイッチワーク初期化 */
	sw[0] = sw[1] = sw[2] = sw[3] = 0;
	/* ボタンが押された時にLCD,SCI,USBにメッセージを送る */
	for(j=0;j<4;j++)
	{
		i = GetSW(j);
		if( ((sw[j]^1) & i) ) /* sw = off->onで条件成立 */
		{
			switch(j){
			case 0:
				Ret = 'u'; /* sw0 Up 2階で開く */
				break;
			case 1:
				Ret = 'd'; /* sw1 Down 1階で開く */
```

```
                break;
            case 2:
                Ret = 'c'; /* sw2 Close 閉じる */
                break;
            case 3:
                Ret = 'q'; /* sw3 Quit 終了 */
                break;
            default:
                break;
            }
        }
    }
#elif USE_LINUX
    if(kbhit())
    {
        Ret = (char) getchar();
    }
#elif USE_MSVS2005
    if(_kbhit())
    {
        Ret = (char) _getche();
    }
#else
    if(kbhit())
    {
        Ret = (char) getche();
    }
#endif
    return Ret;
```

```
}

/*==========================================================================
  入力を表すコンストラクタとメソッド
==========================================================================*/
void EV_Input(struct EV_Input *This)
{
	/* 初期化 */
	This->Command = '¥0';
	This->p_ch = &This->ch;
	This->p_str = &This->str[0];
	This->str[8] = '¥0';
	/* 安全初期化 */
	This->p_Safety = &This->Safety;
	/* 入力許可初期化 */
	This->p_PermitCommand = &This->PermitCommand;
	/* 反転開許可初期化 */
	This->p_PermitTurnOpen = &This->PermitTurnOpen;

	EV_File(&This->SF);
	EV_File(&This->CF);
	EV_File(&This->PCF);
	EV_File(&This->PTOF);
	EV_File(&This->MF);

	/* 安全入力 */
	if(Read(&This->SF, "Safety.txt¥0", This->p_Safety) == NG) return;
	/* 入力許可 */
	if(PermitCommand_Read(&This->PCF, This->p_PermitCommand) == NG) return;
```

```
	/* 反転開許可 */
	if(PermitTurnOpen_Read(&This->PTOF, This->p_PermitTurnOpen) == NG) return;
	/* モーター命令解読 */
	if(Read(&This->MF, "Motor.txt¥0", This->p_ch) == NG) return;
	/* リミットスイッチの前状態読み込み */
	ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9);
}

void OnInput(struct EV_Input *This, Thread *th)
{
	if(Command_Read(&This->CF, &This->Command) == NG) return;
	This->Command = GetChar(This->Command);

	/* 安全入力 */
	if(Read(&This->SF, "Safety.txt¥0", This->p_Safety) == NG) return;
	/* 入力許可 */
	if(PermitCommand_Read(&This->PCF, This->p_PermitCommand) == NG) return;
	/* 反転開許可 */
	if(PermitTurnOpen_Read(&This->PTOF, This->p_PermitTurnOpen) == NG) return;
	/* モーター命令解読 */
	if(Read(&This->MF, "Motor.txt¥0", This->p_ch) == NG) return;
	/* リミットスイッチの前状態読み込み */
	ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9);

	switch(This->Command){
	case 's':
		/* 命令入力 */
		Write(&This->SF, "Safety.txt", 's');
		Motor_Write(&This->MF, 's');
```

```
        This->Command = 'N';
        Command_Write(&This->CF, 'N');
        PermitCommand_Write(&This->PCF, 'N');
        break;
    case 'r':
        /* 命令入力 */
        Write(&This->SF, "Safety.txt", 'h');
        This->Command = 'N';
        Command_Write(&This->CF, 'N');
        PermitCommand_Write(&This->PCF, 'c');
        break;
    case 'q':
        /* 命令入力 */
        Command_Write(&This->CF, This->Command);
        PrintF(ClsPnl, "QUIT");
        delete_(th);
        break;
    default:
        if(This->PermitCommand == 'c'){
            switch(This->Command){
            case 'o':
                if(This->str[4] != 'y'){
                    PermitTurnOpen_Write(&This->PTOF, 'o');
                }
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
```

```
            if((This->ch == 's') && (This->Safety == 'Y') && (This->str[7] == 'n')){
                Motor_Write(&This->MF, 'h');
            }
        }
        /* 命令入力 */
        Command_Write(&This->CF, This->Command);
        PermitCommand_Write(&This->PCF, 'N');
        break;
    case 'c':
        if(This->str[4] != 'y'){
            PermitTurnOpen_Write(&This->PTOF, 'o');
        }
        if(This->Safety == 'h'){
            /* 命令入力 */
            This->Safety = 'Y';
            Write(&This->SF, "Safety.txt", 'Y');
            if((This->ch == 's') && (This->Safety == 'Y') && (This->str[4] == 'n')){
                Motor_Write(&This->MF, 't');
            }
        }
        /* 命令入力 */
        Command_Write(&This->CF, This->Command);
        PermitCommand_Write(&This->PCF, 'N');
        break;
    case 'u':
        if(This->str[4] != 'y'){
            PermitTurnOpen_Write(&This->PTOF, 'o');
        }
        if(This->Safety == 'h'){
```

```
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'y') && (This->str[4] == 'n')){
                        Motor_Write(&This->MF, 't');
                    }
                    else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'n')){
                        Motor_Write(&This->MF, 'j');
                    }
                    else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'y') && (This->str[7] == 'n')){
                        Motor_Write(&This->MF, 'h');
                    }
                }
                /* 命令入力 */
                Command_Write(&This->CF, This->Command);
                PermitCommand_Write(&This->PCF, 'N');
                break;
            case 'd':
                if(This->str[4] != 'y'){
                    PermitTurnOpen_Write(&This->PTOF, 'o');
                }
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'y') && (This->str[4] == 'n')){
```

```
                    Motor_Write(&This->MF, 't');
                }
                else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'n')){
                    Motor_Write(&This->MF, 'k');
                }
                else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'y') && (This->str[7] == 'n')){
                    Motor_Write(&This->MF, 'h');
                }
            }
            /* 命令入力 */
            Command_Write(&This->CF, This->Command);
            PermitCommand_Write(&This->PCF, 'N');
            break;
        case 'y':
            if((This->str[0] != 'y') && (This->str[4] != 'y')){
                PrintF(ClsPnl, "¥nA Basket isn't 1st Floor");
            }
            else{
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'n')){
                        Motor_Write(&This->MF, 'k');
                    }
                    else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'y') && (This->str[7] == 'n')){
                        Motor_Write(&This->MF, 'h');
```

```
                    }
                }
                /* 命令入力 */
                Command_Write(&This->CF, This->Command);
                PermitCommand_Write(&This->PCF, 'N');
            }
            break;
        case 'Y':
            if((This->str[3] != 'y') && (This->str[4] != 'y')){
                PrintF(ClsPnl, "¥nA Basket isn't 2nd Floor");
            }
            else{
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'n')){
                        Motor_Write(&This->MF, 'j');
                    }
                    else if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'y') &&
(This->str[7] == 'n')){
                        Motor_Write(&This->MF, 'h');
                    }
                }
                /* 命令入力 */
                Command_Write(&This->CF, This->Command);
                PermitCommand_Write(&This->PCF, 'N');
            }
```

```
        break;
    case 'h':
        if(This->str[0] != 'y'){
            PrintF(ClsPnl, "¥nA Basket isn't 1st Floor");
        }
        else{
            if(This->str[4] != 'y'){
                PermitTurnOpen_Write(&This->PTOF, 'o');
            }
            if(This->Safety == 'h'){
                /* 命令入力 */
                This->Safety = 'Y';
                Write(&This->SF, "Safety.txt", 'Y');
                if((This->ch == 's') && (This->Safety == 'Y') && (This->str[4] == 'n')){
                    Motor_Write(&This->MF, 't');
                }
            }
            /* 命令入力 */
            Command_Write(&This->CF, This->Command);
            PermitCommand_Write(&This->PCF, 'N');
        }
        break;
    case 'H':
        if(This->str[3] != 'y'){
            PrintF(ClsPnl, "¥nA Basket isn't 2nd Floor");
        }
        else{
            if(This->str[4] != 'y'){
                PermitTurnOpen_Write(&This->PTOF, 'o');
```

```
                }
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[4] == 'n')){
                        Motor_Write(&This->MF, 't');
                    }
                }
                /* 命令入力 */
                Command_Write(&This->CF, This->Command);
                PermitCommand_Write(&This->PCF, 'N');
            }
            break;
        default:
            break;
        }
    }
    else if(This->PermitTurnOpen == 'o'){
        if((This->str[0] == 'y') && (This->str[7] != 'y')){
            switch(This->Command){
            case 'o':
            case 'd':
            case 'y':
                if(This->Safety == 'h'){
                    /* 命令入力 */
                    This->Safety = 'Y';
                    Write(&This->SF, "Safety.txt", 'Y');
                    if((This->ch == 's') && (This->Safety == 'Y') && (This->str[0] == 'y') && (This-
```

```
>str[7] == 'n')){
                                Motor_Write(&This->MF, 'h');
                            }
                        }
                        /* 命令入力 */
                        Command_Write(&This->CF, This->Command);
                        PermitTurnOpen_Write(&This->PTOF, 'N');
                        break;
                    default:
                        break;
                    }
                }
                else if((This->str[3] == 'y') && (This->str[7] != 'y')){
                    switch(This->Command){
                    case 'o':
                    case 'u':
                    case 'Y':
                        if(This->Safety == 'h'){
                            /* 命令入力 */
                            This->Safety = 'Y';
                            Write(&This->SF, "Safety.txt", 'Y');
                            if((This->ch == 's') && (This->Safety == 'Y') && (This->str[3] == 'y') && (This-
>str[7] == 'n')){
                                Motor_Write(&This->MF, 'h');
                            }
                        }
                        /* 命令入力 */
                        Command_Write(&This->CF, This->Command);
                        PermitTurnOpen_Write(&This->PTOF, 'N');
```

```
                    break;
                default:
                    break;
                }
            }
        }
        break;
    }
    return;
}
```

```
/* EV_Controller.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

#ifndef EV_UpDown_h
#define EV_UpDown_h
#include "EV_UpDown.h"
#endif

#ifndef EV_OpenClose_h
```

```
#define EV_OpenClose_h
#include "EV_OpenClose.h"
#endif

/*==========================================================================
 制御盤を表す構造体宣言
==========================================================================*/
struct EV_Controller
{
    /* エレベーターの現在位置オブジェクトの宣言 */
    struct Position P;
    struct Position *p_P;

    /* 上昇オブジェクトの宣言 */
    struct UpMotor UPMT;
    /* 下降オブジェクトの宣言 */
    struct DownMotor DNMT;

    /* エレベーターの位置仮想ログ */
    struct WaitPositionChangeLog WPCL;

    /* エレベーターの現在位置オブジェクトの宣言 */
    struct Door DR;
    struct Door *p_DR;

    /* 開オブジェクトの宣言 */
    struct OpenMotor OPMT;
    /* 閉オブジェクトの宣言 */
    struct CloseMotor CLMT;
```

```
    /* エレベーターの位置仮想ログ */
    struct WaitDoorChangeLog WDCL;

    /* 経過時間テンポラリ */
    struct EV_Time T;

    /* 安全 */
    char Safety;
    char *p_Safety;
    /* Limit */
    char str[9];
    char *p_str;
    /* 命令 */
    char Command;
    char *p_Command;
    char PermitCommand;
    char *p_PermitCommand;
    char PermitTurnOpen;
    char *p_PermitTurnOpen;

    /* ファイルストリーム */
    struct EV_File SF;
    struct EV_File LF;
    struct EV_File CF;
    struct EV_File PCF;
    struct EV_File PTOF;
    struct EV_File MF;
};
```

```
/*==========================================================================
  制御を表すコンストラクタとメソッドのプロトタイプ宣言
==========================================================================*/
void EV_Controller(struct EV_Controller *This, Thread *th);
void OnController(struct EV_Controller *This, Thread *th);
```

```
/* EV_Controller.c */

#include "C.h"
#include "EV_Controller.h"

/*==========================================================================
  制御関数
==========================================================================*/
void EV_Controller(struct EV_Controller *This, Thread *th)
{
    /* 初期化 */
    This->p_P = &This->P;
    Position(This->p_P);
    UpMotor(&This->UPMT);
    DownMotor(&This->DNMT);
    WaitPositionChangeLog(&This->WPCL);
    This->p_DR = &This->DR;
    Door(This->p_DR);
    OpenMotor(&This->OPMT);
    CloseMotor(&This->CLMT);
    WaitDoorChangeLog(&This->WDCL);
    EV_Time(&This->T, th);
    EV_File(&This->SF);
    EV_File(&This->LF);
    EV_File(&This->CF);
    EV_File(&This->PCF);
    EV_File(&This->PTOF);
    EV_File(&This->MF);
```

```
    /* 安全初期化 */
    This->p_Safety = &This->Safety;
    /* Limit初期化 */
    This->p_str = &This->str[0];
    /* 命令初期化 */
    This->p_Command = &This->Command;
    This->p_PermitCommand = &This->PermitCommand;
    This->p_PermitTurnOpen = &This->PermitTurnOpen;

    /* モーター停止命令 */
    Motor_Write(&This->MF, 's');

    /* エレベーターの位置仮想ログ */
    /* 初期値 */
    OnInitWaitPositionChangeLog(&This->WPCL, This->p_P);

    /* エレベーターの位置仮想ログ */
    /* 初期値 */
    OnInitWaitDoorChangeLog(&This->WDCL, This->p_DR);

    /* リミットスイッチの前状態読み込み */
    ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9);
    /* 命令初期化 */
    if(Command_Write(&This->CF, 'N') == NG) return;
    if(PermitCommand_Write(&This->PCF, 'c') == NG) return;
    if(PermitTurnOpen_Write(&This->PTOF, 'N') == NG) return;
}
```

```
/*
 * 主制御関数
 */
void OnController(struct EV_Controller *This, Thread *th)
{
	/* 安全入力 */
	if(Read(&This->SF, "Safety.txt¥0", This->p_Safety) == NG) return;
	/* リミットスイッチの前状態読み込み */
	ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9);
	/* 命令入力 */
	if(Command_Read(&This->CF, This->p_Command) == NG) return;
	/* 入力許可 */
	if(PermitCommand_Read(&This->PCF, This->p_PermitCommand) == NG) return;
	/* 反転開許可 */
	if(PermitTurnOpen_Read(&This->PTOF, This->p_PermitTurnOpen) == NG) return;

	switch(This->Command){
	/* 終了命令ならば */
	case 'q':
		Motor_Write(&This->MF, 's');
		delete_(th);
		break;
	/* 非常停止命令ならば */
	case 's':
		SetPermit(&This->T, OFF);
		break;
	/* 復帰命令ならば */
	case 'r':
		break;
```

