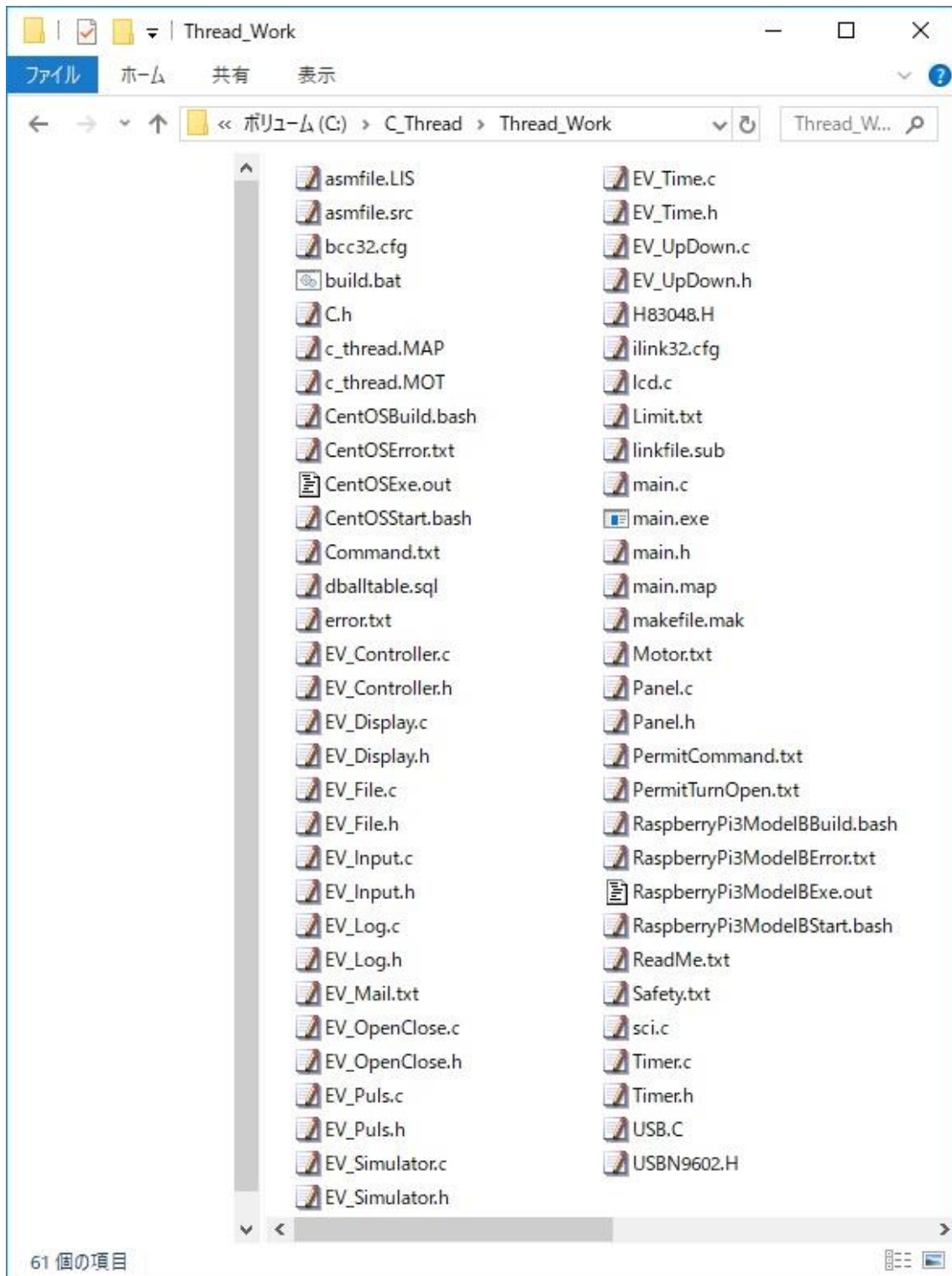


発明の巻

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)が複数で動かします。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7月10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。

=====
このプロジェクトは、4通りの方法でコンパイル 実行 できます。

1つ目の方法：

Windows版 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

makefile.mak build.bat 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 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 (このソフト) が
起動します

2つ目の方法：

Windows版 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

AC/DCコンバータ(ACアダプター) と、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

AC/DCコンバータ の電流電圧 は お店の人 に聞いてください

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2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(短絡コネクタ)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、main.c
を、コンパイルします(build.bat を、編集で中身を確認後、
ダブルクリックします)

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

asmfile.src linkfile.sub build.bat 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

Puls.h Puls.c の記述により、
PortB bit 0 1 2 3 4 5 (AKI-H8-CN1 pin 16 17 18 19 20) から、
エレベーターのモーター指令信号の出力(OUTPUT)があります

error.txt はコンパイルエラーを表示するファイルです

3つ目の方法：

LINUX CentOS6 GCC の利用

LINUX 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

データベース MySQL を使用しておりますので、dballtable.sql
を解析して、以下のコードを試して、MySQL の準備をしてから、
挑戦してみてください

```
yum -y install mysql-community-server
```

以下のコードを試して、<mysql.h> をインストールしてください

```
yum -y install mysql-devel
```

MySQL をインストールしたら、所定の場所に、<mysql.h> があると
思います

エレベーター EV の、非常停止メール通報 について、

```
work@localhost.localdomain
```

```
work@127.0.0.1 のところを、
```

適当な 送信元 ・ 送信先 にしてください

CentOSBuild.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

CentOSError.txt はコンパイルエラーを表示するファイルです

LINUX CentOS6 で CentOSStart.bash をダブルクリックすると、
GCC実行ソフト CentOSExe.out (このソフト) が起動します

私は、CentOS にしましたが、CentOSBuild.bash CentOSStart.bash
が読める方は、好きな LINUX で挑戦してみてください

4つ目の方法：

LINUX Raspberry Pi 3 Model B (ラズベリーパイ) Raspbian GCC の利用

LINUX の GCC を使用するときには、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

データベース MySQL を使用しておりますので、dballtable.sql
を解析して、以下のコードを試して、MySQL の準備をしてから、
挑戦してみてください

```
sudo apt-get install mysql-server
```

以下のコードを試して、<mysql.h> をインストールしてください

```
sudo apt-get install libmariadbclient-dev
```

エレベーター EV の、非常停止メール通報 について、
Linux のシステムコールの mail コマンドと、
Linux のプロセス分割 fork() を使いました
info@hidemine.ciao.jp のところを、
適当な送信先にしてください

RaspberryPi3ModelBBuild.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

RaspberryPi3ModelError.txt はコンパイルエラーを表示するファイルです

Linux Raspbian で RaspberryPi3ModelBStart.bash
をダブルクリックすると、GCC実行ソフト RaspberryPi3ModelBExe.out
(このソフト) が起動します

Puls.h Puls.c の記述により、
GPIO 16 17 18 19 20 (pin 36 11 12 35 38) から、
エレベーターのモーター指令信号の出力(OUTPUT) があります

=====

asmfile.src について

リセットベクタの転送先ラベルが _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

リセットベクタ に続く1番から60番までの 割り込みベクタ について、
使用しない 割り込みベクタ は ラベル `int_error` に転送されます

```
;26 OVIO _INT_OVIO: .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 courses on a race.

ゴールまで14歩です

There are 14 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> course, You click a 'R' button.

For the <2> course, 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

=====

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)を使って

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 ynnnyynn にして上書き保存してください

ynnnnyynn は籠が下階停止状態で扉が閉停止状態を意味します

ynnnnyynn は籠が下階停止状態で扉が閉低速区域を意味します

ynnnnyynn は籠が下階停止状態で扉が中間高速区域を意味します

ynnnnyynn は籠が下階停止状態で扉が開低速区域を意味します

yynnnnyy は籠が下階停止状態で扉が開停止状態を意味します
nynnyynn は籠が下階低速区域で扉が閉停止状態を意味します
nnnnyynn は籠が中間高速区域で扉が閉停止状態を意味します
nnynyynn は籠が上階低速区域で扉が閉停止状態を意味します
nnyyyynn は籠が上階停止状態で扉が閉停止状態を意味します
nnyynynn は籠が上階停止状態で扉が閉低速区域を意味します
nnyynnnn は籠が上階停止状態で扉が中間高速区域を意味します
nnyynnyn は籠が上階停止状態で扉が開低速区域を意味します
nnyynnyy は籠が上階停止状態で扉が開停止状態を意味します

参照ライブラリ

```

/*****
/*      H8/3048F Include File                               */
/*****

struct st_sam {
    void          *MAR;          /* MAR          */
    unsigned int  ETCR;         /* ETCR         */
    unsigned char IOAR;         /* IOAR         */
    unsigned char DTCR;         /* DTCR         */
};

struct st_fam {
    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 {
    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 {
    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 {
    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 {
    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;    /* ADDR B */
    unsigned int  DRC;    /* ADDR C */
    unsigned int  DRD;    /* ADDR D */
    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_MCNTL           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 TxToggle(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 manu. 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をイネーブル    */
    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

```

をセツト*/

```
WriteUSB(USB_RXMSK,USB_RXFIFO0+USB_RXFIFO1+USB_RXFIFO2+USB_RXFIFO3); /* RX MASK
```

をセツト*/

```
WriteUSB(USB_ALTMSK,USB_SD3+USB_RESET_A); /* ALT MASKをセツト*/
```

```
WriteUSB(USB_MAMSK,USB_INTR_E+USB_RX_EV+USB_NAK+USB_TX_EV+USB_ALT); /*
```

MAIN MASKをセツト*/

```
FlushTXC(0);
```

```
FlushRXC(1);
```

```
FlushTXC(1);
```

```
WriteUSB(USB_TXC1,0);
```

```
WriteUSB(USB_RXC1,0);
```

```
WriteUSB(USB_RXC0,USB_RX_EN); /* RX0をイネ-ブル */
```

}

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-トを動作可にする */
```

}

/* 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  nakeevent,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);
        /* ノードをサスペンド */
        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);
    /* ノード 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なのでデータの有無に関係無くDATA1として送信 */
DATA0_1 |= 1;
TxToggle(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();  
            TxToggle(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 = WriteUSBurst(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をアドレス1としてイネーブル */
        WriteUSB(USB_EPC1,USB_EP_EN+01);
        /* TX1送信可 */
    }
}

```

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