```
/* 上階呼命令ならば */
case 'Y':
    if((*This->p_P->p_UnderStop == ON) && (*This->p_DR->p_CloserStop == OFF)){
        break;
    }
/* 上昇命令ならば */
case 'u':
    if(*This->p_P->p_UpperStop == ON){
        /* 開完了時 */
        if(*This->p_DR->p_OpennerStop == ON){
            PermitCommand_Write(&This->PCF, 'c');
            SetPermit(&This->T, ON);
            Command_Write(&This->CF, 'N');
            Clear();
            PrintF(Panel, "Hello EV       ");
            break;
        }
        else{
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
            /* 開 */
            Open(This->p_DR,This->OPMT,This->WDCL, This->p_Safety);
        }
    }
    else if(*This->p_DR->p_CloserStop == ON){
        /* 閉完了時 */
        SetPermit(&This->T, OFF);
        SetCurrentTime(&This->T);
        PermitTurnOpen_Write(&This->PTOF, 'N');
```

```
            /* 上昇 */
            Up(This->p_P,This->UPMT,This->WPCL, This->p_Safety);
        }
        else if(*This->p_DR->p_CloserStop == OFF){
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
            /* 閉 */
            Close(This->p_DR,This->CLMT,This->WDCL, This->p_Safety);
        }
        else{
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
        }
        break;
    /* 下階呼命令ならば */
    case 'y':
        if((*This->p_P->p_UpperStop == ON) && (*This->p_DR->p_CloserStop == OFF)){
            break;
        }
    /* 下降命令ならば */
    case 'd':
        if(*This->p_P->p_UnderStop == ON){
            /* 開完了時 */
            if(*This->p_DR->p_OpennerStop == ON){
                PermitCommand_Write(&This->PCF, 'c');
                SetPermit(&This->T, ON);
                Command_Write(&This->CF, 'N');
                Clear();
```

```
            PrintF(Panel, "Hello EV       ");
            break;
        }
        else{
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
            /* 開 */
            Open(This->p_DR,This->OPMT,This->WDCL, This->p_Safety);
        }
    }
    else if(*This->p_DR->p_CloserStop == ON){
        /* 閉完了時 */
        SetPermit(&This->T, OFF);
        SetCurrentTime(&This->T);
        PermitTurnOpen_Write(&This->PTOF, 'N');
        /* 下降 */
        Down(This->p_P,This->DNMT,This->WPCL, This->p_Safety);
    }
    else if(*This->p_DR->p_CloserStop == OFF){
        SetPermit(&This->T, OFF);
        SetCurrentTime(&This->T);
        /* 閉 */
        Close(This->p_DR,This->CLMT,This->WDCL, This->p_Safety);
    }
    else{
        SetPermit(&This->T, OFF);
        SetCurrentTime(&This->T);
    }
    break;
```

```
/* 開命令ならば */
case 'o':
	/* 開完了時 */
	if(*This->p_DR->p_OpennerStop == ON){
		PermitCommand_Write(&This->PCF, 'c');
		SetPermit(&This->T, ON);
		Command_Write(&This->CF, 'N');
		Clear();
		PrintF(Panel, "Hello EV       ");
		break;
	}
	else{
		SetPermit(&This->T, OFF);
		SetCurrentTime(&This->T);
		/* 開 */
		Open(This->p_DR,This->OPMT,This->WDCL, This->p_Safety);
	}
	break;
/* 閉命令ならば */
case 'c':
	SetPermit(&This->T, OFF);
	SetCurrentTime(&This->T);
	/* 閉完了時 */
	if(*This->p_DR->p_CloserStop == ON){
		PermitTurnOpen_Write(&This->PTOF, 'N');
		Command_Write(&This->CF, 'N');
		PermitCommand_Write(&This->PCF, 'c');
		Clear();
		PrintF(Panel, "Hello EV       ");
```

```
            break;
        }
        else{
            /* 閉 */
            Close(This->p_DR,This->CLMT,This->WDCL, This->p_Safety);
        }
        break;
    /* 閉命令ならば */
    case 'H':
        if(*This->p_P->p_UpperStop == ON){
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
            /* 閉完了時 */
            if(*This->p_DR->p_CloserStop == ON){
                Command_Write(&This->CF, 'N');
                PermitTurnOpen_Write(&This->PTOF, 'N');
                PermitCommand_Write(&This->PCF, 'c');
                Clear();
                PrintF(Panel, "Hello EV       ");
                break;
            }
            else{
                /* 閉 */
                Close(This->p_DR,This->CLMT,This->WDCL, This->p_Safety);
            }
        }

        break;
    /* 閉命令ならば */
```

```
    case 'h':
        if(*This->p_P->p_UnderStop == ON){
            SetPermit(&This->T, OFF);
            SetCurrentTime(&This->T);
            /* 閉完了時 */
            if(*This->p_DR->p_CloserStop == ON){
                Command_Write(&This->CF, 'N');
                PermitTurnOpen_Write(&This->PTOF, 'N');
                PermitCommand_Write(&This->PCF, 'c');
                Clear();
                PrintF(Panel, "Hello EV       ");
                break;
            }
            else{
                /* 閉 */
                Close(This->p_DR,This->CLMT,This->WDCL, This->p_Safety);
            }
        }
        break;
    default:
        break;
    }
    if((GetCurrentTime(&This->T) >= OPENTIMEOUT) && (*This->p_DR->p_OpennerStop == ON) &&
(GetPermit(&This->T) == ON)){
        SetPermit(&This->T, OFF);
        SetCurrentTime(&This->T);
        PermitTurnOpen_Write(&This->PTOF, 'o');
        PermitCommand_Write(&This->PCF, 'N');
```

```
        /* 閉 */
        Command_Write(&This->CF, 'c');
    }
    return;
}
```

```
/* EV_Simulator.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

#ifndef EV_UpDown_h
#define EV_UpDown_h
#include "EV_UpDown.h"
#endif

#ifndef EV_OpenClose_h
```

```
#define EV_OpenClose_h
#include "EV_OpenClose.h"
#endif

/*==========================================================================
 シミュレータを表す関数のプロトタイプ宣言
==========================================================================*/
void DispInput(void);
void Disp(char ch, char str[9]);

/*==========================================================================
 シミュレータを表す構造体
==========================================================================*/
struct EV_Simulator
{
	char ch;
	char *p_ch;
	char ch2;
	char *p_ch2;
	char ch3;
	char *p_ch3;
	char str[9];
	char *p_str;

	/* 時間管理 */
	struct EV_Time T;

	/* ファイルストリーム */
	struct EV_File SF;
```

```
    struct EV_File CF;
    struct EV_File MF;
    struct EV_File LF;
};

/*==========================================================
  シミュレータを表すコンストラクタとメソッドのプロトタイプ宣言
==========================================================*/
void EV_Simulator(struct EV_Simulator *This, Thread *th);
void OnSimulator(struct EV_Simulator *This, Thread *th);
```

```
/* EV_Simulator.c */

#include "C.h"
#include "EV_Simulator.h"

/*==========================================================================
  シミュレータ関数
==========================================================================*/
void EV_Simulator(struct EV_Simulator *This, Thread *th)
{
	/* 初期化 */
	EV_Time(&This->T, th);
	SetCurrentTime(&This->T);
	This->p_ch = &This->ch;
	This->p_ch2 = &This->ch2;
	This->p_ch3 = &This->ch3;
	This->p_str = &This->str[0];
	This->str[8] = '¥0';
	EV_File(&This->SF);
	EV_File(&This->CF);
	EV_File(&This->MF);
	EV_File(&This->LF);

	/* モーター命令解読 */
	if(Read(&This->MF, "Motor.txt¥0", This->p_ch) == NG) return;
	/* リミットスイッチの前状態読み込み */
	if(ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9) == NG) return;
	/* 籠表示 */
```

```
	Disp(This->ch, This->str);
}

void OnSimulator(struct EV_Simulator *This, Thread *th)
{
	/* 終了条件 */
	Read(&This->CF, "Command.txt¥0", This->p_ch3);
	if(This->ch3 == 'q'){
		Clear();
		delete_(th);
		return;
	}

	/* モーター命令解読 */
	Read(&This->MF, "Motor.txt¥0", This->p_ch);

	/* リミットスイッチの前状態読み込み */
	ReadString(&This->LF, "Limit.txt¥0", This->p_str, 9);

	/* 停止条件 */
	Read(&This->SF, "Safety.txt¥0", This->p_ch2);
	if(This->ch2 == 's'){
		Write(&This->CF, "Command.txt¥0", 'N');
		/* 籠表示 */
		Disp(This->ch, This->str);
		return;
	}

	/* リミットスイッチの新状態作成 */
```

```
if(This->ch == 'u'){
        if(This->str[0] == 'y');
        else if(This->str[1] == 'y') This->str[1] = 'n';
        else if(This->str[2] == 'n');
        else if(This->str[3] == 'n') This->str[3] = 'y';
}
else if(This->ch == 'U'){
        if(This->str[0] == 'y');
        else if(This->str[1] == 'y');
        else if(This->str[2] == 'n') This->str[2] = 'y';
        else if(This->str[3] == 'n');
}
else if(This->ch == 'j'){
        if(This->str[0] == 'y') This->str[0] = 'n';
        else if(This->str[1] == 'y') This->str[1] = 'n';
        else if(This->str[2] == 'n') This->str[2] = 'y';
        else if(This->str[3] == 'n') This->str[3] = 'y';
}
else if(This->ch == 'd'){
        if(This->str[3] == 'y');
        else if(This->str[2] == 'y') This->str[2] = 'n';
        else if(This->str[1] == 'n');
        else if(This->str[0] == 'n') This->str[0] = 'y';
}
else if(This->ch == 'D'){
        if(This->str[3] == 'y');
        else if(This->str[2] == 'y');
        else if(This->str[1] == 'n') This->str[1] = 'y';
        else if(This->str[0] == 'n');
```

```
}
else if(This->ch == 'k'){
	if(This->str[3] == 'y') This->str[3] = 'n';
	else if(This->str[2] == 'y') This->str[2] = 'n';
	else if(This->str[1] == 'n') This->str[1] = 'y';
	else if(This->str[0] == 'n') This->str[0] = 'y';
}
else if(This->ch == 'o'){
	if(This->str[4] == 'y');
	else if(This->str[5] == 'y') This->str[5] = 'n';
	else if(This->str[6] == 'n');
	else if(This->str[7] == 'n') This->str[7] = 'y';
}
else if(This->ch == 'O'){
	if(This->str[4] == 'y');
	else if(This->str[5] == 'y');
	else if(This->str[6] == 'n') This->str[6] = 'y';
	else if(This->str[7] == 'n');
}
else if(This->ch == 'h'){
	if(This->str[4] == 'y') This->str[4] = 'n';
	else if(This->str[5] == 'y') This->str[5] = 'n';
	else if(This->str[6] == 'n') This->str[6] = 'y';
	else if(This->str[7] == 'n') This->str[7] = 'y';
}
else if(This->ch == 'c'){
	if(This->str[7] == 'y');
	else if(This->str[6] == 'y') This->str[6] = 'n';
	else if(This->str[5] == 'n');
```

```
        else if(This->str[4] == 'n') This->str[4] = 'y';
    }
    else if(This->ch == 'C'){
        if(This->str[7] == 'y');
        else if(This->str[6] == 'y');
        else if(This->str[5] == 'n') This->str[5] = 'y';
        else if(This->str[4] == 'n');
    }
    else if(This->ch == 't'){
        if(This->str[7] == 'y') This->str[7] = 'n';
        else if(This->str[6] == 'y') This->str[6] = 'n';
        else if(This->str[5] == 'n') This->str[5] = 'y';
        else if(This->str[4] == 'n') This->str[4] = 'y';
    }

    /* リミットスイッチの新状態書き込み */
    WriteString(&This->LF, "Limit.txt¥0", This->str);

    /* 籠表示 */
    Disp(This->ch, This->str);

    return;
}

void DispInput(void)
{
    /* 入力指示 */
    PrintF(InputCommand, "¥nUP = 'u', DOWN = 'd', OPEN = 'o', CLOSE = 'c'");
```

```
    PrintF(InputCommand, "¥nEMERGENCY = 's', RECOVERY = 'r'");
    PrintF(InputCommand, "¥n1st Floor CALL = 'y', 2nd Floor CALL = 'Y'");
    PrintF(InputCommand, "¥n1st Floor CLOSE = 'h', 2nd Floor CLOSE = 'H'");
    PrintF(InputCommand, "¥nQUIT = 'q'");
    PrintF(InputCommand, "¥nCOMMAND>");
}

/*
 * 表示関数
 */
void Disp(char ch, char str[9])
{
    int    i;
#ifdef USE_BCC
    /* 画面クリア */
    CLEAR;
#endif
    if      ((((ch == 'u') || (ch == 'j')) && (str[3] == 'y') && (str[2] == 'y'))
        ||  ((ch == 'k') && (str[3] == 'n') && (str[2] == 'y')))
    {
        for(i = 0; i < 4; i++)
        {
                PrintF(Monitor, "¥n    00000000    ");
        }
        for(i = 4; i < 12; i++)
        {
                PrintF(Monitor, "¥n                ");
        }
    }
```

```
    else if((((ch == 'U') ¦¦ (ch == 'j')) && (str[3] == 'n') && (str[2] == 'y'))
        ¦¦  (((ch == 'd') ¦¦ (ch == 'k')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n'))
        ¦¦  ((ch == 's') && (str[3] == 'n') && (str[2] == 'y')))
    {
        for(i = 0; i < 2; i++)
        {
            PrintF(Monitor, "¥n            ");
        }
        for(i = 2; i < 6; i++)
        {
            PrintF(Monitor, "¥n    00000000    ");
        }
        for(i = 6; i < 12; i++)
        {
            PrintF(Monitor, "¥n            ");
        }
    }
    else if((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n'))
    {
        for(i = 0; i < 4; i++)
        {
            PrintF(Monitor, "¥n            ");
        }
        for(i = 4; i < 8; i++)
        {
            PrintF(Monitor, "¥n    00000000    ");
        }
        for(i = 8; i < 12; i++)
```

```
        {
                PrintF(Monitor, "¥n              ");
        }
    }
    else if((((ch == 'u') ¦¦ (ch == 'j')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n'))
        ¦¦  (((ch == 'D') ¦¦ (ch == 'k')) && (str[1] == 'y') && (str[0] == 'n'))
        ¦¦  ((ch == 's') && (str[1] == 'y') && (str[0] == 'n')))
    {
        for(i = 0; i < 6; i++)
        {
                PrintF(Monitor, "¥n              ");
        }
        for(i = 6; i < 10; i++)
        {
                PrintF(Monitor, "¥n    00000000    ");
        }
        for(i = 10; i < 12; i++)
        {
                PrintF(Monitor, "¥n              ");
        }
    }
    else if(((ch == 'j') && (str[1] == 'y') && (str[0] == 'n'))
        ¦¦  (((ch == 'd') ¦¦ (ch == 'k')) && (str[1] == 'y') && (str[0] == 'y')))
    {
        for(i = 0; i < 8; i++)
        {
                PrintF(Monitor, "¥n              ");
        }
```

```
        for(i = 8; i < 12; i++)
        {
                PrintF(Monitor, "¥n    00000000    ");
        }
    }
    else if((str[3] == 'y') && (str[2] == 'y'))
    {
        if    (((ch == 's') && (str[7] == 'y') && (str[6] == 'y'))
            ¦¦  (((ch == 'o') ¦¦ (ch == 'h')) && (str[7] == 'y') && (str[6] == 'y'))
            ¦¦  ((ch == 't') && (str[7] == 'n') && (str[6] == 'y')))
        {
            for(i = 0; i < 4; i++)
            {
                PrintF(Monitor, "¥n0000       0000");
            }
            for(i = 4; i < 12; i++)
            {
                PrintF(Monitor, "¥n              ");
            }
        }
        else if((((ch == 'O') ¦¦ (ch == 'h')) && (str[7] == 'n') && (str[6] == 'y'))
            ¦¦  (((ch == 'c') ¦¦ (ch == 't')) && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4]
 == 'n'))
            ¦¦  ((ch == 's') && (str[7] == 'n') && (str[6] == 'y')))
        {
            for(i = 0; i < 4; i++)
            {
                PrintF(Monitor, "¥n 0000     0000 ");
```

```
            }
            for(i = 4; i < 12; i++)
            {
                PrintF(Monitor, "¥n              ");
            }
        }
        else if((ch == 's') && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4] == 'n'))
        {
            for(i = 0; i < 4; i++)
            {
                PrintF(Monitor, "¥n  0000    0000  ");
            }
            for(i = 4; i < 12; i++)
            {
                PrintF(Monitor, "¥n              ");
            }
        }
        else if((((ch == 'o') ¦¦ (ch == 'h')) && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4]
== 'n'))
            ¦¦  (((ch == 'C') ¦¦ (ch == 't')) && (str[5] == 'y') && (str[4] == 'n'))
            ¦¦  ((ch == 's') && (str[5] == 'y') && (str[4] == 'n')))
        {
            for(i = 0; i < 4; i++)
            {
                PrintF(Monitor, "¥n   0000  0000   ");
            }
            for(i = 4; i < 12; i++)
            {
                PrintF(Monitor, "¥n              ");
```

```
            }
        }
        else if(((ch == 's') && (str[5] == 'y') && (str[4] == 'y'))
            ¦¦  ((ch == 'h') && (str[5] == 'y') && (str[4] == 'n'))
            ¦¦  (((ch == 'c') ¦¦ (ch == 't')) && (str[5] == 'y') && (str[4] == 'y')))
        {
            for(i = 0; i < 4; i++)
            {
                PrintF(Monitor, "¥n    00000000    ");
            }
            for(i = 4; i < 12; i++)
            {
                PrintF(Monitor, "¥n                ");
            }
        }
    }
    else if((str[1] == 'y') && (str[0] == 'y'))
    {
        if    (((ch == 's') && (str[7] == 'y') && (str[6] == 'y'))
            ¦¦  (((ch == 'o') ¦¦ (ch == 'h')) && (str[7] == 'y') && (str[6] == 'y'))
            ¦¦  ((ch == 't') && (str[7] == 'n') && (str[6] == 'y')))
        {
            for(i = 0; i < 8; i++)
            {
                PrintF(Monitor, "¥n                ");
            }
            for(i = 8; i < 12; i++)
            {
                PrintF(Monitor, "¥n0000       0000");
```

```
            }
        }
        else if((((ch == 'O') ¦¦ (ch == 'h')) && (str[7] == 'n') && (str[6] == 'y'))
            ¦¦  (((ch == 'c') ¦¦ (ch == 't')) && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4]
== 'n'))
            ¦¦  ((ch == 's') && (str[7] == 'n') && (str[6] == 'y')))
        {
            for(i = 0; i < 8; i++)
            {
                PrintF(Monitor, "¥n              ");
            }
            for(i = 8; i < 12; i++)
            {
                PrintF(Monitor, "¥n 0000     0000 ");
            }
        }
        else if((ch == 's') && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4] == 'n'))
        {
            for(i = 0; i < 8; i++)
            {
                PrintF(Monitor, "¥n              ");
            }
            for(i = 8; i < 12; i++)
            {
                PrintF(Monitor, "¥n  0000    0000  ");
            }
        }
        else if((((ch == 'o') ¦¦ (ch == 'h')) && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4]
== 'n'))
```

```
        ¦¦ (((ch == 'C') ¦¦ (ch == 't')) && (str[5] == 'y') && (str[4] == 'n'))
        ¦¦ ((ch == 's') && (str[5] == 'y') && (str[4] == 'n')))
    {
        for(i = 0; i < 8; i++)
        {
            PrintF(Monitor, "¥n              ");
        }
        for(i = 8; i < 12; i++)
        {
            PrintF(Monitor, "¥n   0000  0000   ");
        }
    }
    else if(((ch == 's') && (str[5] == 'y') && (str[4] == 'y'))
        ¦¦ ((ch == 'h') && (str[5] == 'y') && (str[4] == 'n'))
        ¦¦ (((ch == 'c') ¦¦ (ch == 't')) && (str[5] == 'y') && (str[4] == 'y')))
    {
        for(i = 0; i < 8; i++)
        {
            PrintF(Monitor, "¥n              ");
        }
        for(i = 8; i < 12; i++)
        {
            PrintF(Monitor, "¥n    00000000    ");
        }
    }
}
/* 入力指示 */
DispInput();
```

```
        return;
    }
```

```
/* main.h */

#ifndef Panel_h
#define Panel_h
#include "Panel.h"
#endif

#ifndef Timer_h
#define Timer_h
#include "Timer.h"
#endif

#ifndef EV_Time_h
#define EV_Time_h
#include "EV_Time.h"
#endif

#ifndef EV_File_h
#define EV_File_h
#include "EV_File.h"
#endif

#ifndef EV_UpDown_h
#define EV_UpDown_h
#include "EV_UpDown.h"
#endif

#ifndef EV_OpenClose_h
#define EV_OpenClose_h
#include "EV_OpenClose.h"
#endif

#ifndef EV_Input_h
#define EV_Input_h
#include "EV_Input.h"
#endif

#ifndef EV_Controller_h
#define EV_Controller_h
#include "EV_Controller.h"
#endif

#ifndef EV_Simulator_h
#define EV_Simulator_h
#include "EV_Simulator.h"
#endif

#ifdef USE_THREAD
typedef struct tag_Count
{
#ifndef USE_BCC
	int cnt[2];
#else
	int cnt[8];
#endif
}Count;
#endif
```

```
/* main.c */

#include "C.h"
#include "main.h"

#ifdef USE_THREAD
Count Cnt;
int i_cnt, j_cnt;
#ifndef USE_BCC
/* 擬似スレッドの擬似インスタンス宣言 */
Thread* th[2];
#else
/* 擬似スレッドの擬似インスタンス宣言 */
Thread* th[8];
#endif
/* 疑似スレッドの疑似インスタンス宣言 */
Thread *th1[4];
Thread *th19;
Thread *th20;
Thread *th41;
Thread *th42;
Thread *th43;
#endif
#ifdef NOTUSE_FILES
EV_Status s;
#endif

/*==========================================================================
```

```
 入力オブジェクト宣言
==========================================================================*/
struct EV_Input in;

/*==========================================================================
 制御オブジェクト宣言
==========================================================================*/
struct EV_Controller cntrl;

/*==========================================================================
 シミュレータオブジェクト宣言
==========================================================================*/
struct EV_Simulator simu;

void main(void)
{
#ifndef USE_BCC
    char sw[4];
    int i;
    int j;
    int f;
    int cnt;
    static char buff[64];
#endif
#ifdef USE_THREAD
    Thread *th30;
    Thread *th31;
#endif
#ifndef USE_BCC
```

```
    for(i=0;i<0x7fff;i++) {}
    H8init(); /* H8 レジスタ初期化 */
    InitSCI(); /* SCI1初期化(serial) */
    InitLCD(); /* LCD初期化 */

    /* LED OFF */
    SetLED(0,0);
    SetLED(1,0);
    SetLED(2,0);
    SetLED(3,0);

    /*-------------------------------------------------*/
    /* USB初期化 */
    InitUSB();
    INTC.ISCR &= (-1^0x20);  /* IRQ_5 ｾﾝｽｺﾝﾄﾛｰﾙ Active Low */
    INTC.IER ¦= 0x20; /* IRQ5 Enable */
    /*-------------------------------------------------*/
    EnableInterrupt(); /* 割り込み許可 ccr */

    f = 0;
    PrintSCI("CPU MODE %02X¥n",MDCR); /* MODE 6 */
    PrintLCD("¥fReady!3052"); /* '¥f'はLCDクリアに利用 */

    /* スイッチワーク初期化 */
    sw[0] = sw[1] = sw[2] = sw[3] = 0;
#else
    printf("¥nHello BCC");
#endif
#ifdef NOTUSE_FILES
```

```
    /* ファイル初期化 */
    new_EV_Status(&s);
#endif
#ifdef USE_THREAD
    /* タイマー初期化 */
    initWOVI();
    /* 2秒待機 */
    SleepMSec(2000);
    /* LEDTEST */
    th30 = new_Thread(30);
    th31 = new_Thread(31);
    Start(th30);
    Start(th31);
    for(;;)
    {
        /* タイマー呼び出し */
        wovi(5000000.0);
        if(Thread_checkStayAnother() == 1)
        {
            break;
        }
    }
#endif
    Clear();
#ifdef USE_THREAD
    /* LEDTEST */
    delete_(th30);
#endif
    PrintF(Panel, "NEXT          ");
```

```
    /* 2秒待機 */
    SleepMSec(2000);
    Clear();
#ifndef USE_BCC
    for(;;)
    {
        /*-----------------------------------------------*/
        /* ボタンが押された時にLCD,SCI,USBにメッセージを送る */
        for(j=0;j<4;j++)
        {
            i = GetSW(j);
            if( ((sw[j]^1) & i) ) /* sw = off->onで条件成立 */
            {
                SetLED(j,1); /* LED押した瞬間点灯 */
                sprintf(buff,"sw%u",j+1);
                PrintSCI("%s¥n",buff);
                /* NULL(0x00)まで送信 */
                write_buff(buff,strlen(buff)+1);
                PrintLCD(buff);
            }
            else    SetLED(j,0);
            sw[j] = i;
        }

        /*-----------------------------------------------*/
        /* HOSTからのシリアル入力をLCD,USBに送る */
        if( ScanSCI() ) /* SCIに受信データあり? */
        {
```

```
            i = GetSCI(); /* シリアル入力 */
            PutLCD(i); /* LCD出力 */
            buff[0] = i;
            write_buff(buff,1); /* USB出力 */
        }

        /*-----------------------------------------------*/
        /* USBからデータを受信した場合、そのままHOSTへリダイレクトする  */
        if( get_inbufflen() ) /* 受信データあり? */
        {
            /* データ取得(buffサイズは64byteまで) */
            cnt = read_buff(buff,64);
            PrintLCD("¥f"); /* LCDクリア */
            PrintLCD(buff); /* LCDへ表示 */
            PrintSCI(buff); /* シリアル出力 */
            write_buff(buff,cnt); /* USBへリダイレクト */
        }

        /*-----------------------------------------------*/
        /* 動作確認のため点滅 */
        SetLED(3,f);
        f ^= 1;
        for(i=0;i<10000;i++) {} /* 適当にウエイト */
    }
#else
    printf("END");
    /* 5秒待機 */
    SleepMSec(5000);
    return;
```

```
#endif
}

#ifdef USE_THREAD
/*
 * 擬似スレッドの擬似メソッド関数
 */
 /* public void paint(Graphics g)の代用 */
void Repaint(void)
{
#ifndef USE_BCC
    int i;
#else
    int i,j;
#endif
    Clear();
#ifndef USE_BCC
    for(i = 0; i < Cnt.cnt[0]; i++)
    {
        PrintF(Panel, " ");
    }
    PrintF(Panel, "<1>");
    PrintF(Panel, "¥n");
    for(i = 0; i < Cnt.cnt[1]; i++)
    {
        PrintF(Panel, " ");
    }
    PrintF(Panel, "<2>");
#else
```

```
	for(i = 0; i < 8; i++)
	{
		for(j = 0; j < Cnt.cnt[i]; j++)
		{
			printf(" ");
		}
		printf("<%d>", (i + 1));
		for(j = 0; j < 13 - Cnt.cnt[i]; j++)
		{
			printf(" ");
		}
		printf("¦");
		printf("¥n");
	}
#endif
	return;
}

/*
 * 疑似スレッドの疑似メソッド関数
 */
/* スレッドのpublic void run()の代用 */
void Run(Thread *This)
{
	int i;
	Thread *th11;
#ifdef USE_BCC
	char key = '¥0';
#else
```

```
    int j;
    char sw[4];
    /* スイッチワーク初期化 */
    sw[0] = sw[1] = sw[2] = sw[3] = 0;
#endif
    if(This->ID == 1)
    {
        Repaint();
#ifndef USE_BCC
        Cnt.cnt[0]++;
        nextRun(This, (((rand() % 9) + 10) * 100));
#else
        if(kbhit())
        {
#ifdef USE_LINUX
            key = (char) getchar();
#else
            key = (char) getche();
#endif
        }
        if(key == 'r')
        {
            Cnt.cnt[0]++;
        }
        nextRun(This, (((rand() % 9) + 10) * 30));
        while(kbhit())
        {
#ifdef USE_LINUX
```