```
FlushRXC(1);
```

```
/* EPC2をアドレス2としてイネ-ブル */
```

```
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 TxToggle(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 WriteUSBurst(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 = WriteUSBurst(USB_TXD1,USB_TXS1,(char*)rx2buff,sz);
    }
    TxToggle(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[ (USBUFFLEN+outpos-outlen)%USBUFFLEN ];
        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 パリティ無し STOP1

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

```
void InitSCI()
```

```
{
```

```
    int    i;
```

```
    SCI1.SCR = 0;
```

```
    SCI1.SMR = 0; /* パリティ無し 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处理
```

```
    (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=cursor , 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 */
/* #define USE_CENTOS */
/* #define USE_RASPBIAN */
#ifdef USE_CENTOS
#define USE_LINUX
#endif
#ifdef USE_RASPBIAN
#define USE_LINUX
#endif
#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
/* AKI-H8 3052F USB */
#include "h83048.h"
#define SLEEP_PER_SEC 16000.0
#define NOTUSE_FILES
#else
/* time_t, tm, time(), clock(), CLOCKS_PER_SEC */
#include <time.h>
#ifdef USE_LINUX
#include <termios.h> /* kbhit() */
#include <unistd.h> /* kbhit(), mail, fork() */
#include <fcntl.h> /* kbhit() */
/* mail バークレー・ソケット */
#define _OE_SOCKETS
#include <sys/types.h> /* mail */
#include <sys/socket.h> /* mail */
#include <netinet/in.h> /* mail */
#include <netdb.h> /* mail */
#include <arpa/inet.h> /* mail バークレー・ソケット */
#ifdef USE_CENTOS
#include <mysql.h> /* LINUX CentOS GCC MySQL */
#endif
#ifdef USE_RASPBIAN
#include <mysql/mysql.h> /* LINUX Raspbian GCC MySQL */
#endif
#ifdef USE_RASPBIAN
#include <wiringPi.h> /* LINUX Raspberry Pi 3 Model B I/O */
#endif
#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\r0") == 0)
{
    sprintf(str, "%s", "\n\rf");
}
sprintf(buff,"%s", str);
PrintSCI("%s",buff);
PrintLCD(str);
#endif

break;

case Panel:

#ifndef USE_BCC

if(strcmp(str, "\n\r0") == 0)
{
    sprintf(str, "%s", "\n\rf");
}

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 wovilnit(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  
  
#ifdef USE_LINUX
```



```
void wovi(double threadPerSec); /* タイマ関数 */  
  
#else  
  
void wovi(void); /* タイマ関数 */  
  
#endif  
  
void initWOVI(void); /* タイマ初期化関数 */  
  
#endif  
  
#ifdef USE_BCC  
  
void PrintCurrentTime(void); /* 現在日時表示 */  
  
void myDateTime(long *mydate, long *mytime); /* 現在日時取得 */  
  
#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;
```

```
Thread th144;
```

```
Thread th145;
```

```
#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;
    }
#ifdef 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;  
}  
else if(id == 44)  
{  
    new_List = &th144;  
}  
else if(id == 45)  
{  
    new_List = &th145;  
}  
  
#endif  
  
#ifdef USE_BCC  
    new_List = (Thread *)calloc(1, sizeof(Thread));  
  
#endif
```

```

if(new_List == NULL)
{
    Printf(Pannel, "¥n");
    Printf(Pannel, "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 wovilnit(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 */
#ifdef USE_LINUX
void wovi(double threadPerSec)
#else
void wovi(void)
#endif
{
#ifdef USE_BCC
    /* woviClock は秒数時計 */
#endif
#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;
}

void myDateTime(long *mydate, long *mytime)
{

```

```
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);

*mydate = t_st->tm_year + 1900;

*mydate *= 100;

*mydate += (t_st->tm_mon + 1);

*mydate *= 100;

*mydate += t_st->tm_mday;

*mytime = t_st->tm_hour;

*mytime *= 100;

*mytime += t_st->tm_min;

*mytime *= 100;

*mytime += 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
```

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

```
#ifndef 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, strlen, 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", 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);

/* 經過時間 */

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_OPST = OFF;
```

```
    This->m_OPST = OFF;
```

```
    This->p_CloserSlow = &This->m_CLSL;
```

```
    This->p_CloserStop = &This->m_CLST;
```

```
    This->p_OpennerSlow = &This->m_OPST;
```

```
    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_fmmove == OFF){
        *DR->p_fmmove = 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_fmmove == OFF){
        *DR->p_fmmove = 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_fmmove == OFF){
            *DR->p_fmmove = 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;
    Checkmove(DR->p_CloserStop, DR->p_fmove, This->tmp);
    This->tmp = (This->strLimit[5] == 'y') ? ON : OFF;
    Checkmove(DR->p_CloserSlow, DR->p_fmove, This->tmp);
    This->tmp = (This->strLimit[6] == 'y') ? ON : OFF;
    Checkmove(DR->p_OpennerSlow, DR->p_fmove, This->tmp);
    This->tmp = (This->strLimit[7] == 'y') ? ON : OFF;
    Checkmove(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_Display.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
```

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

```
シミュレータを表す関数のプロトタイプ宣言
```

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

```
void Displnput(void);
```

```
void Disp(char ch, char str[9]);
```

```
/* EV_Display.c */
```

```
#include "C.h"
```

```
#include "EV_Display.h"
```

```
void DisplInput(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])
```

```
{
```

```
#ifdef USE_BCC
```

```
    int i;
```

```
    /* 画面クリア */
```

```
    CLEAR;
```

```
    if((((ch == 'o') || (ch == 'h')) && (str[3] == 'y') && (str[7] == 'y'))
```

```
        || ((ch == 't') && (str[3] == 'y') && (str[7] == 'n') && (str[6] == 'y'))
```

```
        || ((ch == 's') && (str[3] == 'y') && (str[7] == '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[3] == 'y') && (str[7] == 'n') && (str[6] == 'y'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'y') && (str[7] == 'n') && (str[6] == 'n') && (str[5] ==
'n') && (str[4] == 'n'))
    || ((ch == 's') && (str[3] == 'y') && (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[3] == 'y') && (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[3] == 'y') && (str[7] == 'n') && (str[6] == 'n') && (str[5] ==
'n') && (str[4] == 'n'))
    || (((ch == 'C') || (ch == 't')) && (str[3] == 'y') && (str[5] == 'y') && (str[4] == 'n'))
    || ((ch == 's') && (str[3] == 'y') && (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 == 'u') || (ch == 'j')) && (str[3] == 'y') && (str[4] == 'y'))
    || ((ch == 'k') && (str[3] == 'n') && (str[2] == 'y') && (str[4] == 'y'))
    || ((ch == 'h') && (str[3] == 'y') && (str[5] == 'y') && (str[4] == 'n'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'y') && (str[4] == 'y'))
    || ((ch == 's') && (str[3] == '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((((ch == 'o') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'y'))
    || ((ch == 't') && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] == 'y'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'y')))
{
    for(i = 0; i < 1; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 1; i < 5; i++)
    {
        Printf(Monitor, "%n0000    0000");
    }
    for(i = 5; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}
else if((((ch == 'O') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] ==
'y'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] ==
'n') && (str[5] == 'n') && (str[4] == 'n'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] == 'y')))

```

```

{
    for(i = 0; i < 1; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 1; i < 5; i++)
    {
        Printf(Monitor, "%n 0000  0000 ");
    }
    for(i = 5; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}
else if((ch == 's') && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] == 'n') && (str[5]
== 'n') && (str[4] == 'n'))
{
    for(i = 0; i < 1; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 1; i < 5; i++)
    {
        Printf(Monitor, "%n 0000  0000 ");
    }
    for(i = 5; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}

```



```

    }
}
else if((((ch == 'o') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'y') && (str[7] == 'n') && (str[6] ==
'n') && (str[5] == 'n') && (str[4] == 'n'))
    || (((ch == 'C') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'y') && (str[5] == 'y') && (str[4] ==
'n'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'y') && (str[5] == 'y') && (str[4] == 'n'))))
{
    for(i = 0; i < 1; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 1; i < 5; i++)
    {
        Printf(Monitor, "%n 0000 0000 ");
    }
    for(i = 5; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}
else if((((ch == 'U') || (ch == 'j')) && (str[3] == 'n') && (str[2] == 'y') && (str[4] == 'y'))
    || (((ch == 'd') || (ch == 'k')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[4] == 'y'))
    || ((ch == 'h') && (str[3] == 'n') && (str[2] == 'y') && (str[5] == 'y') && (str[4] == 'n'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'y') && (str[4] == 'y'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'y') && (str[4] == '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 == 'o') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[7] == 'y'))
    || ((ch == 't') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[7]
== 'n') && (str[6] == 'y'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[7]
== 'y'))))
{
    for(i = 0; i < 4; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 4; i < 8; i++)
    {
        Printf(Monitor, "%n0000      0000");
    }
    for(i = 8; i < 12; i++)
    {

```

```

        Printf(Monitor, "%n      ");
    }
}
else if((((ch == 'O') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[7] == 'n') && (str[6] == 'y'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4] == 'n'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[7]
== 'n') && (str[6] == 'y')))
{
    for(i = 0; i < 4; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 4; i < 8; i++)
    {
        Printf(Monitor, "%n 0000    0000 ");
    }
    for(i = 8; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}
else if((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[7]
== 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4] == 'n'))
{
    for(i = 0; i < 4; i++)
    {
        Printf(Monitor, "%n      ");
    }
}

```

```

}
for(i = 4; i < 8; i++)
{
    Printf(Monitor, "%n 0000 0000 ");
}
for(i = 8; i < 12; i++)
{
    Printf(Monitor, "%n      ");
}
}
else if((((ch == 'o') || (ch == 'h')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[7] == 'n') && (str[6] == 'n') && (str[5] == 'n') && (str[4] == 'n'))
    || (((ch == 'C') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[5] == 'y') && (str[4] == 'n'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[5]
== 'y') && (str[4] == 'n')))
{
    for(i = 0; i < 4; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 4; i < 8; i++)
    {
        Printf(Monitor, "%n 0000 0000 ");
    }
    for(i = 8; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}