```
                key = (char) getchar();
#else
                key = (char) getche();
#endif
            }
#endif
        }
        else if(This->ID == 2)
        {
            Repaint();
#ifndef USE_BCC
            Cnt.cnt[1]++;
            nextRun(This, (((rand() % 9) + 10) * 100));
#else
            if(kbhit())
            {
#ifdef USE_LINUX
                key = (char) getchar();
#else
                key = (char) getche();
#endif
            }
            if(key == 'l')
            {
                Cnt.cnt[1]++;
            }
            nextRun(This, (((rand() % 9) + 10) * 30));
            while(kbhit())
            {
```

```
#ifdef USE_LINUX
                key = (char) getchar();
#else
                key = (char) getche();
#endif
            }
#endif
        }
#ifdef USE_BCC
        else if(((This->ID) >= 3) && ((This->ID) <= 8))
        {
                Repaint();
                Cnt.cnt[(This->ID) - 1]++;
                nextRun(This, (((rand() % 9) + 10) * 200));
        }
#endif
        else if(This->ID == 11)
        {
            if(This->count == 1)
            {
                Clear();
                PrintF(Panel, "<1>1st         ");
                countUpNextRun(This, (1900 * 1));
            }
            else if(This->count == 2)
            {
                Clear();
                PrintF(Panel, "<1>2nd");
                PrintF(Panel, "<1>Stop   ");
```

```
            Stop(This);
        }
        else if(This->count == 3)
        {
            Clear();
            PrintF(Panel, "<1>3rd        ");
            countUpNextRun(This, (1500 * 1));
        }
        else if(This->count == 4)
        {
            Clear();
            PrintF(Panel, "<1>Stop       ");
            Stop(This);
        }
    }
    else if(This->ID == 12)
    {
        if(This->count == 1)
        {
            Clear();
            PrintF(Panel, "<2>1st        ");
            countUpNextRun(This, (1700 * 2));
        }
        else if(This->count == 2)
        {
            Clear();
            PrintF(Panel, "<2>2nd        ");
            countUpNextRun(This, (1700 * 2));
        }
```

```
        else if(This->count == 3)
        {
            Clear();
            PrintF(Panel, "<2>3rd        ");
            countUpNextRun(This, (1700 * 2));
        }
        else
        {
            Clear();
            PrintF(Panel, "<2>Stop");
            Stop(This);
            delete_(This);
        }
    }
    else if(This->ID == 13)
    {
        if(This->count == 1)
        {
            Clear();
            PrintF(Panel, "<3>1st        ");
            countUpNextRun(This, (1700 * 3));
        }
        else if(This->count == 2)
        {
            Clear();
            PrintF(Panel, "<3>2nd        ");
            countUpNextRun(This, (1700 * 3));
        }
```

```
        else if(This->count == 3)
        {
            Clear();
            PrintF(Panel, "<3>3rd         ");
            countUpNextRun(This, (1700 * 3));
        }
        else
        {
            Clear();
            PrintF(Panel, "<3>Stop");
            Stop(This);
            delete_(This);
        }
    }
    else if(This->ID == 14)
    {
        if(This->count == 1)
        {
            Clear();
            PrintF(Panel, "<4>1st         ");
            countUpNextRun(This, (1500 * 4));
        }
        else if(This->count == 2)
        {
            Clear();
            PrintF(Panel, "<4>2nd");
            countUpNextRun(This, (1500 * 4));

            PrintF(Panel, "<1>Start  ");
```

```
            th11 = Thread_Start(11);
            countUpNextRun(th11, (1500 * 1));
        }
        else if(This->count == 3)
        {
            Clear();
            PrintF(Panel, "<4>3rd         ");
            countUpNextRun(This, (1500 * 4));
        }
        else if(This->count == 4)
        {
            th11 = Thread_getThread(11);
            if(th11 != NULL)
            {
                delete_(th11);
            }

            PrintF(Panel, "<4>Sto");
            Stop(This);
            delete_(This);
        }
    }
    else if(This->ID == 19)
    {
#ifdef USE_LINUX
        nextRun(This, 4000);
#else
        nextRun(This, 1);
#endif
```

```
#ifndef USE_BCC
        /* ボタンが押された時にLCD,SCI,USBにメッセージを送る */
        for(j=0;j<4;j++)
        {
            i = GetSW(j);
            if( ((sw[j]^1) & i) ) /* sw = off->onで条件成立 */
            {
                Thread_Toggle(j + 20);
                nextRun(This, 1000);
            }
        }
#else
        key = '¥0';
        key = GetChar(key);

        if(key == '1')
        {
            Thread_Toggle(21);
        }
        else if(key == '2')
        {
            Thread_Toggle(22);
        }
        else if(key == '3')
        {
            Thread_Toggle(23);
        }
        else if(key == '4')
        {
```

```
            Thread_Toggle(24);
        }
        else if(key == '5')
        {
            Thread_Toggle(25);
        }
        else if(key == '6')
        {
            Thread_Toggle(26);
        }
        else if(key == '7')
        {
            Thread_Toggle(27);
        }
        else if(key == '8')
        {
            Thread_Toggle(28);
        }
        else if(key == '9')
        {
            Thread_Toggle(29);
        }
        else if(key == '0')
        {
            Thread_Toggle(20);
        }
#endif
    }
```

```
    else if(This->ID == 20)
    {
        PrintF(Panel, "0");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 21)
    {
        PrintF(Panel, "1");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 22)
    {
        PrintF(Panel, "2");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 23)
    {
        PrintF(Panel, "3");
        countUpNextRun(This, 2000);
    }
#ifdef USE_BCC
    else if((This->ID >= 24) && (This->ID <= 29))
    {
        printf("%d", This->ID - 20);
        nextRun(This, 2000);
    }
#endif
#ifndef USE_BCC
    else if(This->ID == 30)
```

```
    {
        if(This->count == 0)
        {
            This->count++;
            PB.DR &= 0x0e;
            nextRun(This, 1000);
        }
        else if(This->count == 1)
        {
            This->count--;
            PB.DR ¦= 0x01;
            nextRun(This, 1000);
        }
    }
#endif
    else if(This->ID == 31)
    {
        if(This->count == 0)
        {
            /* 第1部分 */
#ifdef USE_BCC
            printf("¥nThread Ready GO! There are 8 cources on a race.");
            printf("¥nThere are 80 cells to a GOAL.");
            printf("¥nFor the <1> cource, You click a 'R' button.");
            printf("¥nFor the <2> cource, You click a 'L' button.");
#endif
#ifndef USE_BCC
            countUpNextRun(This, 0);
#else
```

```
            /* 5秒待機 */
            countUpNextRun(This, 5000);
#endif
        }
        else if(This->count == 1)
        {
            /* 擬似スレッド開始 */
            PrintF(Panel, "¥n");
            PrintF(Panel, "Thread Ready GO!");
            /* 2秒待機 */
            countUpNextRun(This, 2000);
        }
        else if(This->count == 2)
        {
#ifndef USE_BCC
            /* 擬似スレッドの擬似インスタンス初期化 */
            for(i = 0; i < 2; i++)
            {
                th[i] = new_Thread(i + 1);
            }
#else
            /* 擬似スレッドの擬似インスタンス初期化 */
            for(i = 0; i < 8; i++)
            {
                th[i] = new_Thread(i + 1);
            }
#endif
            countUpNextRun(This, 1);
        }
```

```
        else if(This->count == 3)
        {
#ifndef USE_BCC
            if(Cnt.cnt[0] >= 13)
            {
                i_cnt = 1;
                This->count++;
            }
            else if(Cnt.cnt[1] >= 13)
            {
                i_cnt = 2;
                This->count++;
            }
#else
            i_cnt = Cnt.cnt[0];
            j_cnt = 0;
            for(i = 1; i < 8; i++)
            {
                if(i_cnt < Cnt.cnt[i])
                {
                    i_cnt = Cnt.cnt[i];
                    j_cnt = i;
                }
            }
            if(i_cnt >= 13) This->count++;
#endif
            nextRun(This, 1);
        }
```

```
        else if(This->count == 4)
        {
            Clear();
            if(i_cnt == 1)
            {
                PrintF(Panel, "GOAL!<1>WON    ");
            }
            else if(i_cnt == 2)
            {
                PrintF(Panel, "GOAL!<2>WON    ");
            }
#ifdef USE_BCC
            else
            {
                printf("GOAL!¥n<%d>WON", (j_cnt + 1));
            }
#endif
#ifndef USE_BCC
            delete_(th[0]);
            delete_(th[1]);
#else
            for(i = 0; i < 8; i++)
            {
                delete_(th[i]);
            }
#endif
            /* 2秒待機 */
            countUpNextRun(This, 2000);
        }
```

```
else if(This->count == 5)
{
	Clear();
	PrintF(Panel, "NEXT          ");
	/* 2秒待機 */
	countUpNextRun(This, 2000);
}
else if(This->count == 6)
{
	Clear();
	/* 第2部分 */
	PrintF(Panel, "CountUp       ");
	/* 2秒待機 */
	countUpNextRun(This, 2000);
}
else if(This->count == 7)
{
	/* 疑似スレッド開始 */
	Clear();
	/* 疑似スレッドの疑似インスタンス初期化 */
	for(i = 0; i < 4; i++)
	{
		th1[i] = new_Thread(i + 11);
	}
	countUpNextRun(This, 1);
}
else if(This->count == 8)
{
	if(Thread_checkStayAnother() == 2)
```

```
        {
            This->count++;
        }
        nextRun(This, 1);
    }
    else if(This->count == 9)
    {
        /* 2秒待機 */
        countUpNextRun(This, 2000);
    }
    else if(This->count == 10)
    {
        Clear();
        PrintF(Panel, "NEXT          ");
        /* 2秒待機 */
        countUpNextRun(This, 2000);
    }
    else if(This->count == 11)
    {
        Clear();
        /* 第3部分 */
        PrintF(Panel, "Toggle        ");
        /* 2秒待機 */
        countUpNextRun(This, 2000);
    }
    else if(This->count == 12)
    {
        th19 = new_Thread(19);
        Start(th19);
```

```
        th20 = new_Thread(20);
        Start(th20);
        countUpNextRun(This, 1);
    }
    else if(This->count == 13)
    {
        if(Thread_checkStayAnother() == 3)
        {
            delete_(th19);
            This->count++;
        }
        nextRun(This, 1);
    }
    else if(This->count == 14)
    {
        countUpNextRun(This, 2000);
    }
    else if(This->count == 15)
    {
        Clear();
        PrintF(Panel, "NEXT          ");
        /* 2秒待機 */
        countUpNextRun(This, 2000);
    }
    else if(This->count == 16)
    {
        Clear();
        /* 第4部分 */
```

```
            PrintF(Panel, "Hello EV       ");
            /* 2秒待機 */
            countUpNextRun(This, 2000);
        }
        else if(This->count == 17)
        {
            /* 擬似スレッドの擬似インスタンス初期化 */
            th41 = new_Thread(41);
            th42 = new_Thread(42);
            th43 = new_Thread(43);

            delete_(This);
        }
    }
    else if(This->ID == 41)
    {
        nextRun(This, 100);
        OnInput(&in, This);
    }
    else if(This->ID == 42)
    {
        nextRun(This, 100);
        OnController(&cntrl, This);
    }
    else if(This->ID == 43)
    {
        nextRun(This, 2000);
        OnSimulator(&simu, This);
    }
```

```
    return;
}

/* スレッドのコンストラクタのpublic void init()の代用 */
void Init(Thread *This)
{
    if(This->ID == 1)
    {
        Cnt.cnt[0] = 0;
        nextRun(This, (((rand() % 9) + 10) * 30));
    }
    else if(This->ID == 2)
    {
        Cnt.cnt[1] = 0;
        nextRun(This, (((rand() % 9) + 10) * 30));
    }
    else if((This->ID >= 3) && (This->ID <= 8))
    {
        Cnt.cnt[(This->ID) - 1] = 0;
        nextRun(This, (((rand() % 9) + 10) * 200));
    }
    else if(This->ID == 11)
    {
        PrintF(Panel, "<1>Init");
        countUpNextRun(This, (1500 * 1));
    }
    else if(This->ID == 12)
    {
        PrintF(Panel, "<2>Init  ");
```

```
        countUpNextRun(This, (1500 * 2));
    }
    else if(This->ID == 13)
    {
        PrintF(Panel, "¥n");
        PrintF(Panel, "<3>Init");
        countUpNextRun(This, (1500 * 3));
    }
    else if(This->ID == 14)
    {
        PrintF(Panel, "<4>Init  ");
        countUpNextRun(This, (1500 * 4));
    }
    else if(This->ID == 20)
    {
        Clear();
        PrintF(Panel, "<0>Init        ");
        PrintF(Panel, "¥n");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 21)
    {
        Clear();
        PrintF(Panel, "<1>Init        ");
        PrintF(Panel, "¥n");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 22)
    {
```

```
        Clear();
        PrintF(Panel, "<2>Init        ");
        PrintF(Panel, "¥n");
        countUpNextRun(This, 2000);
    }
    else if(This->ID == 23)
    {
        Clear();
        PrintF(Panel, "<3>Init        ");
        PrintF(Panel, "¥n");
        countUpNextRun(This, 2000);
    }
#ifdef USE_BCC
    else if((This->ID >= 24) && (This->ID <= 29))
    {
        printf("¥n<%d>Init¥n", This->ID - 20);
        nextRun(This,2000);
    }
#endif
#ifndef USE_BCC
    else if(This->ID == 30)
    {
        PB.DDR = 0xff; /* bit7..0 out  */
        PB.DR ¦= 0xff;
    }
#endif
    else if(This->ID == 41)
    {
```

```
        nextRun(This, 100);
        EV_Input(&in);
    }
    else if(This->ID == 42)
    {
        nextRun(This, 100);
        EV_Controller(&cntrl, This);
    }
    else if(This->ID == 43)
    {
        nextRun(This, 2000);
        EV_Simulator(&simu, This);
    }
    return;
}

/* スレッドのデストラクタの代用 */
void Destroy(Thread *This)
{
    if(This->ID == 11)
    {
        Clear();
        PrintF(Panel, "<1>Destroy");
    }
    else if(This->ID == 12)
    {
        PrintF(Panel, "<2>Destro");
    }
    else if(This->ID == 13)
```

```
{
	PrintF(Panel, "<3>Destro");
}
else if(This->ID == 14)
{
	PrintF(Panel, "¥n");
	PrintF(Panel, "<4>Destroy	");
}
if(This->ID == 20)
{
	Clear();
	PrintF(Panel, "<0>Destroy	");
	PrintF(Panel, "¥n");
}
else if(This->ID == 21)
{
	Clear();
	PrintF(Panel, "<1>Destroy	");
	PrintF(Panel, "¥n");
}
else if(This->ID == 22)
{
	Clear();
	PrintF(Panel, "<2>Destroy	");
	PrintF(Panel, "¥n");
}
else if(This->ID == 23)
{
	Clear();
```