```

```

    }
}
else if((((ch == 'h') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[5]
== 'y') && (str[4] == 'n'))
    || (((ch == 'c') || (ch == 't')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[4] == 'y'))
    || ((ch == 's') && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] == 'n') && (str[4]
== 'y'))))
{
    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 == 'o') || (ch == 'h')) && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'y'))
    || ((ch == 't') && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] == 'y'))
    || ((ch == 's') && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'y'))))
{
    for(i = 0; i < 6; i++)
    {
        Printf(Monitor, "%n      ");
    }
}

```

```

}
for(i = 6; i < 10; i++)
{
    Printf(Monitor, "%n0000    0000");
}
for(i = 10; i < 12; i++)
{
    Printf(Monitor, "%n        ");
}
}
else if((((ch == 'O') || (ch == 'h')) && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] ==
'y'))
    || (((ch == 'c') || (ch == 't')) && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] ==
'n') && (str[5] == 'n') && (str[4] == 'n'))
    || ((ch == 's') && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] == 'y'))))
{
    for(i = 0; i < 6; i++)
    {
        Printf(Monitor, "%n        ");
    }
    for(i = 6; i < 10; i++)
    {
        Printf(Monitor, "%n 0000    0000 ");
    }
    for(i = 10; i < 12; i++)
    {
        Printf(Monitor, "%n        ");
    }
}
}

```

```

else if((ch == 's') && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] == 'n') && (str[5]
== 'n') && (str[4] == 'n'))
{
    for(i = 0; i < 6; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 6; i < 10; i++)
    {
        Printf(Monitor, "%n 0000 0000 ");
    }
    for(i = 10; i < 12; i++)
    {
        Printf(Monitor, "%n      ");
    }
}
else if((((ch == 'o') || (ch == 'h')) && (str[1] == 'y') && (str[0] == 'n') && (str[7] == 'n') && (str[6] ==
'n') && (str[5] == 'n') && (str[4] == 'n'))
    || (((ch == 'C') || (ch == 't')) && (str[1] == 'y') && (str[0] == 'n') && (str[5] == 'y') && (str[4] ==
'n'))
    || ((ch == 's') && (str[1] == 'y') && (str[0] == 'n') && (str[5] == 'y') && (str[4] == 'n'))))
{
    for(i = 0; i < 6; i++)
    {
        Printf(Monitor, "%n      ");
    }
    for(i = 6; i < 10; i++)
    {
        Printf(Monitor, "%n 0000 0000 ");
    }
}

```

```

}
for(i = 10; i < 12; i++)
{
    Printf(Monitor, "%n    ");
}
}
else if((((ch == 'u') || (ch == 'j')) && (str[3] == 'n') && (str[2] == 'n') && (str[1] == 'n') && (str[0] ==
'n') && (str[4] == 'y'))
    || (((ch == 'D') || (ch == 'k')) && (str[1] == 'y') && (str[0] == 'n') && (str[4] == 'y'))
    || ((ch == 'h') && (str[1] == 'y') && (str[0] == 'n') && (str[5] == 'y') && (str[4] == 'n'))
    || (((ch == 'c') || (ch == 't')) && (str[1] == 'y') && (str[0] == 'n') && (str[4] == 'y'))
    || ((ch == 's') && (str[1] == 'y') && (str[0] == 'n') && (str[4] == 'y')))
{
    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 == 'o') || (ch == 'h')) && (str[0] == 'y') && (str[7] == 'y'))
    || ((ch == 't') && (str[0] == 'y') && (str[7] == 'n') && (str[6] == 'y'))

```



```

    || ((ch == 's') && (str[0] == 'y') && (str[7] == '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[0] == 'y') && (str[7] == 'n') && (str[6] == 'y'))
    || (((ch == 'c') || (ch == 't')) && (str[0] == 'y') && (str[7] == 'n') && (str[6] == 'n') && (str[5] ==
'n') && (str[4] == 'n'))
    || ((ch == 's') && (str[0] == 'y') && (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[0] == 'y') && (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[0] == 'y') && (str[7] == 'n') && (str[6] == 'n') && (str[5] ==
'n') && (str[4] == 'n'))
    || (((ch == 'C') || (ch == 't')) && (str[0] == 'y') && (str[5] == 'y') && (str[4] == 'n'))
    || ((ch == 's') && (str[0] == 'y') && (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 == 'j') && (str[1] == 'y') && (str[0] == 'n') && (str[4] == 'y'))
    || (((ch == 'd') || (ch == 'k')) && (str[0] == 'y') && (str[4] == 'y'))
    || ((ch == 'h') && (str[0] == 'y') && (str[5] == 'y') && (str[4] == 'n'))
    || (((ch == 'c') || (ch == 't')) && (str[0] == 'y') && (str[4] == 'y'))
    || ((ch == 's') && (str[0] == 'y') && (str[4] == 'y')))
{
    for(i = 0; i < 8; i++)

```

```
{
    Printf(Monitor, "%n    ");
}
for(i = 8; i < 12; i++)
{
    Printf(Monitor, "%n 00000000 ");
}
}
#endif
/* 入力指示 */
DisplInput();
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
```

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

```
  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;
}
}
}
}
}

#else

#ifdef USE_LINUX
    if(kbhit())
    {
        Ret = (char) getchar();
    }
}

#ifdef USE_MSVS2005
    if(_kbhit())
    {
        Ret = (char) _getche();
    }
}

#else
    if(kbhit())
    {
        Ret = (char) getche();
    }
}
```



```
#endif
```

```
#endif
```

```
#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(Panel, "¥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(Panel, "¥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(Pannel, "%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(Pannel, "%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(Pannel, "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(Pannel, "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_Puls.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
```

```
/* Raspberry Pi 3 Model B I/O */
```

```
#ifdef USE_RASPBIAN
```

```
#define GPIO16 16
```

```
#define GPIO17 17
```

```
#define GPIO18 18
```

```
#define GPIO19 19
```

```
#define GPIO20 20
```

```
#endif
```

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

```
送信を表す構造体
```

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

```
struct EV_Puls
```

```
{
```

```
    char ch;
```

```
    char *p_ch;
```

```
    char Command;
```

```
    char *p_Command;
```

```
    /* ファイルストリーム */
```

```
    struct EV_File CF;
```

```
    struct EV_File MF;
```

```
};
```

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

```
送信を表す関数のプロトタイプ宣言
```

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

```
void EV_Set(int addressDataSet, int dataSet, int addressClockSet,
```

```
int clockSet);
```

```
void EV_EnableSet(void);
```

```
int EV_AddressSet(Thread *th, int base, int address);
```

```
int EV_DataSet(Thread *th, int base, int data);
```

```
void EV_AddressDataSet(struct EV_Puls *puls, Thread *th,
```

```
int address_1, int address_2, int address_3, int address_4,
```

```
int data_1, int data_2, int data_3, int data_4);
```

```
/*=====
送信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_Puls(struct EV_Puls *This, Thread *th);
void OnPuls(struct EV_Puls *This, Thread *th);
```

```
/* EV_Puls.c */
```

```
#include "C.h"
```

```
#include "EV_Puls.h"
```

```
void EV_Set(int addressDataSet, int dataSet, int addressClockSet,  
int clockSet){
```

```
#ifndef USE_BCC
```

```
    /* address data set */
```

```
    if(addressDataSet == 0){
```

```
        PB.DR &= 0xfe;
```

```
    }
```

```
    else if(addressDataSet == 1){
```

```
        PB.DR |= 0x01;
```

```
    }
```

```
    /* data set */
```

```
    if(dataSet == 0){
```

```
        PB.DR &= 0xfd;
```

```
    }
```

```
    else if(dataSet == 1){
```

```
        PB.DR |= 0x02;
```

```
    }
```

```
    /* address clock set */
```

```
    if(addressClockSet == 0){
```

```
        PB.DR &= 0xfb;
```

```
    }
```

```
    else if(addressClockSet == 1){
```

```
        PB.DR |= 0x04;
```

```

}

/* clock set */
if(clockSet == 0){
    PB.DR &= 0xf7;
}

else if(clockSet == 1){
    PB.DR |= 0x08;
}

/* disable set */
PB.DR &= 0xef;

#endif

#ifdef USE_RASPBIAN

/* address data set */
digitalWrite(GPIO16, addressDataSet);

/* data set */
digitalWrite(GPIO17, dataSet);

/* address clock set */
digitalWrite(GPIO18, addressClockSet);

/* clock set */
digitalWrite(GPIO19, clockSet);

/* disable set */
digitalWrite(GPIO20, 0);

#endif

return;
}

void EV_EnableSet(void){

#ifdef USE_BCC

/* address data set */

```

```

PB.DR &= 0xfe;

/* data set */

PB.DR &= 0xfd;

/* address clock set */

PB.DR &= 0xfb;

/* clock set */

PB.DR &= 0xf7;

/* enable set */

PB.DR |= 0x10;

#endif

#ifdef USE_RASPBIAN

/* address data set */

digitalWrite(GPIO16, 0);

/* data set */

digitalWrite(GPIO17, 0);

/* address clock set */

digitalWrite(GPIO18, 0);

/* clock set */

digitalWrite(GPIO19, 0);

/* enable set */

digitalWrite(GPIO20, 1);

#endif

return;

}

int EV_AddressSet(Thread *th, int base, int address){

int Ret;

Ret = NG;

if(th->count == base){

```

```

    EV_Set(address, 0, 0, 0);

    th->count++;

    Ret = OK;
}
else if(th->count == base + 1){
    EV_Set(address, 0, 1, 0);

    th->count++;

    Ret = OK;
}
return Ret;
}

```

```

int EV_DataSet(Thread *th, int base, int data){
    int Ret;

    Ret = NG;

    if(th->count == base){
        EV_Set(0, data, 0, 0);

        th->count++;

        Ret = OK;
    }
    else if(th->count == base + 1){
        EV_Set(0, data, 0, 1);

        th->count++;

        Ret = OK;
    }
    return Ret;
}