```
        PrintF(Panel, "<3>Destroy      ");
        PrintF(Panel, "¥n");
    }
#ifdef USE_BCC
    else if((This->ID >= 24) && (This->ID <= 29))
    {
        printf("¥n<%d>Destroy¥n", This->ID - 20);
    }
#endif
    return;
}
#endif

#ifndef USE_BCC
/*=================================================================
                                LEDコントロール
-----------------------------------------------------------------
    int SetLED(int no,int onoff)

    int         no              LEDナンバー 0～3
    int         onoff       0=OFF,1=ON
    戻り値                  以前のLEDの状態     (0=OFF,else=ON)

    LEDをコントロールします。
=================================================================*/
int SetLED(int no,int onoff)
{
    int f;
    f = PB.DR&(1<<no);
```

```
    if( onoff == 0 ) PB.DR ¦= (1<<no); /* off (1) */
    else PB.DR &= 0xff^(1<<no); /* on (0) */
    return( f );
}

/*=====================================================================
                                SW状態取得
---------------------------------------------------------------------
    int GetSW(int no)

    int         no              SWナンバー 0～3
    戻り値                      SWの状態(0=OFF,else=ON)

    SWの状態を取得します。
=====================================================================*/
int GetSW(int no)
{
    return( ((PA.DR&(1<<no))?0:1) );
}

/*=====================================================================
                                H8初期化
---------------------------------------------------------------------
    BUSモードや、ポートの初期化

    P1    bit1  BUS         USB A0
    P3          BUS         USB D7..0
    P6 bit4     BUS         USB RD
```

```
    P6 bit5     BUS         USB WR
    P8 bit2     BUS         USB CS
    P9 bit5     BUS         USB INT(IRQ5)
    P9 bit3     BUS         RS232C
    P9 bit1     BUS         RS232C

    PA bit0..3   IN         SW0..3
    PB bit0..3   OUT         LED0..3  LCD DB4..7
    PB bit4     OUT             LCD RS
    PB bit7     OUT             LCD E
==========================================================================*/
void H8init()
{
    BSC.ABWCR = 0x06; /* 8bit BUS MODE */

    P1.DDR = 0xff; /* all OUT */
    P2.DDR = 0xff; /* all OUT */
    P2.PCR = 0x00; /* Pull up off */
    P5.DDR = 0xff; /* all OUT */
    P5.PCR = 0x00; /* Pull up off */
    P6.DDR = 0xff; /* all OUT */
    P9.DDR = 0xdf; /* Bit5 IN */
    P8.DDR = 0xff; /* all OUT */
    PA.DDR = 0xf0; /* bit7..4 out , bit3..0 in */
    PB.DDR = 0xff; /* bit7..0 out */
}
#endif
```

実行環境

```
-I"c:\borland\Bcc55\include"
-L"c:\borland\Bcc55\lib"
```

-L"c:\borland\Bcc55\Lib"

```
# makefile.mak
CC = bcc32
LL = ilink32
INCLUDE = -I"C:\borland\bcc55\Include"
LIB = -L"C:\borland\bcc55\Lib"
CFLAGS = -O2 -w -tWC -D"USE_BCC"
LFLAGS = /Tpe
TARGET = main.exe
OBJS = Panel.obj Timer.obj EV_Time.obj EV_File.obj EV_UpDown.obj EV_OpenClose.obj EV_Input.obj
EV_Controller.obj EV_Simulator.obj main.obj
$(TARGET): $(OBJS)
	$(LL) $(LFLAGS) $(LIB) \
	$(OBJS) c0x32.obj,$(TARGET),,cw32.lib import32.lib
main.obj : main.c main.h EV_Simulator.h EV_Controller.h EV_Input.h EV_OpenClose.h EV_UpDown.h
EV_File.h EV_Time.h Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c main.c
EV_Simulator.obj : EV_Simulator.c EV_Simulator.h EV_OpenClose.h EV_UpDown.h EV_File.h EV_Time.h
Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c EV_Simulator.c
EV_Controller.obj : EV_Controller.c EV_Controller.h EV_OpenClose.h EV_UpDown.h EV_File.h EV_Time.h
Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c EV_Controller.c
EV_Input.obj : EV_Input.c EV_Input.h EV_OpenClose.h EV_UpDown.h EV_File.h EV_Time.h Timer.h Panel.h
C.h
	$(CC) $(CFLAGS) -c EV_Input.c
EV_OpenClose.obj : EV_OpenClose.c EV_OpenClose.h EV_UpDown.h EV_File.h EV_Time.h Timer.h Panel.h
C.h
	$(CC) $(CFLAGS) -c EV_OpenClose.c
EV_UpDown.obj : EV_UpDown.c EV_UpDown.h EV_File.h EV_Time.h Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c EV_UpDown.c
EV_File.obj : EV_File.c EV_File.h Panel.h C.h
	$(CC) $(CFLAGS) -c EV_File.c
EV_Time.obj : EV_Time.c EV_Time.h Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c EV_Time.c
Timer.obj : Timer.c Timer.h Panel.h C.h
	$(CC) $(CFLAGS) -c Timer.c
Panel.obj : Panel.c Panel.h C.h
	$(CC) $(CFLAGS) -c Panel.c
clean:
	del *.obj
	del main.tds
	del main.ilc
	del main.ild
	del main.ilf
	del main.ils
```

```
; asmfile.src

 .CPU 300HA
 .SECTION V,CODE,LOCATE=H'000000
 .IMPORT _main
 .IMPORT _usb_int
 .IMPORT _InterruptITU0

 .DATA.L _start ;リセットベクトル
;1 Reserved
_INT_Reserved1: .DATA.L int_error
;2 Reserved
_INT_Reserved2: .DATA.L int_error
;3 Reserved
_INT_Reserved3: .DATA.L int_error
;4 Reserved
_INT_Reserved4: .DATA.L int_error
;5 Reserved
_INT_Reserved5: .DATA.L int_error
;6 Reserved
_INT_Reserved6: .DATA.L int_error
;7 NMI
_INT_NMI: .DATA.L int_error
;8 TRAP
_INT_TRAP1: .DATA.L int_error
;9 TRAP
_INT_TRAP2: .DATA.L int_error
;10 TRAP
```

```
_INT_TRAP3: .DATA.L int_error
;11 TRAP
_INT_TRAP4: .DATA.L int_error
;12 IRQ0
IRQ0: .DATA.L int_error
;13 IRQ1
IRQ1: .DATA.L int_error
;14 IRQ2
IRQ2: .DATA.L int_error
;15 IRQ3
IRQ3: .DATA.L int_error
;16 IRQ4
IRQ4: .DATA.L int_error
;17 IRQ5
IRQ5: .DATA.L usb_interrupt ;USB割り込み
;18 Reserved
_INT_Reserved18: .DATA.L int_error
;19 Reserved
_INT_Reserved19: .DATA.L int_error
;20 WOVI
_INT_WOVI: .DATA.L int_error
;21 CMI
_INT_CMI: .DATA.L int_error
;22 Reserved
_INT_Reserved22: .DATA.L int_error
;23 Reserved
_INT_Reserved23: .DATA.L int_error
;24 IMIA0
_INT_IMIA0: .DATA.L int_error
```

```
;25 IMIB0
_INT_IMIB0: .DATA.L int_error
;26 OVI0
_INT_OVI0: .DATA.L _ITU_OVI_0 ;タイマ0割り込み
;27 Reserved
_INT_Reserved27: .DATA.L int_error
;28 IMIA1
_INT_IMIA1: .DATA.L int_error
;29 IMIB1
_INT_IMIB1: .DATA.L int_error
;30 OVI1
_INT_OVI1: .DATA.L int_error
;31 Reserved
_INT_Reserved31: .DATA.L int_error
;32 IMIA2
_INT_IMIA2: .DATA.L int_error
;33 IMIB2
_INT_IMIB2: .DATA.L int_error
;34 OVI2
_INT_OVI2: .DATA.L int_error
;35 Reserved
_INT_Reserved35: .DATA.L int_error
;36 IMIA3
_INT_IMIA3: .DATA.L int_error
;37 IMIB3
_INT_IMIB3: .DATA.L int_error
;38 OVI3
_INT_OVI3: .DATA.L int_error
;39 Reserved
```

```
_INT_Reserved39: .DATA.L int_error
;40 IMIA4
_INT_IMIA4: .DATA.L int_error
;41 IMIB4
_INT_IMIB4: .DATA.L int_error
;42 OVI4
_INT_OVI4: .DATA.L int_error
;43 Reserved
_INT_Reserved43: .DATA.L int_error
;44 DEND0A
_INT_DEND0A: .DATA.L int_error
;45 DEND0B
_INT_DEND0B: .DATA.L int_error
;46 DEND1A
_INT_DEND1A: .DATA.L int_error
;47 DEND1B
_INT_DEND1B: .DATA.L int_error
;48 Reserved
_INT_Reserved48: .DATA.L int_error
;49 Reserved
_INT_Reserved49: .DATA.L int_error
;50 Reserved
_INT_Reserved50: .DATA.L int_error
;51 Reserved
_INT_Reserved51: .DATA.L int_error
;52 ERI0
_INT_ERI0: .DATA.L int_error
;53 RXI0
_INT_RXI0: .DATA.L int_error
```

```
;54 TXI0
_INT_TXI0: .DATA.L int_error
;55 TEI0
_INT_TEI0: .DATA.L int_error
;56 ERI1
_INT_ERI1: .DATA.L int_error
;57 RXI1
_INT_RXI1: .DATA.L int_error
;58 TXI1
_INT_TXI1: .DATA.L int_error
;59 TEI1
_INT_TEI1: .DATA.L int_error
;60 ADI
_INT_ADI: .DATA.L int_error

;------------------------------------------------------
 .SECTION P,CODE,ALIGN=2
_start:
 mov.l #H'0FFFF10,er7

;初期化付きデータを使用する場合、RAMに転送する
 ; c_thread.MAP のメモリアドレス使用状況を見る
 ; メモリアドレスが重複するとコンパイルエラーになる
 ; linkfile.sub も D(99C0), C(9A00) 等必要があれば合わせる
 mov.l #H'99C0, er0 ; 転送元(99C0)
 mov.l #H'0FFE000, er1 ; 転送先
 mov.l #DATA_END, er2 ; 転送終了
init_loop:
```

```
 cmp.l er1, er2
 beq init_end
 mov.b @er0+, r3l
 mov.b r3l, @er1
 inc.l #1, er1
 bra init_loop
init_end:
 jsr @_main

; 割り込み未使用
int_error:
 rte

usb_interrupt:
 push.l er0
 push.l er1
 push.l er2
 push.l er3
 push.l er4
 push.l er5
 push.l er6
 jsr @_usb_int
 pop.l er6
 pop.l er5
 pop.l er4
 pop.l er3
 pop.l er2
 pop.l er1
 pop.l er0
```

```
 rte

_ITU_OVI_0:
 push.l er0
 push.l er1
 push.l er2
 push.l er3
 push.l er4
 push.l er5
 push.l er6
 jsr @_InterruptITU0
 pop.l er6
 pop.l er5
 pop.l er4
 pop.l er3
 pop.l er2
 pop.l er1
 pop.l er0
 rte

;------------------------------------------------------
; 割り込み許可、禁止ルーチン

 .EXPORT _EnableInterrupt,_DisableInterrupt
_EnableInterrupt:
 andc.b #H'3f,ccr
 rts
_DisableInterrupt:
 orc.b #H'c0,ccr
```

```
 rts

;-----------------------------------------------------------
 .SECTION D,DATA

 .SECTION B,DATA
DATA_END: .RES.W 1

 .END
```

```
OUTPUT c_thread
PRINT c_thread
INPUT asmfile, main, EV_Simulator, EV_Controller, EV_Input, EV_OpenClose, EV_UpDown, EV_File,
EV_Time, Timer, Panel, sci, lcd, usb
LIB c:\h8\akic\c38hab
START R(0FFE000), P(200), D(99C0), C(9A00)
ROM (D, R)
EXIT
```

```
@rem build.bat
C:
set bccDir="C:\borland\bcc55\Bin"
set akih8asmDir="c:\h8\akiasm"
set akih8cDir="c:\h8\akic"
set path=%bccDir%;%path%
set path=%akih8cDir%;%akih8asmDir%;%path%
set CurrentDir="%~dp0"
cd %CurrentDir%
del error.txt
make -f makefile.mak >> error.txt
make -f makefile.mak clean >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% Panel.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% Timer.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_Time.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_File.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_UpDown.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_OpenClose.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_Input.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_Controller.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% EV_Simulator.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% main.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% usb.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% sci.c >> error.txt
cc38h -cpu=300ha -include=%akih8cDir% lcd.c >> error.txt
a38h asmfile.src >> error.txt
l38h -subcommand=linkfile.sub >> error.txt
c38h c_thread >> error.txt
del %CurrentDir%*.obj >> error.txt
del %CurrentDir%c_thread.abs >> error.txt
error.txt
exit
```

```
#!/bin/bash
cd `dirname $0`
find $PWD -name linuxBuild.bash
rm ./linuxError.txt
gcc -D"USE_LINUX" -o linuxExe main.c EV_Simulator.c EV_Controller.c EV_Input.c EV_OpenClose.c
EV_UpDown.c EV_File.c EV_Time.c Timer.c Panel.c &>>./linuxError.txt
exit
```

```
#!/bin/bash
cd `dirname $0`
find $PWD -name linuxStart.bash
./linuxExe
exit
```

実行環境状態ファイル

r

yynnyynn

q

C

N

S

出力ファイル

```
 Start         Length     Name                   Class
0001:00401000 00000FED0H _TEXT                  CODE
0002:00411000 000003754H _DATA                  DATA
0003:00414754 000000B50H _BSS                   BSS
0004:00000000 0000000A4H _TLS                   TLS
```

```
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***     03/11/18 15:11:13
PAGE    1
PROGRAM NAME =


  1                   1    ; asmfile.src
  2                   2
  3                   3     .CPU 300HA
  4 000000            4     .SECTION V,CODE,LOCATE=H'000000
  5                   5     .IMPORT _main
  6                   6     .IMPORT _usb_int
  7                   7     .IMPORT _InterruptITU0
  8                   8
  9 000000 00000000   9     .DATA.L _start ;リセットベクトル
 10                  10    ;1 Reserved
 11 000004 00000000  11     _INT_Reserved1: .DATA.L int_error
 12                  12    ;2 Reserved
 13 000008 00000000  13     _INT_Reserved2: .DATA.L int_error
 14                  14    ;3 Reserved
 15 00000C 00000000  15     _INT_Reserved3: .DATA.L int_error
 16                  16    ;4 Reserved
 17 000010 00000000  17     _INT_Reserved4: .DATA.L int_error
 18                  18    ;5 Reserved
 19 000014 00000000  19     _INT_Reserved5: .DATA.L int_error
 20                  20    ;6 Reserved
 21 000018 00000000  21     _INT_Reserved6: .DATA.L int_error
 22                  22    ;7 NMI
 23 00001C 00000000  23     _INT_NMI: .DATA.L int_error
 24                  24    ;8 TRAP
```

```
25 000020 00000000          25    _INT_TRAP1: .DATA.L int_error
26                          26    ;9 TRAP
27 000024 00000000          27    _INT_TRAP2: .DATA.L int_error
28                          28    ;10 TRAP
29 000028 00000000          29    _INT_TRAP3: .DATA.L int_error
30                          30    ;11 TRAP
31 00002C 00000000          31    _INT_TRAP4: .DATA.L int_error
32                          32    ;12 IRQ0
33 000030 00000000          33    IRQ0: .DATA.L int_error
34                          34    ;13 IRQ1
35 000034 00000000          35    IRQ1: .DATA.L int_error
36                          36    ;14 IRQ2
37 000038 00000000          37    IRQ2: .DATA.L int_error
38                          38    ;15 IRQ3
39 00003C 00000000          39    IRQ3: .DATA.L int_error
40                          40    ;16 IRQ4
41 000040 00000000          41    IRQ4: .DATA.L int_error
42                          42    ;17 IRQ5
43 000044 00000000          43    IRQ5: .DATA.L usb_interrupt ;USB割り込み
44                          44    ;18 Reserved
45 000048 00000000          45    _INT_Reserved18: .DATA.L int_error
46                          46    ;19 Reserved
47 00004C 00000000          47    _INT_Reserved19: .DATA.L int_error
48                          48    ;20 WOVI
49 000050 00000000          49    _INT_WOVI: .DATA.L int_error
50                          50    ;21 CMI
51 000054 00000000          51    _INT_CMI: .DATA.L int_error
52                          52    ;22 Reserved
53 000058 00000000          53    _INT_Reserved22: .DATA.L int_error
```

```
  54                    54    ;23 Reserved
  55 00005C 00000000          55    _INT_Reserved23: .DATA.L int_error
  56                    56    ;24 IMIA0
  57 000060 00000000          57    _INT_IMIA0: .DATA.L int_error
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***     03/11/18 15:11:13
PAGE    2
PROGRAM NAME =


  58                    58    ;25 IMIB0
  59 000064 00000000          59    _INT_IMIB0: .DATA.L int_error
  60                    60    ;26 OVI0
  61 000068 00000000          61    _INT_OVI0: .DATA.L _ITU_OVI_0 ;タイマ0割り込み
  62                    62    ;27 Reserved
  63 00006C 00000000          63    _INT_Reserved27: .DATA.L int_error
  64                    64    ;28 IMIA1
  65 000070 00000000          65    _INT_IMIA1: .DATA.L int_error
  66                    66    ;29 IMIB1
  67 000074 00000000          67    _INT_IMIB1: .DATA.L int_error
  68                    68    ;30 OVI1
  69 000078 00000000          69    _INT_OVI1: .DATA.L int_error
  70                    70    ;31 Reserved
  71 00007C 00000000          71    _INT_Reserved31: .DATA.L int_error
  72                    72    ;32 IMIA2
  73 000080 00000000          73    _INT_IMIA2: .DATA.L int_error
  74                    74    ;33 IMIB2
  75 000084 00000000          75    _INT_IMIB2: .DATA.L int_error
  76                    76    ;34 OVI2
  77 000088 00000000          77    _INT_OVI2: .DATA.L int_error
  78                    78    ;35 Reserved
```

```
 79 00008C 00000000          79    _INT_Reserved35: .DATA.L int_error
 80                          80    ;36 IMIA3
 81 000090 00000000          81    _INT_IMIA3: .DATA.L int_error
 82                          82    ;37 IMIB3
 83 000094 00000000          83    _INT_IMIB3: .DATA.L int_error
 84                          84    ;38 OVI3
 85 000098 00000000          85    _INT_OVI3: .DATA.L int_error
 86                          86    ;39 Reserved
 87 00009C 00000000          87    _INT_Reserved39: .DATA.L int_error
 88                          88    ;40 IMIA4
 89 0000A0 00000000          89    _INT_IMIA4: .DATA.L int_error
 90                          90    ;41 IMIB4
 91 0000A4 00000000          91    _INT_IMIB4: .DATA.L int_error
 92                          92    ;42 OVI4
 93 0000A8 00000000          93    _INT_OVI4: .DATA.L int_error
 94                          94    ;43 Reserved
 95 0000AC 00000000          95    _INT_Reserved43: .DATA.L int_error
 96                          96    ;44 DEND0A
 97 0000B0 00000000          97    _INT_DEND0A: .DATA.L int_error
 98                          98    ;45 DEND0B
 99 0000B4 00000000          99    _INT_DEND0B: .DATA.L int_error
100                         100    ;46 DEND1A
101 0000B8 00000000         101    _INT_DEND1A: .DATA.L int_error
102                         102    ;47 DEND1B
103 0000BC 00000000         103    _INT_DEND1B: .DATA.L int_error
104                         104    ;48 Reserved
105 0000C0 00000000         105    _INT_Reserved48: .DATA.L int_error
106                         106    ;49 Reserved
107 0000C4 00000000         107    _INT_Reserved49: .DATA.L int_error
```

```
 108                    108    ;50 Reserved
 109 0000C8 00000000        109    _INT_Reserved50: .DATA.L int_error
 110                    110    ;51 Reserved
 111 0000CC 00000000        111    _INT_Reserved51: .DATA.L int_error
 112                    112    ;52 ERI0
 113 0000D0 00000000        113    _INT_ERI0: .DATA.L int_error
 114                    114    ;53 RXI0
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***     03/11/18 15:11:13
PAGE    3
PROGRAM NAME =

 115 0000D4 00000000        115    _INT_RXI0: .DATA.L int_error
 116                    116    ;54 TXI0
 117 0000D8 00000000        117    _INT_TXI0: .DATA.L int_error
 118                    118    ;55 TEI0
 119 0000DC 00000000        119    _INT_TEI0: .DATA.L int_error
 120                    120    ;56 ERI1
 121 0000E0 00000000        121    _INT_ERI1: .DATA.L int_error
 122                    122    ;57 RXI1
 123 0000E4 00000000        123    _INT_RXI1: .DATA.L int_error
 124                    124    ;58 TXI1
 125 0000E8 00000000        125    _INT_TXI1: .DATA.L int_error
 126                    126    ;59 TEI1
 127 0000EC 00000000        127    _INT_TEI1: .DATA.L int_error
 128                    128    ;60 ADI
 129 0000F0 00000000        129    _INT_ADI: .DATA.L int_error
 130                    130
 131                    131    ;------------------------------------------------------
```

```
132 000000                132     .SECTION P,CODE,ALIGN=2
133 000000                133     _start:
134 000000 7A0700FFFF10       134     mov.l #H'0FFFF10,er7
135                       135
136                       136     ;初期化付きデータを使用する場合、RAMに転送する
137                       137     ; c_thread.MAP のメモリアドレス使用状況を見る
138                       138     ; メモリアドレスが重複するとコンパイルエラーになる
139                       139     ; linkfile.sub も D(99C0), C(9A00) 等必要があれば合わせる
140 000006 7A00000099C0        140     mov.l #H'99C0, er0 ; 転送元(99C0)
141 00000C 7A0100FFE000      141     mov.l #H'0FFE000, er1 ; 転送先
142 000012 7A0200000000      142     mov.l #DATA_END, er2 ; 転送終了
143 000018                143     init_loop:
144 000018 1F92           144     cmp.l er1, er2
145 00001A 58700008           145     beq init_end
146 00001E 6C0B           146     mov.b @er0+, r3l
147 000020 689B           147     mov.b r3l, @er1
148 000022 0B71           148     inc.l #1, er1
149 000024 40F2           149     bra init_loop
150 000026                150     init_end:
151 000026 5E000000           151     jsr @_main
152                       152
153                       153     ; 割り込み未使用
154 00002A                154     int_error:
155 00002A 5670           155     rte
156                       156
157 00002C                157     usb_interrupt:
158 00002C 01006DF0           158     push.l er0
159 000030 01006DF1           159     push.l er1
160 000034 01006DF2           160     push.l er2
```

```
  161 000038 01006DF3          161     push.l er3
  162 00003C 01006DF4          162     push.l er4
  163 000040 01006DF5          163     push.l er5
  164 000044 01006DF6          164     push.l er6
  165 000048 5E000000          165     jsr @_usb_int
  166 00004C 01006D76          166     pop.l er6
  167 000050 01006D75          167     pop.l er5
  168 000054 01006D74          168     pop.l er4
  169 000058 01006D73          169     pop.l er3
  170 00005C 01006D72          170     pop.l er2
  171 000060 01006D71          171     pop.l er1
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***     03/11/18 15:11:13
PAGE    4
PROGRAM NAME =


  172 000064 01006D70          172     pop.l er0
  173 000068 5670              173     rte
  174                          174
  175 00006A                   175     _ITU_OVI_0:
  176 00006A 01006DF0          176     push.l er0
  177 00006E 01006DF1          177     push.l er1
  178 000072 01006DF2          178     push.l er2
  179 000076 01006DF3          179     push.l er3
  180 00007A 01006DF4          180     push.l er4
  181 00007E 01006DF5          181     push.l er5
  182 000082 01006DF6          182     push.l er6
  183 000086 5E000000          183     jsr @_InterruptITU0
  184 00008A 01006D76          184     pop.l er6
  185 00008E 01006D75          185     pop.l er5
```

```
186 000092 01006D74          186     pop.l er4
187 000096 01006D73          187     pop.l er3
188 00009A 01006D72          188     pop.l er2
189 00009E 01006D71          189     pop.l er1
190 0000A2 01006D70          190     pop.l er0
191 0000A6 5670              191     rte
192                  192
193                  193    ;---------------------------------------------------------
194                  194    ; 割り込み許可、禁止ルーチン
195                  195
196                  196     .EXPORT _EnableInterrupt,_DisableInterrupt
197 0000A8               197    _EnableInterrupt:
198 0000A8 063F          198     andc.b #H'3f,ccr
199 0000AA 5470          199     rts
200 0000AC               200    _DisableInterrupt:
201 0000AC 04C0          201     orc.b #H'c0,ccr
202 0000AE 5470          202     rts
203                  203
204                  204    ;---------------------------------------------------------
205 000000               205     .SECTION D,DATA
206                  206
207 000000               207     .SECTION B,DATA
208 000000 00000002         208    DATA_END: .RES.W 1
209                  209
210                  210     .END
*****TOTAL ERRORS      0
*****TOTAL WARNINGS    0
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***     03/11/18 15:11:13
PAGE    5
```

*** CROSS REFERENCE LIST

NAME SECTION ATTR VALUE SEQUENCE

B B SCT 00000000 207*

D D SCT 00000000 205*

DATA_END B 00000000 142 208*

IRQ0 V 00000030 33*

IRQ1 V 00000034 35*

IRQ2 V 00000038 37*

IRQ3 V 0000003C 39*

IRQ4 V 00000040 41*

IRQ5 V 00000044 43*

P P SCT 00000000 132*

V V SCT 00000000 4*

_DisableInterrupt P EXPT 000000AC 196 200*

_EnableInterrupt P EXPT 000000A8 196 197*

_INT_ADI V 000000F0 129*

_INT_CMI V 00000054 51*

_INT_DEND0A V 000000B0 97*

_INT_DEND0B V 000000B4 99*

_INT_DEND1A V 000000B8 101*

_INT_DEND1B V 000000BC 103*

_INT_ERI0 V 000000D0 113*

_INT_ERI1 V 000000E0 121*

_INT_IMIA0 V 00000060 57*

_INT_IMIA1 V 00000070 65*

_INT_IMIA2 V 00000080 73*

_INT_IMIA3 V 00000090 81*

_INT_IMIA4 V 000000A0 89*

_INT_IMIB0 V 00000064 59*

_INT_IMIB1 V 00000074 67*

_INT_IMIB2 V 00000084 75*

_INT_IMIB3 V 00000094 83*

_INT_IMIB4 V 000000A4 91*

_INT_NMI V 0000001C 23*

_INT_OVI0 V 00000068 61*

_INT_OVI1 V 00000078 69*

_INT_OVI2 V 00000088 77*

_INT_OVI3 V 00000098 85*

_INT_OVI4 V 000000A8 93*

_INT_RXI0 V 000000D4 115*

_INT_RXI1 V 000000E4 123*

_INT_Reserved1 V 00000004 11*

_INT_Reserved18 V 00000048 45*

_INT_Reserved19 V 0000004C 47*

_INT_Reserved2 V 00000008 13*

_INT_Reserved22 V 00000058 53*

_INT_Reserved23 V 0000005C 55*

_INT_Reserved27 V 0000006C 63*

_INT_Reserved3 V 0000000C 15*

_INT_Reserved31 V 0000007C 71*

_INT_Reserved35 V 0000008C 79*

_INT_Reserved39 V 0000009C 87*

_INT_Reserved4 V 00000010 17*

_INT_Reserved43 V 000000AC 95*

_INT_Reserved48 V 000000C0 105*

_INT_Reserved49 V 000000C4 107*

*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 *** 03/11/18 15:11:13

PAGE 6

*** CROSS REFERENCE LIST

NAME SECTION ATTR VALUE SEQUENCE

_INT_Reserved5 V 00000014 19*

_INT_Reserved50 V 000000C8 109*

_INT_Reserved51 V 000000CC 111*

_INT_Reserved6 V 00000018 21*

_INT_TEI0 V 000000DC 119*

_INT_TEI1 V 000000EC 127*

_INT_TRAP1 V 00000020 25*

_INT_TRAP2 V 00000024 27*

_INT_TRAP3 V 00000028 29*

_INT_TRAP4 V 0000002C 31*

_INT_TXI0 V 000000D8 117*

_INT_TXI1 V 000000E8 125*

_INT_WOVI V 00000050 49*

_ITU_OVI_0 P 0000006A 61 175*

_InterruptITU0 IMPT 00000000 7 183

_main IMPT 00000000 5 151

_start P 00000000 9 133*

_usb_int IMPT 00000000 6 165

init_end P 00000026 145 150*

init_loop P 00000018 143* 149