```

```

void EV_AddressDataSet(struct EV_Puls *puls, Thread *th,

```



```

int address_1, int address_2, int address_3, int address_4,
int data_1, int data_2, int data_3, int data_4){
    if(EV_AddressSet(th, 0, address_1) == OK);
    else if(EV_AddressSet(th, 2, address_2) == OK);
    else if(EV_AddressSet(th, 4, address_3) == OK);
    else if(EV_AddressSet(th, 6, address_4) == OK);
    else if(EV_DataSet(th, 8, data_1) == OK);
    else if(EV_DataSet(th, 10, data_2) == OK);
    else if(EV_DataSet(th, 12, data_3) == OK);
    else if(EV_DataSet(th, 14, data_4) == OK);
    else{
        EV_EnableSet();
        th->count = 0;
        switch(puls->Command){
            case 'q':
#endif USE_BCC
                /* address data set */
                PB.DR &= 0xfe;
                /* data set */
                PB.DR &= 0xfd;
                /* address clock set */
                PB.DR &= 0xfb;
                /* clock set */
                PB.DR &= 0xf7;
                /* disable set */
                PB.DR &= 0xef;
#endif
#endif USE_RASPBIAN

```

```

        /* address data set */
        digitalWrite(GPIO16, 0);
        /* data set */
        digitalWrite(GPIO17, 0);
        /* address clock set */
        digitalWrite(GPIO18, 0);
        /* clock set */
        digitalWrite(GPIO19, 0);
        /* disable set */
        digitalWrite(GPIO20, 0);
#endif

        delete_(th);
        break;
    default:
        break;
    }
}
return;
}

void EV_Puls(struct EV_Puls *This, Thread *th){
    This->p_ch = &This->ch;
    This->p_Command = &This->Command;
    EV_File(&This->MF);
    EV_File(&This->CF);
#ifdef USE_BCC
    PB.DDR = 0xff; /* bit7..0 out */
    PB.DR |= 0xff;
#endif
}

```

```

#ifdef USE_RASPBIAN
    if (wiringPiSetupGpio() == -1) exit(NG);
    pinMode(GPIO16, OUTPUT);
    pinMode(GPIO17, OUTPUT);
    pinMode(GPIO18, OUTPUT);
    pinMode(GPIO19, OUTPUT);
    pinMode(GPIO20, OUTPUT);
#endif

    return;
}

void OnPuls(struct EV_Puls *This, Thread *th){
    if(th->count == 0){
        /* 命令入力 */
        Command_Read(&This->CF, This->p_Command);
        /* モータ一命令解読 */
        Read(&This->MF, "Motor.txt¥0", This->p_ch);
    }
    switch(This->ch){
    case 's':
        EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 0, 0, 0);
        break;
    case 'j':
        EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 0, 0, 1);
        break;
    case 'u':
        EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 0, 1, 0);
        break;
    case 'U':

```

```
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 0, 1, 1);  
    break;  
case 'k':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 1, 0, 0);  
    break;  
case 'd':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 1, 0, 1);  
    break;  
case 'D':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 1, 1, 0);  
    break;  
case 'h':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 0, 1, 1, 1);  
    break;  
case 'o':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 1, 0, 0, 0);  
    break;  
case 'O':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 1, 0, 0, 1);  
    break;  
case 't':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 1, 0, 1, 0);  
    break;  
case 'c':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 1, 0, 1, 1);  
    break;  
case 'C':  
    EV_AddressDataSet(This, th, 0, 1, 1, 1, 1, 1, 0, 0);  
    break;
```

default:

break;

}

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_Display_h
```

```
#define EV_Display_h
```

```
#include "EV_Display.h"
```

```
#endif
```

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

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;
}
```

```
/* EV_Log.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
```

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

```
記録を表す構造体
```

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

```
struct EV_Log{
```

```
    MYSQL *conn;
```

```
    MYSQL_RES *resp;
```

```
MYSQL_ROW row;
char str_sql1[255];
char str_sql2[255];
long mydate;
long mytime;
char ch_safety;
int i_safety;
char str_limit[9];
char ch_command;
char ch_permitcommand;
char ch_permitturnopen;
char ch_motor;
char *p_ch_safety;
char *p_str_limit;
char *p_ch_command;
char *p_ch_permitcommand;
char *p_ch_permitturnopen;
char *p_ch_motor;
struct EV_File SF;
struct EV_File LF;
struct EV_File CF;
struct EV_File PCF;
struct EV_File PTOF;
struct EV_File MF;
};

/*=====
記録を表すプロトタイプ宣言
=====*/
```

```
void EV_Log(struct EV_Log *This); /* database接続 */
```

```
void delete_EV_Log(struct EV_Log *This); /* database切断 */
```

```
void OnLog(struct EV_Log *This, Thread *th); /* database記録 */
```

```
/* EV_Log.c */

#include "C.h"

#include "EV_Log.h"

#define DBSERVER "localhost"

#define DBID "pi"

#define DBPASSWORD "raspberry"

#define DBNAME "ev001"

#define DBPORTNO 3306

#define SERVER_NAME "127.0.0.1"

#define ERR -1

#define BUFSIZE 1024

#ifdef USE_CENTOS

/* 送信ユーザー名(Linux Login ID) */

#define MAIL_FROM_HOST "work"

/* 送信サーバー名(自身 IP 127.0.0.1) */

#define MAIL_FROM_SERVER "localhost.localdomain"

/* 送信名 */

#define MAIL_FROM_HOST_AT_SERVER "work@localhost.localdomain"

/* 受信名(送信先 E-mail address) */

#define RCPT_TO_HOST_AT_SERVER "work@localhost.localdomain"

#endif

/* 送信メール内容ファイル */

#define SEND_DATA "./EV_Mail.txt"
```



```

char *command_name;

int socket(int domain, int type, int protocol);

/* 非常停止メッセージのメール通報のプロトタイプ */

void emergency(void);

/* database接続 */

void EV_Log(struct EV_Log *This)
{
    This->conn = NULL;

    This->resp = NULL;

    This->p_ch_safety = &This->ch_safety;

    This->p_str_limit = &This->str_limit[0];

    This->p_ch_command = &This->ch_command;

    This->p_ch_permitcommand = &This->ch_permitcommand;

    This->p_ch_permitturnopen = &This->ch_permitturnopen;

    This->p_ch_motor = &This->ch_motor;

    EV_File(&This->SF);

    EV_File(&This->LF);

    EV_File(&This->CF);

    EV_File(&This->PCF);

    EV_File(&This->PTOF);

    EV_File(&This->MF);

    memset(&This->str_sql2[0], 0x00, sizeof(This->str_sql2));

    /* mysql接続 */

    This->conn = mysql_init(NULL);

    if(!mysql_real_connect(This->conn, DBSERVER, DBID, DBPASSWORD, DBNAME, DBPORTNO, NULL,
0))
    {

```

```

    /* error */

    printf("%s¥n", mysql_error(This->conn));

    exit(NG);

}

return;

}

/* databaset切断 */

void delete_EV_Log(struct EV_Log *This)

{

    mysql_close(This->conn);

    return;

}

/* database記録 */

void OnLog(struct EV_Log *This, Thread *th)

{

    This->i_safety = 0;

    snprintf(This->str_sql1, sizeof(This->str_sql1), "select * from s_log order by lg_ymd desc, lg_hms
desc limit 1;" );

    mysql_query(This->conn , This->str_sql1);

    This->resp = mysql_use_result(This->conn);

    if((This->row = mysql_fetch_row(This->resp)) != NULL )

    {

        /* 直前のSafety(安全)のDatabase記録を採取 */

        This->i_safety = (int) This->row[2][0];

        /* Debug */

        /* printf("¥n¥d ¥d : ¥s" , atoi(This->row[0]), atoi(This->row[1]), This->row[2]); */

```

```

}

mysql_free_result(This->resp);

myDateTime(&This->mydate, &This->mytime);
Read(&This->SF, "Safety.txt¥0", This->p_ch_safety);
ReadString(&This->LF, "Limit.txt¥0", This->p_str_limit, 9);
Read(&This->CF, "Command.txt¥0", This->p_ch_command);
Read(&This->PCF, "PermitCommand.txt¥0", This->p_ch_permitcommand);
Read(&This->PTOF, "PermitTurnOpen.txt¥0", This->p_ch_permitturnopen);
Read(&This->MF, "Motor.txt¥0", This->p_ch_motor);

sprintf(This->str_sql2, "insert into s_log(lg_ymd, lg_hms, lg_safety, lg_limit, lg_command,
lg_permitcommand, lg_permitturnopen, lg_motor) values ( %ld, %ld, '%c', '%s', '%c', '%c', '%c', '%c');",
This->mydate, This->mytime, This->ch_safety, This->p_str_limit, This->ch_command, This-
>ch_permitcommand, This->ch_permitturnopen, This->ch_motor);

/* Debug */
/* printf("¥n¥s¥n", This->str_sql2); */

mysql_query(This->conn, This->str_sql2);

/* 直前のSafety(安全)の記録がr(Run 運転)かどうか */
if(This->i_safety - ((int) 'r') == 0)
{
    /* 現在のSafety(安全)の記録がs(Stop 非常停止)かどうか */
    if(This->ch_safety == 's')
    {
        /* 非常停止メッセージのメール通報 */
        emergency();
    }
}

```

```

    }
}

if(This->ch_command == 'q'){
    delete_(th);
}
return;
}

#ifdef USE_CENTOS
/* 非常停止メッセージのメール通報 */
void emergency(void)
{
    /* ソケットディスクリプタ */
    int sds;
    FILE *fp;
    /*サーバプロセスのソケットアドレス情報 */
    struct sockaddr_in server;
    /* ホスト情報 */
    struct hostent *hp;
    char buf[BUFSIZE];
    int i_buf;
    char ch_buf;

    /* 画面クリア */
    CLEAR;

    /* ソケットの作成 */