```
int_error               P       0000002A   11   13   15   17   19   21   23   25   27   29   31   33
                                   35   37   39   41   45   47   49   51   53   55   57   59
                                   63   65   67   69   71   73   75   77   79   81   83   85
                                   87   89   91   93   95   97   99  101  103  105  107  109
                                  111  113  115  117  119  121  123  125  127  129  154*
usb_interrupt           P       0000002C   43  157*
*** H8/300H ASSEMBLER (Evaluation software) Ver.1.0 ***    03/11/18 15:11:13
PAGE    7

*** SECTION DATA LIST

SECTION                 ATTRIBUTE   SIZE        START

V                       ABS-CODE    00000F4     000000
P                       REL-CODE    00000B0
D                       REL-DATA    0000000
B                       REL-DATA    0000002
```

S00E0000635F7468726561644D4F54C8
S1130000000002000000022A0000022A0000022A67
S1130010000022A0000022A0000022A0000022A2D
S1130020000022A0000022A0000022A0000022A1D
S10B00300000022A0000022A6D
S1130038000022A0000022A0000022A0000022C03
S1130048000022A0000022A0000022A0000022AF5
S1130058000022A0000022A0000022A0000022AE5
S10B00680000026A0000022AF5
S1130070000022A0000022A0000022A0000022ACD
S1130080000022A0000022A0000022A0000022ABD
S1130090000022A0000022A0000022A0000022AAD
S10B00A00000022A0000022AFD
S11300A80000022A0000022A0000022A0000022A95
S11300B80000022A0000022A0000022A0000022A85
S11300C80000022A0000022A0000022A0000022A75
S10B00D80000022A0000022AC5
S11300E00000022A0000022A0000022A0000022A5D
S10700F00000022ADD
S11302007A0700FFFF107A00000099C07A0100FF0F
S1130210E0007A0200FFE0101F92587000086C0B98
S1130220689B0B7140F25E0002B0567001006DF0E6
S113023001006DF101006DF201006DF301006DF439
S113024001006DF501006DF65E00527401006D76DC
S113025001006D7501006D7401006D7301006D7215
S113026001006D7101006D70567001006DF00100A9
S11302706DF101006DF201006DF301006DF40100F9
S11302806DF501006DF65E004C5401006D760100C2
S11302906D7501006D7401006D7301006D720100D5
S11302A06D7101006D705670063F547004C0547038
S11302B05E00638A7A370000000A790B0001193364
S11302C00FF47A0600FFE1C819550B5579257FFF16
S11302D04DF85C000F6A5E004DF05E004F700D3804
S11302E00D305C000EE60D380DB05C000EDE0D38EF
S11302F0790000025C000ED40D38790000035C0025
S11303000ECA5E0051167FF472507FF570505E0086
S113031002A80D3228F117506DF07A0000009A0000
S113032001006DF05E004E400B970B877A000000D2
S11303309A0F01006DF05E0050440B9718886EC849
S113034000036EC800026EC8000168C87A0000FF8F
S1130350E0465E0041FA5E004C807A00000007D060
S11303605E0047587900001E5E00484E0F857900F5
S1130370001F5E00484E01006FF000040FD05E00C6
S11303804A0A01006F7000045E004A0A01006B20F4
S113039000009C8A01006DF001006B2000009C8628
S11303A001006DF05E004C7C0B970B975E004A706A
S11303B07920000146D65E004C9A0FD05E0049D6E4
S11303C07A0100009A1B0D305E004CC27A000000D7
S11303D007D05E0047585E004C9A19550D505C00DB
S11303E00E380D0D0D5117F10AC16819D90117D136
S11303F0660147540DB80D505C000DD00D5009B087
S11304006DF07A0000009A2C01006DF00FE05E00A1
S11304105C2C0B970B8701006DF67A0000009A3174
S113042001006DF05E004E400B970B970FE05E00EE
S11304305CD009B00D010FE05E005AA801006DF613
S11304405E0050440B9740080D380D505C000D7C46
S11304500DD017F50FC10AD168980B557925000403

S108046058D0FF785E97
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H8/300H LINKAGE EDITOR (Evaluation software) Ver.1.0

LINK COMMAND LINE

LNK -subcommand=linkfile.sub

LINK SUBCOMMANDS

```
OUTPUT c_thread
PRINT c_thread
INPUT asmfile, main, EV_Simulator, EV_Controller, EV_Input, EV_OpenClose, EV_UpDown, EV_File,
EV_Time, Timer, Panel, sci, lcd, usb
LIB c:\h8\akic\c38hab
START R(0FFE000), P(200), D(99C0), C(9A00)
ROM (D, R)
EXIT
```


*** LINKAGE EDITOR LINK MAP LIST ***

SECTION	NAME	START	-	END	LENGTH	UNIT NAME	MODULE NAME
ATTRIBUTE : CODE NOSHR							
V		H'00000000	-	H'000000F3	H'000000F4	asmfile	asmfile
* TOTAL ADDRESS *		H'00000000	-	H'000000F3	H'000000F4		
ATTRIBUTE : CODE NOSHR							
P		H'00000200	-	H'000002AF	H'000000B0	asmfile	asmfile
		H'000002B0	-	H'0000126B	H'00000FBC	main	main
		H'0000126C	-	H'00001E8F	H'00000C24	EV_Simulator	EV_Simulator
		H'00001E90	-	H'0000280B	H'0000097C	EV_Controller	EV_Controller
		H'0000280C	-	H'00003149	H'0000093E	EV_Input	EV_Input
		H'0000314A	-	H'000039B1	H'00000868	EV_OpenClose	EV_OpenClose
		H'000039B2	-	H'000041F9	H'00000848	EV_UpDown	EV_UpDown

```
                H'000041FA   -   H'000045ED   H'000003F4
                                 EV_File                 EV_File
                H'000045EE   -   H'00004745   H'00000158
                                 EV_Time                 EV_Time
                H'00004746   -   H'00004C99   H'00000554
                                 Timer                   Timer
                H'00004C9A   -   H'00004DEF   H'00000156
                                 Panel                   Panel
                H'00004DF0   -   H'00004EC1   H'000000D2
                                 sci                     sci
                H'00004EC2   -   H'000050FF   H'0000023E
                                 lcd                     lcd
                H'00005100   -   H'00005BF1   H'00000AF2
                                 usb                     usb
                H'00005BF2   -   H'00005C2B   H'0000003A
                                 rand                    rand
                H'00005C2C   -   H'00005C89   H'0000005E
                                 sprintf                 sprintf
                H'00005C8A   -   H'00005CB3   H'0000002A
                                 strcmp                  strcmp
                H'00005CB4   -   H'00005CCF   H'0000001C
                                 strcpy                  strcpy
                H'00005CD0   -   H'00005CEB   H'0000001C
                                 strlen                  strlen



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                   ***    LINKAGE EDITOR LINK MAP LIST     ***


SECTION   NAME                START    -    END       LENGTH
                                 UNIT NAME                MODULE NAME


ATTRIBUTE :   CODE  NOSHR

P                  H'00005CEC   -   H'00005D1B   H'00000030
                                 vsprintf                vsprintf
                H'00005D1C   -   H'00005FF5   H'000002DA
                                 addd3                   addd3
                H'00005FF6   -   H'00006227   H'00000232
                                 divd3                   divd3
                H'00006228   -   H'000062A1   H'0000007A
                                 dtol3                   dtol3
                H'000062A2   -   H'000062AD   H'0000000C
                                 eqd3                    eqd3
                H'000062AE   -   H'000062BD   H'00000010
                                 ged3                    ged3
                H'000062BE   -   H'000062CD   H'00000010
                                 ltd3                    ltd3
                H'000062CE   -   H'00006313   H'00000046
                                 ltod3                   ltod3
                H'00006314   -   H'00006331   H'0000001E
                                 mv83                    mv83
                H'00006332   -   H'00006359   H'00000028
```

```
                    mvn3                    mvn3
               H'0000635A   -   H'00006367   H'0000000E
                    ned3                    ned3
               H'00006368   -   H'00006389   H'00000022
                    spregld3                spregld3
               H'0000638A   -   H'000063B1   H'00000028
                    spregsv3                spregsv3
               H'000063B2   -   H'0000815F   H'00001DAE
                    _fmtout                 _fmtout
               H'00008160   -   H'0000821B   H'000000BC
                    cmpd3                   cmpd3
               H'0000821C   -   H'00008241   H'00000026
                    divl3                   divl3
               H'00008242   -   H'00008261   H'00000020
                    mull3                   mull3
               H'00008262   -   H'00008647   H'000003E6
                    _dti                    _dti
               H'00008648   -   H'000087EB   H'000001A4
                    _its                    _its
               H'000087EC   -   H'00008845   H'0000005A
                    memcpy                  memcpy
               H'00008846   -   H'00008881   H'0000003C
                    divul3                  divul3
               H'00008882   -   H'000088A9   H'00000028
                    _allzero                _allzero
               H'000088AA   -   H'000089A1   H'000000F8
                    _calcnpw                _calcnpw


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                  ***    LINKAGE EDITOR LINK MAP LIST     ***


SECTION   NAME              START    -    END      LENGTH
                              UNIT NAME              MODULE NAME


ATTRIBUTE :  CODE  NOSHR

P                H'000089A2   -   H'00008A45   H'000000A4
                    _log10                  _log10
               H'00008A46   -   H'00008ABD   H'00000078
                    _lsfts                  _lsfts
               H'00008ABE   -   H'00008AEB   H'0000002E
                    _pow5                   _pow5
               H'00008AEC   -   H'00008B65   H'0000007A
                    _rsfts                  _rsfts
               H'00008B66   -   H'00008C11   H'000000AC
                    _sub                    _sub
               H'00008C12   -   H'00008CB5   H'000000A4
                    _unpack                 _unpack
               H'00008CB6   -   H'00008CF3   H'0000003E
                    memcmp                  memcmp
               H'00008CF4   -   H'00008D7B   H'00000088
                    _mult64                 _mult64
```

```
                H'00008D7C   -   H'00008EDD   H'00000162
                                 _power                  _power
                H'00008EDE   -   H'00008FC7   H'000000EA
                                 _rnd                    _rnd
                H'00008FC8   -   H'00009063   H'0000009C
                                 _setsbit                _setsbit
                H'00009064   -   H'00009169   H'00000106
                                 frexp                   frexp
                H'0000916A   -   H'0000929F   H'00000136
                                 modf                    modf
                H'000092A0   -   H'000092C1   H'00000022
                                 dslc3                   dslc3
                H'000092C2   -   H'000092E3   H'00000022
                                 dsruc3                  dsruc3
                H'000092E4   -   H'00009319   H'00000036
                                 itod3                   itod3
                H'0000931A   -   H'00009607   H'000002EE
                                 muld3                   muld3
                H'00009608   -   H'00009659   H'00000052
                                 _duchek                 _duchek
                H'0000965A   -   H'000096AB   H'00000052
                                 _lsft                   _lsft
                H'000096AC   -   H'00009839   H'0000018E
                                 _mult                   _mult
                H'0000983A   -   H'000098D5   H'0000009C
                                 _pow10                  _pow10
                H'000098D6   -   H'0000991D   H'00000048
                                 _add                    _add
                H'0000991E   -   H'0000994D   H'00000030
                                 memset                  memset


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                   ***    LINKAGE EDITOR LINK MAP LIST     ***


SECTION   NAME              START    -    END      LENGTH
                                UNIT NAME                MODULE NAME

* TOTAL ADDRESS *           H'00000200   -   H'0000994D   H'0000974E


ATTRIBUTE :   DATA  NOSHR ROM

D                H'000099C0   -   H'000099C0   H'00000000
                                 asmfile                 asmfile
                H'000099C0   -   H'000099CF   H'00000010
                                 usb                     usb

* TOTAL ADDRESS *           H'000099C0   -   H'000099CF   H'00000010


ATTRIBUTE :   DATA  NOSHR

C                H'00009A00   -   H'00009C8D   H'0000028E
```

```
                    main                    main
          H'00009C8E  -  H'00009DE8  H'0000015B
                    EV_Simulator            EV_Simulator
          H'00009DEA  -  H'00009E11  H'00000028
                    EV_Controller           EV_Controller
          H'00009E12  -  H'00009E77  H'00000066
                    EV_Input                EV_Input
          H'00009E78  -  H'00009EC3  H'0000004C
                    EV_OpenClose            EV_OpenClose
          H'00009EC4  -  H'00009F06  H'00000043
                    EV_UpDown               EV_UpDown
          H'00009F08  -  H'00009F79  H'00000072
                    EV_File                 EV_File
          H'00009F7A  -  H'00009F81  H'00000008
                    EV_Time                 EV_Time
          H'00009F82  -  H'00009FB9  H'00000038
                    Timer                   Timer
          H'00009FBA  -  H'00009FC4  H'0000000B
                    Panel                   Panel
          H'00009FC6  -  H'0000A07F  H'000000BA
                    usb                     usb
          H'0000A080  -  H'0000A087  H'00000008
                    _fmtout                 _fmtout
          H'0000A088  -  H'0000A187  H'00000100
                    _ctype                  _ctype
          H'0000A188  -  H'0000A20F  H'00000088
                    _its                    _its
          H'0000A210  -  H'0000A217  H'00000008
                    _log10                  _log10
          H'0000A218  -  H'0000A2F7  H'000000E0
                    _pow5                   _pow5
          H'0000A2F8  -  H'0000A3FB  H'00000104
                    _power                  _power


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             ***    LINKAGE EDITOR LINK MAP LIST     ***


SECTION   NAME              START    -    END      LENGTH
                    UNIT NAME               MODULE NAME


ATTRIBUTE :  DATA  NOSHR

C                   H'0000A3FC  -  H'0000A403  H'00000008
                    frexp                   frexp
          H'0000A404  -  H'0000A40B  H'00000008
                    modf                    modf

* TOTAL ADDRESS *          H'00009A00  -  H'0000A40B  H'00000A0C


ATTRIBUTE :  DATA  NOSHR RAM
```

```
R                   H'00FFE000   -   H'00FFE000   H'00000000
                                    asmfile                 asmfile
                    H'00FFE000   -   H'00FFE00F   H'00000010
                                    usb                     usb

* TOTAL ADDRESS *           H'00FFE000   -   H'00FFE00F   H'00000010


ATTRIBUTE :  DATA  NOSHR

B                   H'00FFE010   -   H'00FFE011   H'00000002
                                    asmfile                 asmfile
                    H'00FFE012   -   H'00FFE207   H'000001F6
                                    main                    main
                    H'00FFE208   -   H'00FFE21B   H'00000014
                                    EV_File                 EV_File
                    H'00FFE21C   -   H'00FFE43F   H'00000224
                                    Timer                   Timer
                    H'00FFE440   -   H'00FFE4BF   H'00000080
                                    Panel                   Panel
                    H'00FFE4C0   -   H'00FFE50F   H'00000050
                                    sci                     sci
                    H'00FFE510   -   H'00FFE54F   H'00000040
                                    lcd                     lcd
                    H'00FFE550   -   H'00FFE823   H'000002D4
                                    usb                     usb
                    H'00FFE824   -   H'00FFE85F   H'0000003C
                                    _fmtout                 _fmtout
                    H'00FFE860   -   H'00FFE863   H'00000004
                                    _rnext                  _rnext
                    H'00FFE864   -   H'00FFE865   H'00000002
                                    _errno                  _errno

* TOTAL ADDRESS *           H'00FFE010   -   H'00FFE865   H'00000856


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                      ***  LINKAGE EDITOR EXTERNALLY DEFINED SYMBOLS LIST  ***

                    SYMBOL  NAME                ADDR            TYPE

                    $ADDD$3                     H'00005DE6      DAT
                    $CMPD$3                     H'00008160      DAT
                    $DIVD$3                     H'00006090      DAT
                    $DIVL$3                     H'0000821C      DAT
                    $DIVUL$3                    H'00008846      DAT
                    $DSLC$3                     H'000092A0      DAT
                    $DSRUC$3                    H'000092C2      DAT
                    $DTOL$3                     H'00006228      DAT
                    $EQD$3                      H'000062A2      DAT
                    $GED$3                      H'000062AE      DAT
                    $ITOD$3                     H'000092E4      DAT
                    $LTD$3                      H'000062BE      DAT
                    $LTOD$3                     H'000062CE      DAT
                    $MULD$3                     H'000093D0      DAT
```

$MULL$3 H'00008242 DAT
$MV8$3 H'00006314 DAT
MVN3 H'00006332 DAT
NED3 H'0000635A DAT
$SUBD$3 H'00005DB6 DAT
sp_regld3 H'00006368 DAT
sp_regsv3 H'0000638A DAT
_Checkfmove H'00004708 ENT
_Clear H'00004C9A ENT
_ClearLCD H'00004FE0 ENT
_Close H'0000396A ENT
_CloseMotor H'0000341E ENT
_Cnt H'00FFE012 DAT
_Command_Read H'00004404 ENT
_Command_Write H'00004450 ENT
_Destroy H'000010D6 ENT
_DisableInterrupt H'000002AC DAT
_Disp H'0000177A ENT
_DispInput H'0000172A ENT
_DispUSBPort H'00005210 ENT
_Door H'0000314A ENT
_Down H'000041B2 ENT
_DownMotor H'00003C86 ENT
_EV_Controller H'00001E90 ENT
_EV_File H'0000424E ENT
_EV_Input H'00002878 ENT
_EV_Simulator H'0000126C ENT
_EV_Time H'000045EE ENT
_EnableInterrupt H'000002A8 DAT
_GetChar H'0000280C ENT
_GetCurrentTime H'00004650 ENT
_GetPermit H'000046EA ENT
_GetSCI H'00004E20 ENT
_GetSW H'0000121A ENT
_H8init H'00001240 ENT
_Init H'00000E68 ENT
_InitITU H'00004C1E ENT

*** LINKAGE EDITOR EXTERNALLY DEFINED SYMBOLS LIST ***

SYMBOL NAME ADDR TYPE

_InitLCD H'00004F70 ENT
_InitSCI H'00004DF0 ENT
_InitUSB H'00005116 ENT
_InterruptITU0 H'00004C54 ENT
_LCDOut4 H'00004F18 ENT
_Limit_Read H'000045AA ENT
_LocateLCD H'00005020 ENT
_Motor_Read H'0000455C ENT
_Motor_Write H'00004524 ENT
_OnCloseMotor H'0000343A ENT
_OnController H'00002030 ENT

```
_OnDownMotor                H'00003CA2      ENT
_OnInitWaitDoorChangeLog    H'000036A6      ENT
_OnInitWaitPositionChangeLog H'00003F00     ENT
_OnInput                    H'000029A4      ENT
_OnOpenMotor                H'000031DA      ENT
_OnSimulator                H'00001356      ENT
_OnUpMotor                  H'00003A42      ENT
_OnWaitCloseDoorChangeLog   H'0000384E      ENT
_OnWaitDownPositionChangeLog H'0000409C     ENT
_OnWaitOpenDoorChangeLog    H'0000377A      ENT
_OnWaitUpPositionChangeLog  H'00003FCE      ENT
_Open                       H'00003922      ENT
_OpenMotor                  H'000031BE      ENT
_PermitCommand_Read         H'00004374      ENT
_PermitCommand_Write        H'000043C0      ENT
_PermitTurnOpen_Read        H'00004494      ENT
_PermitTurnOpen_Write       H'000044E0      ENT
_Position                   H'000039B2      ENT
_PrintF                     H'00004CC2      ENT
_PrintLCD                   H'00005044      ENT
_PrintSCI                   H'00004E40      ENT
_PutLCD                     H'00004FF4      ENT
_PutSCI                     H'00004E10      ENT
_Read                       H'000042E2      ENT
_ReadString                 H'0000433C      ENT
_Repaint                    H'000004E4      ENT
_Run                        H'00000550      ENT
_ScanSCI                    H'00004E30      ENT
_SetCurrentTime             H'00004632      ENT
_SetLED                     H'000011CC      ENT
_SetPermit                  H'000046B6      ENT
_SleepMSec                  H'00004758      ENT
_Start                      H'00004A0A      ENT
_Stop                       H'00004A38      ENT
_Thread_Start               H'00004AD0      ENT
_Thread_Toggle              H'00004B0E      ENT
_Thread_checkAllDelete      H'00004A56      ENT
_Thread_checkStayAnother    H'00004A70      ENT
_Thread_getThread           H'00004A96      ENT
_Up                         H'0000416A      ENT
```


*** LINKAGE EDITOR EXTERNALLY DEFINED SYMBOLS LIST ***

```
SYMBOL  NAME                ADDR            TYPE

_UpMotor                    H'00003A26      ENT
_WaitDoorChangeLog          H'0000367E      ENT
_WaitPositionChangeLog      H'00003EE6      ENT
_WaitSecond                 H'00004694      ENT
_Wait_ms                    H'0000472A      ENT
_Write                      H'00004258      ENT
_WriteString                H'000042AA      ENT
__add                       H'000098D6      ENT
```

__allzero	H'00008882	ENT
__calcnpw	H'000088AA	ENT
__ctype	H'0000A088	DAT
__dti	H'00008262	ENT
__duchek	H'00009608	ENT
__errno	H'00FFE864	DAT
__fmtout	H'000063B2	ENT
__its	H'00008648	ENT
__log10	H'000089A2	ENT
__lsft	H'0000965A	ENT
__lsfts	H'00008A46	ENT
__mult	H'000096AC	ENT
__mult64	H'00008CF4	ENT
__pow10	H'0000983A	ENT
__pow5	H'00008ABE	ENT
__power	H'00008D7C	ENT
__rnd	H'00008EDE	ENT
__rnext	H'00FFE860	DAT
__rsfts	H'00008AEC	ENT
__setsbit	H'00008FC8	ENT
__sub	H'00008B66	ENT
__unpack	H'00008C12	ENT
_cntrl	H'00FFE088	DAT
_countUpNextRun	H'0000482E	ENT
delete	H'000049D6	ENT
_frexp	H'00009064	ENT
_getClock	H'00004746	ENT
_get_inbufflen	H'00005BCA	ENT
_get_outbufflen	H'00005BDE	ENT
_i_cnt	H'00FFE016	DAT
_in	H'00FFE04A	DAT
_initWOVI	H'00004C80	ENT
_init_usbbuff	H'00005A2E	ENT
_j_cnt	H'00FFE018	DAT
_main	H'000002B0	ENT
_memcmp	H'00008CB6	ENT
_memcpy	H'000087EC	ENT
_memset	H'0000991E	ENT
_modf	H'0000916A	ENT
_new_EV_Status	H'000041FA	ENT
_new_Thread	H'0000484E	ENT
_nextRun	H'000047EA	ENT
_rand	H'00005BF2	ENT

*** LINKAGE EDITOR EXTERNALLY DEFINED SYMBOLS LIST ***

SYMBOL NAME	ADDR	TYPE
_read_buff	H'00005B6C	ENT
_read_outbuff	H'00005B0E	ENT
_s	H'00FFE046	DAT
_simu	H'00FFE180	DAT
_sprintf	H'00005C2C	ENT

_status	H'00FFE208	DAT
_strcmp	H'00005C8A	ENT
_strcpy	H'00005CB4	ENT
_strlen	H'00005CD0	ENT
_th	H'00FFE01A	DAT
_th1	H'00FFE022	DAT
_th101	H'00FFE260	DAT
_th102	H'00FFE27E	DAT
_th111	H'00FFE29C	DAT
_th112	H'00FFE2BA	DAT
_th113	H'00FFE2D8	DAT
_th114	H'00FFE2F6	DAT
_th119	H'00FFE314	DAT
_th120	H'00FFE332	DAT
_th121	H'00FFE350	DAT
_th122	H'00FFE36E	DAT
_th123	H'00FFE38C	DAT
_th130	H'00FFE3AA	DAT
_th131	H'00FFE3C8	DAT
_th141	H'00FFE3E6	DAT
_th142	H'00FFE404	DAT
_th143	H'00FFE422	DAT
_th19	H'00FFE032	DAT
_th20	H'00FFE036	DAT
_th41	H'00FFE03A	DAT
_th42	H'00FFE03E	DAT
_th43	H'00FFE042	DAT
_usb_int	H'00005274	ENT
_vsprintf	H'00005CEC	ENT
_wovi	H'00004C7C	ENT
_woviClock	H'00FFE21C	DAT
_woviInit	H'00004BEC	ENT
_woviRun	H'00004B52	ENT
_woviThreadFirst	H'00FFE224	DAT
_woviThreadLast	H'00FFE242	DAT
_write_buff	H'00005AA8	ENT
_write_inbuff	H'00005A4C	ENT

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	bcc32 -O2 -w -tWC -D"USE_BCC" -c Panel.c

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Panel.c:

	bcc32 -O2 -w -tWC -D"USE_BCC" -c Timer.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

Timer.c:

警告 W8057 Timer.c 393: パラメータ 'threadPerSec' は一度も使用されない(関数 wovi)

	bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_Time.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_Time.c:

	bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_File.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_File.c:

警告 W8004 EV_File.c 74: 'Ret' に代入した値は使われていない(関数 Write)

警告 W8004 EV_File.c 108: 'Ret' に代入した値は使われていない(関数 WriteString)

警告 W8071 EV_File.c 166: 変換によって有効桁が失われる(関数 Read)

警告 W8004 EV_File.c 162: 'Ret' に代入した値は使われていない(関数 Read)

警告 W8004 EV_File.c 203: 'Ret' に代入した値は使われていない(関数 ReadString)

警告 W8004 EV_File.c 229: 'Ret' に代入した値は使われていない(関数 PermitCommand_Read)

警告 W8004 EV_File.c 247: 'Ret' に代入した値は使われていない(関数 PermitCommand_Write)

警告 W8004 EV_File.c 265: 'Ret' に代入した値は使われていない(関数 Command_Read)

警告 W8004 EV_File.c 283: 'Ret' に代入した値は使われていない(関数 Command_Write)

警告 W8004 EV_File.c 301: 'Ret' に代入した値は使われていない(関数 PermitTurnOpen_Read)

警告 W8004 EV_File.c 319: 'Ret' に代入した値は使われていない(関数 PermitTurnOpen_Write)

警告 W8066 EV_File.c 343: 実行されないコード(関数 Motor_Write)

警告 W8066 EV_File.c 364: 実行されないコード(関数 Motor_Read)

警告 W8066 EV_File.c 367: 実行されないコード(関数 Motor_Read)

警告 W8066 EV_File.c 382: 実行されないコード(関数 Limit_Read)

警告 W8066 EV_File.c 385: 実行されないコード(関数 Limit_Read)

bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_UpDown.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_UpDown.c:

bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_OpenClose.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_OpenClose.c:

bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_Input.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_Input.c:

bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_Controller.c

Borland C++ 5.5.1 for Win32 Copyright (c) 1993, 2000 Borland

EV_Controller.c:

bcc32 -O2 -w -tWC -D"USE_BCC" -c EV_Simulator.c

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EV_Simulator.c:

警告 W8019 EV_Simulator.c 68: コードは効果を持たない(関数 OnSimulator)

警告 W8019 EV_Simulator.c 86: コードは効果を持たない(関数 OnSimulator)

警告 W8019 EV_Simulator.c 104: コードは効果を持たない(関数 OnSimulator)

警告 W8019 EV_Simulator.c 122: コードは効果を持たない(関数 OnSimulator)

bcc32 -O2 -w -tWC -D"USE_BCC" -c main.c

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main.c:

警告 W8004 main.c 291: 'key' に代入した値は使われていない(関数 Run)

ilink32 /Tpe -L"C:¥borland¥bcc55¥Lib" Panel.obj Timer.obj EV_Time.obj EV_File.obj

EV_UpDown.obj EV_OpenClose.obj EV_Input.obj EV_Controller.obj EV_Simulator.obj main.obj

c0x32.obj,main.exe,,cw32.lib import32.lib

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```
MAKE Version 5.2  Copyright (c) 1987, 2000 Borland
        del *.obj
        del main.tds
        del main.ilc
        del main.ild
        del main.ilf
        del main.ils
H8/300H ASSEMBLER (Evaluation software) Ver.1.0
  *****TOTAL ERRORS      0
  *****TOTAL WARNINGS    0
H8/300H LINKAGE EDITOR (Evaluation software) Ver.1.0

: OUTPUT c_thread
: PRINT c_thread
: INPUT asmfile, main, EV_Simulator, EV_Controller, EV_Input, EV_OpenClose, EV_UpDown, EV_File,
EV_Time, Timer, Panel, sci, lcd, usb
: LIB c:¥h8¥akic¥c38hab
: START R(0FFE000), P(200), D(99C0), C(9A00)
: ROM (D, R)
: EXIT

LINKAGE EDITOR COMPLETED
H8/300H OBJECT CONVERTER (Evaluation software) Ver.1.0

OBJECT CONVERTER COMPLETED
```

著作者:

しのみや　ひでみね

篠宮　　英峰