```

```

if((sds = socket(PF_INET, SOCK_STREAM, 0)) == ERR)
{
    perror("client: socket");
    exit(NG);
}

/* サーバの情報を格納 */
memset((void*)&server, 0, sizeof(server));

server.sin_family = PF_INET;
server.sin_addr.s_addr = inet_addr(SERVER_NAME);

/* ポート番号25 */
server.sin_port = htons(25);

printf("%d¥r¥n", server.sin_family);

/* IPアドレスの設定 */
hp = gethostbyname(MAIL_FROM_SERVER);
memcpy(&(server.sin_addr), hp->h_addr_list[0], hp->h_length);

/* サーバに接続 */
if(connect(sds, (struct sockaddr *)&server, sizeof(server))==ERR)
{
    perror("client: connect");
    exit(NG);
}

read(sds, buf, sizeof(buf));

printf("%s¥r¥n", buf);

/* HELOの送信 */
strcpy(buf, "HELO ");
strcat(buf, MAIL_FROM_HOST);

```

```
strcat(buf, "¥r¥n¥0");  
printf("%s", buf);  
write(sds, buf, strlen(buf));  
memset(&buf[0], 0x00, sizeof(buf));  
read(sds, buf, sizeof(buf));  
printf("%s", buf);
```

```
/* MAIL FROMの送信 */
```

```
strcpy(buf, "MAIL FROM:");  
strcat(buf, MAIL_FROM_HOST);  
strcat(buf, "¥r¥n¥0");  
printf("%s", buf);  
write(sds, buf, strlen(buf));  
memset(&buf[0], 0x00, sizeof(buf));  
read(sds, buf, sizeof(buf));  
printf("%s", buf);
```

```
/* RCPT TOの送信 */
```

```
strcpy(buf, "RCPT TO:");  
strcat(buf, RCPT_TO_HOST_AT_SERVER);  
strcat(buf, "¥r¥n¥0");  
printf("%s", buf);  
write(sds, buf, strlen(buf));  
memset(&buf[0], 0x00, sizeof(buf));  
read(sds, buf, sizeof(buf));  
printf("%s", buf);
```

```
/* DATA の送信 */
```

```
strcpy(buf, "DATA¥r¥n¥0");
```

```

printf("%s", buf);
write(sds, buf, strlen(buf));
memset(&buf[0], 0x00, sizeof(buf));
read(sds, buf, sizeof(buf));
printf("%s", buf);
i_buf = 0;
if((fp = fopen(SEND_DATA, "r")) != NULL)
{
    strcpy(buf, "");
    while((ch_buf = fgetc(fp)) != EOF)
    {
        buf[i_buf++] = ch_buf;
    }
    fclose(fp);
    strcat(buf, "¥r¥n.¥r¥n¥0");
    /* 非常停止メッセージ通報 */
    printf("%s", buf);
    write(sds, buf, strlen(buf));
    memset(&buf[0], 0x00, sizeof(buf));
    read(sds, buf, sizeof(buf));
    printf("%s", buf);
}

strcpy(buf, "QUIT¥r¥n¥0");
printf("%s", buf);
write(sds, buf, strlen(buf));
memset(&buf[0], 0x00, sizeof(buf));
read(sds, buf, sizeof(buf));
printf("%s", buf);

```

```
    return;
}

#endif

#ifdef USE_RASPBIAN
/* 非常停止メッセージのメール通報 */
void emergency(void)
{
    /* プロセス分割用 */
    pid_t p;

    p = fork(); /* プロセス分割 */
    if(p == 0) /* 子プロセス */
    {
        /* 非常停止メッセージ通報 */
        system("echo An EV is stopped emergency! | mail -s ¥\"This is from Raspberry Pi.¥\"
info@hidemine.ciao.jp");
        printf("An EV is stopped emergency!");

        exit(OK); /* 子プロセス終了 */
    }

    return;
}

#endif
```



```
/* 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_Display_h  
#define EV_Display_h  
#include "EV_Display.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_Puls_h  
#define EV_Puls_h  
#include "EV_Puls.h"  
#endif
```

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

```
#ifdef USE_LINUX
#ifndef EV_Log_h
#define EV_Log_h
#include "EV_Log.h"
#endif
#endif

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

int main(void);
```

```
/* 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

/* 擬似スレッドの擬似インスタンス宣言 */
Thread *th1[4];
Thread *th19;
Thread *th20;
Thread *th41;
Thread *th42;
Thread *th43;
Thread *th44;
Thread *th45;
#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;
```

```
/*=====
 送信オブジェクト宣言
=====*/
```

```
struct EV_Puls puls;
```

```
/*=====
 シミュレータオブジェクト宣言
=====*/
```

```
struct EV_Simulator simu;
```

```
#ifdef USE_LINUX
```

```
/*=====
 記録オブジェクト宣言
=====*/
```

```
struct EV_Log lg;
```

```
#endif
```

```
int main(void)
```

```

{
#ifdef 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
#ifdef 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 センソコントロ-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 */
#ifdef USE_CENTOS
        wovi(15000000.0);
#else
#ifdef USE_RASPBIAN
        wovi(2500000.0);
#else
        wovi();
#endif
#endif
        if(Thread_checkAllDelete() == OK)
        {
            break;
        }
    }
#endif

    Clear();
    Printf(Panel, "NEXT      ");
    /* 2秒待機 */
    SleepMSec(2000);
    Clear();
#ifdef 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++) {} /* 適当にウェイト */
```

```
}
```

```
#else
```

```
printf("END");
```

```
/* 5秒待機 */
```

```
SleepMSec(5000);
```

```
return OK;
```

```
#endif
```

```
}
```

```
#ifndef 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 *th1;
#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();
#ifdef 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) * 15));
    while(kbhit())
    {
#ifdef USE_LINUX
        key = (char) getchar();
#else
        key = (char) getche();
#endif
    }
}
}
else if(This->ID == 2)
{
    Repaint();
}
#endif 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) * 15));
    while(kbhit())
    {
#ifdef USE_LINUX
        key = (char) getchar();
#else
        key = (char) getche();
#endif
    }
}
#endif
}
#endif
#ifdef USE_BCC
    else if(((This->ID) >= 3) && ((This->ID) <= 8))
    {

```

```

        Repaint();
        Cnt.cnt[(This->ID) - 1]++;
        nextRun(This, (((rand() % 9) + 10) * 40));
    }
#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(Pannel, "<3>1st    ");
        countUpNextRun(This, (1700 * 3));
    }
    else if(This->count == 2)
    {
        Clear();
        Printf(Pannel, "<3>2nd    ");
        countUpNextRun(This, (1700 * 3));
    }
    else if(This->count == 3)
    {
        Clear();
        Printf(Pannel, "<3>3rd    ");
        countUpNextRun(This, (1700 * 3));
    }
    else
    {
        Clear();
        Printf(Pannel, "<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
#ifdef 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);
}
#endif USE_BCC
else if((This->ID >= 24) && (This->ID <= 29))
{
    printf("%d", This->ID - 20);
    nextRun(This, 2000);
}
#endif
#endif 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 14 cells to a GOAL.");
        printf("%nFor the <1> course, You click a 'R' button.");
        printf("%nFor the <2> course, You click a 'L' button.");
#endif
#endif

        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(Pannel, "%n");

        Printf(Pannel, "Thread Ready GO!");

        /* 2秒待機 */

        countUpNextRun(This, 2000);
    }
}

```

```

    }
    else if(This->count == 2)
    {
#ifdef 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)
    {
#ifdef 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(Pannel, "GOAL!<1>WON  ");
    }
    else if(i_cnt == 2)
    {
        Printf(Pannel, "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

#ifdef USE_LINUX
    This->count = 15;
#else
    This->count++;
#endif

    /* 2秒待機 */
    nextRun(This, 2000);
}
else if(This->count == 5)
{
    Clear();
    Printf(Pannel, "NEXT    ");
    /* 2秒待機 */
    countUpNextRun(This, 2000);
}

```

```

}
else if(This->count == 6)
{
    Clear();
    /* 第2部分 */
    Printf(Pannel, "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(Pannel, "NEXT ");
    /* 2秒待機 */
    countUpNextRun(This, 2000);
}
else if(This->count == 11)
{
    Clear();
    /* 第3部分 */
    Printf(Pannel, "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(Pannel, "NEXT    ");
    /* 2秒待機 */
    countUpNextRun(This, 2000);
}
else if(This->count == 16)
{
    Clear();
    /* 第4部分 */
    Printf(Pannel, "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);
    th44 = new_Thread(44);

#ifdef USE_LINUX
    th45 = new_Thread(45);
#endif

    delete_(This);

    /* LEDTEST */
    delete_(Thread_getThread(30));
}
}
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, 110);
    OnPuls(&puls, This);
}

```

```

    }

    else if(This->ID == 44)
    {
        nextRun(This, 2000);
        OnSimulator(&simu, This);
    }

#ifdef USE_LINUX
    else if(This->ID == 45)
    {
        nextRun(This, 2000);
        OnLog(&lg, This);
    }
#endif

    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);
}
#endif 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, 110);
        EV_Puls(&puls, This);
    }
    else if(This->ID == 44)
    {
        nextRun(This, 2000);
    }

```

```
        EV_Simulator(&simu, This);
    }
#ifdef USE_LINUX
    else if(This->ID == 45)
    {
        nextRun(This,1);
        EV_Log(&lg);
    }
#endif
    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(Pannel, "<1>Destroy");
    }
    else if(This->ID == 12)
    {
        Printf(Pannel, "<2>Destro");
    }
    else if(This->ID == 13)
    {
        Printf(Pannel, "<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

#ifdef USE_LINUX

    else if(This->ID == 45)
    {
        delete_EV_Log(&lg);
    }

#endif

    return;
}

#endif

#ifdef 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


```
drop database if exists ev001;
```

```
create database ev001;
```

```
use ev001;
```

```
GRANT SELECT ON ev001.* TO pi@localhost IDENTIFIED BY 'raspberry';
```

```
GRANT UPDATE ON ev001.* TO pi@localhost IDENTIFIED BY 'raspberry';
```

```
GRANT INSERT ON ev001.* TO pi@localhost IDENTIFIED BY 'raspberry';
```

```
GRANT DELETE ON ev001.* TO pi@localhost IDENTIFIED BY 'raspberry';
```

```
DROP TABLE IF EXISTS s_log;
```

```
CREATE TABLE s_log (
```

```
lg_ymd decimal(8) not null comment '日付',
```

```
lg_hms decimal(6) not null comment '時刻',
```

```
lg_safety varchar(1) not null comment '安全スイッチ',
```

```
lg_limit varchar(9) not null comment 'リミットスイッチ',
```

```
lg_command varchar(1) not null comment '命令入力',
```

```
lg_permitcommand varchar(1) not null comment '命令許可',
```

```
lg_permitturnopen varchar(1) not null comment '反転開許可',
```

```
lg_motor varchar(1) not null comment 'モーター出力',
```

```
PRIMARY KEY(lg_ymd,lg_hms)
```

```
)
```

```
ENGINE = INNODB
```

```
Default Charset = UTF8
```

```
COLLATE = UTF8_BIN
```

```
COMMENT='ログ'
```

```
;
```

An EV is stopped emergency!

```
-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_Display.obj
EV_Input.obj EV_Controller.obj EV_Puls.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_Puls.h EV_Controller.h EV_Input.h EV_Display.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_Display.h EV_File.h EV_Time.h Timer.h Panel.h C.h
    $(CC) $(CFLAGS) -c EV_Simulator.c
EV_Puls.obj : EV_Puls.c EV_Puls.h EV_File.h EV_Time.h Timer.h Panel.h C.h
    $(CC) $(CFLAGS) -c EV_Puls.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_File.h EV_Time.h Timer.h Panel.h C.h
    $(CC) $(CFLAGS) -c EV_Input.c
EV_Display.obj : EV_Display.c EV_Display.h EV_File.h EV_Time.h Timer.h Panel.h C.h
    $(CC) $(CFLAGS) -c EV_Display.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
```

```
; C言語の関数 を参照
```

```
.IMPORT _main ; C言語の関数main を参照
```

```
.IMPORT _usb_int ; C言語の関数usb_int を参照
```

```
.IMPORT _InterruptITU0 ; C言語の関数InterruptITU0 を参照
```

```
;-----
```

```
; リセットベクタ の 転送先ラベル が _start になっています
```

```
; リセットベクタ
```

```
.DATA.L _start
```

```
;-----
```

```
; リセットベクタ に続く1番から60番までの 割り込みベクタ
```

```
; について、使用しない 割り込みベクタ は ラベルint_error
```

```
; に転送されます
```

```
; 割り込みベクタ
```

```
; 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
; タイマ0割り込み は、 ラベル_ITU_OVI_0 に転送されます
; 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 のラベルから処理を開始
```

```
; リセットベクタの転送先
```

```
_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:
```

```
; 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
```

```
jsr @_main
```

```
; 割り込み未使用
```

```
int_error:
```

```
; rte (returnと同じ意味)で終了
```

```
rte
```

;------

; USB割り込み からの転送先

usb_interrupt:

; スタック 退避

push.l er0

push.l er1

push.l er2

push.l er3

push.l er4

push.l er5

push.l er6

; C言語の関数usb_int を呼び出しています

jsr @_usb_int

; スタック 戻

pop.l er6

pop.l er5

pop.l er4

pop.l er3

pop.l er2

pop.l er1

pop.l er0

; 終了

rte

;------

; タイマ0割り込み からの転送先

_ITU_OVI_0:

; スタック 退避

push.l er0

push.l er1

push.l er2

push.l er3

push.l er4

push.l er5

push.l er6

; 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

jsr @_InterruptITU0

; スタック戻

pop.l er6

pop.l er5

pop.l er4

pop.l er3

pop.l er2

pop.l er1

pop.l er0

; 終了

rte

;-----

; 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
; 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_Puls, EV_Controller, EV_Input, EV_Display, 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=%asih8cDir%;%asih8asmDir%;%path%
set CurrentDir="%~dp0"
cd %CurrentDir%
del error.txt
make -f makefile.mak >> error.txt
make -f makefile.mak clean >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% usb.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% sci.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% lcd.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% Panel.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% Timer.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Time.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_File.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_UpDown.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_OpenClose.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Display.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Input.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Controller.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Puls.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% EV_Simulator.c >> error.txt
cc38h.exe -cpu=300ha -include=%asih8cDir% main.c >> error.txt
a38h.exe asmfile.src >> error.txt
l38h.exe -subcommand=linkfile.sub >> error.txt
c38h.exe c_thread.abs >> 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 CentOSBuild.bash
rm ./CentOSError.txt
gcc -D"USE_CENTOS" -Wall -o CentOSExe.out main.c EV_Log.c EV_Simulator.c EV_Puls.c EV_Controller.c
EV_Input.c EV_Display.c EV_OpenClose.c EV_UpDown.c EV_File.c EV_Time.c Timer.c Panel.c -
I/usr/include/mysql -L/usr/lib/mysql -lmysqlclient &>>./CentOSError.txt
exit
```

```
#!/bin/bash
cd `dirname $0`
find $PWD -name CentOSStart.bash
./CentOSExe.out
exit
```

```
#!/bin/bash
cd `dirname $0`
find $PWD -name RaspberryPi3ModelBBuild.bash
rm ./RaspberryPi3ModelBError.txt
gcc -D"USE_RASPBIAN" -Wall -o RaspberryPi3ModelBExe.out main.c EV_Log.c EV_Simulator.c EV_Puls.c
EV_Controller.c EV_Input.c EV_Display.c EV_OpenClose.c EV_UpDown.c EV_File.c EV_Time.c Timer.c
Panel.c -I/usr/local/include -L/usr/local/lib -lwiringPi -lmariadbclient &>>./RaspberryPi3ModelBError.txt
exit
```

```
#!/bin/bash
cd `dirname $0`
find $PWD -name RaspberryPi3ModelBStart.bash
./RaspberryPi3ModelBExe.out
exit
```

実行環境状態ファイル

yynnyynn

N

出力ファイル

Start	Length	Name	Class
0001:00401000	000010C78H	_TEXT	CODE
0002:00412000	0000039A4H	_DATA	DATA
0003:004159A4	000000B70H	_BSS	BSS
0004:00000000	0000000A4H	_TLS	TLS

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PROGRAM NAME =

```
1          1 ; asmfile.src
2          2
3          3 .CPU 300HA
4 000000    4 .SECTION V,CODE,LOCATE=H'000000
5          5
6          6 ; C言語の関数 を参照
7          7 .IMPORT _main ; C言語の関数main を参照
8          8 .IMPORT _usb_int ; C言語の関数usb_int を参照
9          9 .IMPORT _InterruptIU0 ; C言語の関数InterruptIU0 を参照
10         10
11         11 ;-----
12         12 ; リセットベクタの転送先ラベルが _start になっています
13         13 ; リセットベクタ
14 000000 00000000    14 .DATA.L _start
15         15
16         16 ;-----
17         17 ; リセットベクタに続く1番から60番までの割り込みベクタ
18         18 ; について、使用しない割り込みベクタはラベルint_error
19         19 ; に転送されます
20         20 ; 割り込みベクタ
21         21 ; 1 Reserved
22 000004 00000000    22 _INT_Reserved1: .DATA.L int_error
23         23 ; 2 Reserved
24 000008 00000000    24 _INT_Reserved2: .DATA.L int_error
```

25	25	; 3 Reserved
26	00000C 00000000	26 _INT_Reserved3: .DATA.L int_error
27	27	; 4 Reserved
28	000010 00000000	28 _INT_Reserved4: .DATA.L int_error
29	29	; 5 Reserved
30	000014 00000000	30 _INT_Reserved5: .DATA.L int_error
31	31	; 6 Reserved
32	000018 00000000	32 _INT_Reserved6: .DATA.L int_error
33	33	; 7 NMI
34	00001C 00000000	34 _INT_NMI: .DATA.L int_error
35	35	; 8 TRAP
36	000020 00000000	36 _INT_TRAP1: .DATA.L int_error
37	37	; 9 TRAP
38	000024 00000000	38 _INT_TRAP2: .DATA.L int_error
39	39	; 10 TRAP
40	000028 00000000	40 _INT_TRAP3: .DATA.L int_error
41	41	; 11 TRAP
42	00002C 00000000	42 _INT_TRAP4: .DATA.L int_error
43	43	; 12 IRQ0
44	000030 00000000	44 IRQ0: .DATA.L int_error
45	45	; 13 IRQ1
46	000034 00000000	46 IRQ1: .DATA.L int_error
47	47	; 14 IRQ2
48	000038 00000000	48 IRQ2: .DATA.L int_error
49	49	; 15 IRQ3
50	00003C 00000000	50 IRQ3: .DATA.L int_error
51	51	; 16 IRQ4
52	000040 00000000	52 IRQ4: .DATA.L int_error
53	53	; 17 IRQ5

54 000044 00000000 54 IRQ5: .DATA.L usb_interrupt ; USB割り込み

55 55 ; 18 Reserved

56 000048 00000000 56 _INT_Reserved18: .DATA.L int_error

57 57 ; 19 Reserved

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PROGRAM NAME =

58 00004C 00000000 58 _INT_Reserved19: .DATA.L int_error

59 59 ; 20 WOVI

60 000050 00000000 60 _INT_WOVI: .DATA.L int_error

61 61 ; 21 CMI

62 000054 00000000 62 _INT_CMI: .DATA.L int_error

63 63 ; 22 Reserved

64 000058 00000000 64 _INT_Reserved22: .DATA.L int_error

65 65 ; 23 Reserved

66 00005C 00000000 66 _INT_Reserved23: .DATA.L int_error

67 67 ; 24 IMIA0

68 000060 00000000 68 _INT_IMIA0: .DATA.L int_error

69 69 ; 25 IMIB0

70 000064 00000000 70 _INT_IMIB0: .DATA.L int_error

71 71 ; タイマ0割り込みは、ラベル_ITU_OVI_0に転送されます

72 72 ; 26 OVIO

73 000068 00000000 73 _INT_OVIO: .DATA.L _ITU_OVI_0 ; タイマ0割り込み

74 74 ; 27 Reserved

75 00006C 00000000 75 _INT_Reserved27: .DATA.L int_error

76 76 ; 28 IMIA1

77 000070 00000000 77 _INT_IMIA1: .DATA.L int_error

78 78 ; 29 IMIB1

79	000074	00000000	79	_INT_IMIB1: .DATA.L int_error
80			80	;30 OVI1
81	000078	00000000	81	_INT_OVI1: .DATA.L int_error
82			82	;31 Reserved
83	00007C	00000000	83	_INT_Reserved31: .DATA.L int_error
84			84	;32 IMIA2
85	000080	00000000	85	_INT_IMIA2: .DATA.L int_error
86			86	;33 IMIB2
87	000084	00000000	87	_INT_IMIB2: .DATA.L int_error
88			88	;34 OVI2
89	000088	00000000	89	_INT_OVI2: .DATA.L int_error
90			90	;35 Reserved
91	00008C	00000000	91	_INT_Reserved35: .DATA.L int_error
92			92	;36 IMIA3
93	000090	00000000	93	_INT_IMIA3: .DATA.L int_error
94			94	;37 IMIB3
95	000094	00000000	95	_INT_IMIB3: .DATA.L int_error
96			96	;38 OVI3
97	000098	00000000	97	_INT_OVI3: .DATA.L int_error
98			98	;39 Reserved
99	00009C	00000000	99	_INT_Reserved39: .DATA.L int_error
100			100	;40 IMIA4
101	0000A0	00000000	101	_INT_IMIA4: .DATA.L int_error
102			102	;41 IMIB4
103	0000A4	00000000	103	_INT_IMIB4: .DATA.L int_error
104			104	;42 OVI4
105	0000A8	00000000	105	_INT_OVI4: .DATA.L int_error
106			106	;43 Reserved
107	0000AC	00000000	107	_INT_Reserved43: .DATA.L int_error

108 108 ;44 DEND0A
109 0000B0 00000000 109 _INT_DEND0A: .DATA.L int_error
110 110 ;45 DEND0B
111 0000B4 00000000 111 _INT_DEND0B: .DATA.L int_error
112 112 ;46 DEND1A
113 0000B8 00000000 113 _INT_DEND1A: .DATA.L int_error
114 114 ;47 DEND1B

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PROGRAM NAME =

115 0000BC 00000000 115 _INT_DEND1B: .DATA.L int_error
116 116 ;48 Reserved
117 0000C0 00000000 117 _INT_Reserved48: .DATA.L int_error
118 118 ;49 Reserved
119 0000C4 00000000 119 _INT_Reserved49: .DATA.L int_error
120 120 ;50 Reserved
121 0000C8 00000000 121 _INT_Reserved50: .DATA.L int_error
122 122 ;51 Reserved
123 0000CC 00000000 123 _INT_Reserved51: .DATA.L int_error
124 124 ;52 ERI0
125 0000D0 00000000 125 _INT_ERI0: .DATA.L int_error
126 126 ;53 RXI0
127 0000D4 00000000 127 _INT_RXI0: .DATA.L int_error
128 128 ;54 TXI0
129 0000D8 00000000 129 _INT_TXI0: .DATA.L int_error
130 130 ;55 TEI0
131 0000DC 00000000 131 _INT_TEI0: .DATA.L int_error

```

132          132 ;56 ERI1
133 0000E0 00000000      133  _INT_ERI1: .DATA.L int_error
134          134 ;57 RXI1
135 0000E4 00000000      135  _INT_RXI1: .DATA.L int_error
136          136 ;58 TXI1
137 0000E8 00000000      137  _INT_TXI1: .DATA.L int_error
138          138 ;59 TEI1
139 0000EC 00000000      139  _INT_TEI1: .DATA.L int_error
140          140 ;60 ADI
141 0000F0 00000000      141  _INT_ADI: .DATA.L int_error
142          142
143          143 ;-----
144 000000      144  .SECTION P,CODE,ALIGN=2
145          145 ;_start のラベルから処理を開始
146          146 ;リセットベクタの転送先
147 000000      147  _start:
148 000000 7A0700FFFF10    148  mov.l #H'0FFFF10,er7
149          149 ;初期化付きデータを使用する場合、RAMに転送する
150          150 ;c_thread.MAPのメモリアドレス使用状況を見る
151          151 ;メモリアドレスが重複するとコンパイルエラーになる
152          152 ;linkfile.subもD(99C0),C(9A00)等必要があれば合わせる
153 000006 7A00000099C0    153  mov.l #H'99C0,er0 ;転送元(99C0)
154 00000C 7A0100FFE000    154  mov.l #H'0FFE000,er1 ;転送先
155 000012 7A0200000000    155  mov.l #DATA_END,er2 ;転送終了
156 000018          156  init_loop:
157 000018 1F92          157  cmp.l er1,er2
158 00001A 58700008          158  beq init_end
159 00001E 6C0B          159  mov.b @er0+,r3l
160 000020 689B          160  mov.b r3l,@er1

```

```

161 000022 0B71      161  inc.l #1, er1
162 000024 40F2      162  bra init_loop
163 000026          163  init_end:
164          164  ;C言語の関数main を呼び出しています
165          165  ;C言語の関数main は、 void main(void); という形で、
166          166  ;main.c に記述があります
167 000026 5E000000      167  jsr @_main
168          168  ;割り込み未使用
169 00002A          169  int_error:
170          170  ;rte (returnと同じ意味) で終了
171 00002A 5670      171  rte

```

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PROGRAM NAME =

```

172          172
173          173  ;-----
174          174  ;USB割り込み からの転送先
175 00002C          175  usb_interrupt:
176          176  ;スタック 退避
177 00002C 01006DF0      177  push.l er0
178 000030 01006DF1      178  push.l er1
179 000034 01006DF2      179  push.l er2
180 000038 01006DF3      180  push.l er3
181 00003C 01006DF4      181  push.l er4
182 000040 01006DF5      182  push.l er5
183 000044 01006DF6      183  push.l er6
184          184  ;C言語の関数usb_int を呼び出しています
185 000048 5E000000      185  jsr @_usb_int

```

```

186          186 ;スタック戻
187 00004C 01006D76      187  pop.l er6
188 000050 01006D75      188  pop.l er5
189 000054 01006D74      189  pop.l er4
190 000058 01006D73      190  pop.l er3
191 00005C 01006D72      191  pop.l er2
192 000060 01006D71      192  pop.l er1
193 000064 01006D70      193  pop.l er0
194          194 ;終了
195 000068 5670          195  rte
196          196
197          197 ;-----
198          198 ;タイマ0割り込みからの転送先
199 00006A          199  _ITU_OVI_0:
200          200 ;スタック退避
201 00006A 01006DF0      201  push.l er0
202 00006E 01006DF1      202  push.l er1
203 000072 01006DF2      203  push.l er2
204 000076 01006DF3      204  push.l er3
205 00007A 01006DF4      205  push.l er4
206 00007E 01006DF5      206  push.l er5
207 000082 01006DF6      207  push.l er6
208          208 ;C言語の関数InterruptITU0 を呼び出しています
209          209 ;C言語の関数InterruptITU0 は void InterruptITU0(void);
210          210 ;という形で、Timer.h Timer.c に記述があります
211 000086 5E000000      211  jsr @_InterruptITU0
212          212 ;スタック戻
213 00008A 01006D76      213  pop.l er6
214 00008E 01006D75      214  pop.l er5

```

```

215 000092 01006D74      215  pop.l er4
216 000096 01006D73      216  pop.l er3
217 00009A 01006D72      217  pop.l er2
218 00009E 01006D71      218  pop.l er1
219 0000A2 01006D70      219  pop.l er0
220          220  ;終了
221 0000A6 5670          221  rte
222          222
223          223  ;-----
224          224  ;C言語から
225          225  ;_EnableInterrupt (割り込み許可)
226          226  ;_DisableInterrupt (割り込み禁止)
227          227  ;を呼び出せるようにしています
228          228  ;C言語の Panel.h に 外部参照プロトタイプ宣言 があります

```

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PROGRAM NAME =

```

229          229  ; extern void EnableInterrupt(void);
230          230  ; extern void DisableInterrupt(void);
231          231  ; C言語からの呼び出し名は、
232          232  ; EnableInterrupt();
233          233  ; DisableInterrupt();
234          234  ; です
235          235  ; 割り込み許可、禁止ルーチン
236          236  .EXPORT _EnableInterrupt,_DisableInterrupt
237 0000A8          237  _EnableInterrupt:
238 0000A8 063F          238  andc.b #H'3f,ccr

```

```

239 0000AA 5470      239   rts
240 0000AC          240   _DisableInterrupt:
241 0000AC 04C0     241   orc.b #H'c0,ccr
242 0000AE 5470     242   rts
243                243
244                244   ;-----
245 000000          245   .SECTION D,DATA
246                246
247 000000          247   .SECTION B,DATA
248 000000 00000002  248   DATA_END: .RES.W 1
249                249
250                250   .END

```

*****TOTAL ERRORS 0

*****TOTAL WARNINGS 0

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*** CROSS REFERENCE LIST

NAME	SECTION	ATTR	VALUE	SEQUENCE
B	B	SCT	00000000	247*
D	D	SCT	00000000	245*
DATA_END	B		00000000	155 248*
IRQ0	V		00000030	44*
IRQ1	V		00000034	46*
IRQ2	V		00000038	48*
IRQ3	V		0000003C	50*
IRQ4	V		00000040	52*

IRQ5	V	00000044	54*		
P	P	SCT 00000000	144*		
V	V	SCT 00000000	4*		
_DisableInterrupt		P EXPT 000000AC	236	240*	
_EnableInterrupt		P EXPT 000000A8	236	237*	
_INT_ADI	V	000000F0	141*		
_INT_CMI	V	00000054	62*		
_INT_DEND0A	V	000000B0	109*		
_INT_DEND0B	V	000000B4	111*		
_INT_DEND1A	V	000000B8	113*		
_INT_DEND1B	V	000000BC	115*		
_INT_ERI0	V	000000D0	125*		
_INT_ERI1	V	000000E0	133*		
_INT_IMIA0	V	00000060	68*		
_INT_IMIA1	V	00000070	77*		
_INT_IMIA2	V	00000080	85*		
_INT_IMIA3	V	00000090	93*		
_INT_IMIA4	V	000000A0	101*		
_INT_IMIB0	V	00000064	70*		
_INT_IMIB1	V	00000074	79*		
_INT_IMIB2	V	00000084	87*		
_INT_IMIB3	V	00000094	95*		
_INT_IMIB4	V	000000A4	103*		
_INT_NMI	V	0000001C	34*		
_INT_OVI0	V	00000068	73*		
_INT_OVI1	V	00000078	81*		
_INT_OVI2	V	00000088	89*		
_INT_OVI3	V	00000098	97*		
_INT_OVI4	V	000000A8	105*		

_INT_RXI0	V	000000D4	127*
_INT_RXI1	V	000000E4	135*
_INT_Reserved1	V	00000004	22*
_INT_Reserved18	V	00000048	56*
_INT_Reserved19	V	0000004C	58*
_INT_Reserved2	V	00000008	24*
_INT_Reserved22	V	00000058	64*
_INT_Reserved23	V	0000005C	66*
_INT_Reserved27	V	0000006C	75*
_INT_Reserved3	V	0000000C	26*
_INT_Reserved31	V	0000007C	83*
_INT_Reserved35	V	0000008C	91*
_INT_Reserved39	V	0000009C	99*
_INT_Reserved4	V	00000010	28*
_INT_Reserved43	V	000000AC	107*
_INT_Reserved48	V	000000C0	117*
_INT_Reserved49	V	000000C4	119*

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*** CROSS REFERENCE LIST

NAME	SECTION	ATTR	VALUE	SEQUENCE
_INT_Reserved5	V		00000014	30*
_INT_Reserved50	V		000000C8	121*
_INT_Reserved51	V		000000CC	123*
_INT_Reserved6	V		00000018	32*
_INT_TEIO	V		000000DC	131*

```

_INT_TEI1          V      000000EC  139*
_INT_TRAP1        V      00000020  36*
_INT_TRAP2        V      00000024  38*
_INT_TRAP3        V      00000028  40*
_INT_TRAP4        V      0000002C  42*
_INT_TXI0         V      000000D8  129*
_INT_TXI1         V      000000E8  137*
_INT_WOVI         V      00000050  60*
_ITU_OVI_0        P      0000006A  73 199*
_InterruptITU0    IMPT 00000000   9 211
_main             IMPT 00000000   7 167
_start           P      00000000  14 147*
_usb_int         IMPT 00000000   8 185
init_end         P      00000026  158 163*
init_loop        P      00000018  156* 162
int_error        P      0000002A  22 24 26 28 30 32 34 36 38 40 42 44
                 46 48 50 52 56 58 60 62 64 66 68 70
                 75 77 79 81 83 85 87 89 91 93 95 97
                 99 101 103 105 107 109 111 113 115 117 119 121
                 123 125 127 129 131 133 135 137 139 141 169*
usb_interrupt    P      0000002C  54 175*

```

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*** 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
S1130000000022A0000022A0000022A67
S1130010000022A0000022A0000022A2D
S1130020000022A0000022A0000022A1D
S10B0030000022A0000022A6D
S1130038000022A0000022A0000022C03
S1130048000022A0000022A0000022AF5
S1130058000022A0000022A0000022AE5
S10B0068000022A0000022AF5
S1130070000022A0000022A0000022ACD
S1130080000022A0000022A0000022ABD
S1130090000022A0000022A0000022AAD
S10B00A0000022A0000022AFD
S11300A8000022A0000022A0000022A95
S11300B8000022A0000022A0000022A85
S11300C8000022A0000022A0000022A75
S10B00D8000022A0000022AC5
S11300E0000022A0000022A0000022A5D
S10700F0000022ADD
S11302007A0700FFFF107A0000099C07A0100FF0F
S1130210E0007A0200FFE0101F92587000086C0B98
S1130220689B0B7140F25E0002B0567001006DF0E6
S113023001006DF101006DF201006DF301006DF439
S113024001006DF501006DF65E004F5001006D7603
S113025001006D7501006D7401006D7301006D7215
S113026001006D7101006D70567001006DF00100A9
S11302706DF101006DF201006DF301006DF40100F9
S11302806DF501006DF65E00493001006D760100E9
S11302906D7501006D7401006D7301006D720100D5
S11302A06D7101006D705670063F547004C0547038
S11302B05E0060667A37000000A790B000119338B
S11302C00FF47A0600FFE1E419550B5579257FFFA
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S11303605E0044147900001E5E00450A01006FF030
S113037000047900001F5E00450A0F8501006F70BD
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S10403905E0B
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S11303A11B0D305E00499E7A00000007D05E0044B9
S11303B1145E00497619550D505C000EAE0D0D0DFE
S11303C15117F10AC16819D90117D1660147540DB3
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S11303E1009A2C01006DF00FE05E0059080B970B8A
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S1130B6C01006FE000120FC10FE05E0044A65A00B3
S1130B7C0E0201006F6000127A2000000005461C73
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S1130BCC44EA5A000E0201006F6000127A20000002
S1130BDC000746365E00497619DD0DD07910000BFF
S1130BEC5E00450A0DD217F210321032010078A0C4
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LINK COMMAND LINE

LNK -subcommand=linkfile.sub

LINK SUBCOMMANDS

OUTPUT c_thread
 PRINT c_thread
 INPUT asmfile, main, EV_Simulator, EV_Puls, EV_Controller, EV_Input, EV_Display, 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'000012BD	H'0000100E
		main	main
	H'000012BE	- H'0000177D	H'000004C0
		EV_Simulator	EV_Simulator
	H'0000177E	- H'00001AF9	H'0000037C
		EV_Puls	EV_Puls
	H'00001AFA	- H'00002475	H'0000097C
		EV_Controller	EV_Controller
	H'00002476	- H'00002DB3	H'0000093E
		EV_Input	EV_Input
	H'00002DB4	- H'00002E05	H'00000052
		EV_Display	EV_Display

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H'00002E06 - H'0000366D H'00000868
              EV_OpenClose          EV_OpenClose
H'0000366E - H'00003EB5 H'00000848
              EV_UpDown             EV_UpDown
H'00003EB6 - H'000042A9 H'000003F4
              EV_File               EV_File
H'000042AA - H'00004401 H'00000158
              EV_Time               EV_Time
H'00004402 - H'00004975 H'00000574
              Timer                 Timer
H'00004976 - H'00004ACB H'00000156
              Panel                 Panel
H'00004ACC - H'00004B9D H'000000D2
              sci                   sci
H'00004B9E - H'00004DDB H'0000023E
              lcd                   lcd
H'00004DDC - H'000058CD H'00000AF2
              usb                   usb
H'000058CE - H'00005907 H'0000003A
              rand                  rand
H'00005908 - H'00005965 H'0000005E
              sprintf               sprintf
H'00005966 - H'0000598F H'0000002A
              strcmp                strcmp

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*** LINKAGE EDITOR LINK MAP LIST ***

SECTION NAME	START - END	LENGTH
	UNIT NAME	MODULE NAME

ATTRIBUTE : CODE NOSHR

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	H'000059AC - H'000059C7	H'0000001C
	strlen	strlen
	H'000059C8 - H'000059F7	H'00000030
	vsprintf	vsprintf
	H'000059F8 - H'00005CD1	H'000002DA
	add3	add3
	H'00005CD2 - H'00005F03	H'00000232
	divd3	divd3
	H'00005F04 - H'00005F7D	H'0000007A
	dtoa3	dtoa3
	H'00005F7E - H'00005F89	H'0000000C
	eqd3	eqd3
	H'00005F8A - H'00005F99	H'00000010
	ged3	ged3
	H'00005F9A - H'00005FA9	H'00000010
	ltd3	ltd3
	H'00005FAA - H'00005FEF	H'00000046

	ltod3		ltod3
H'00005FF0	- H'0000600D	H'0000001E	
	mv83		mv83
H'0000600E	- H'00006035	H'00000028	
	mvn3		mvn3
H'00006036	- H'00006043	H'0000000E	
	ned3		ned3
H'00006044	- H'00006065	H'00000022	
	spregld3		spregld3
H'00006066	- H'0000608D	H'00000028	
	spregsv3		spregsv3
H'0000608E	- H'00007E3B	H'00001DAE	
	_fmtout		_fmtout
H'00007E3C	- H'00007EF7	H'000000BC	
	cmpd3		cmpd3
H'00007EF8	- H'00007F1D	H'00000026	
	divl3		divl3
H'00007F1E	- H'00007F3D	H'00000020	
	mull3		mull3
H'00007F3E	- H'00008323	H'000003E6	
	_dti		_dti
H'00008324	- H'000084C7	H'000001A4	
	_its		_its
H'000084C8	- H'00008521	H'0000005A	
	memcpy		memcpy
H'00008522	- H'0000855D	H'0000003C	
	divul3		divul3

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*** LINKAGE EDITOR LINK MAP LIST ***

SECTION NAME	START	-	END	LENGTH	MODULE NAME
	UNIT NAME		UNIT NAME		MODULE NAME

ATTRIBUTE : CODE NOSHR

P	H'0000855E	-	H'00008585	H'00000028	
	_allzero				_allzero
	H'00008586	-	H'0000867D	H'000000F8	
	_calcnpw				_calcnpw
	H'0000867E	-	H'00008721	H'000000A4	
	_log10				_log10
	H'00008722	-	H'00008799	H'00000078	
	_lsfts				_lsfts
	H'0000879A	-	H'000087C7	H'0000002E	
	_pow5				_pow5
	H'000087C8	-	H'00008841	H'0000007A	
	_rsfts				_rsfts
	H'00008842	-	H'000088ED	H'000000AC	
	_sub				_sub
	H'000088EE	-	H'00008991	H'000000A4	
	_unpack				_unpack

```

H'00008992 - H'000089CF H'0000003E
             memcmp             memcmp
H'000089D0 - H'00008A57 H'00000088
             _mult64           _mult64
H'00008A58 - H'00008BB9 H'00000162
             _power            _power
H'00008BBA - H'00008CA3 H'000000EA
             _rnd              _rnd
H'00008CA4 - H'00008D3F H'0000009C
             _setsbit          _setsbit
H'00008D40 - H'00008E45 H'00000106
             frexp             frexp
H'00008E46 - H'00008F7B H'00000136
             modf              modf
H'00008F7C - H'00008F9D H'00000022
             dslc3             dslc3
H'00008F9E - H'00008FBF H'00000022
             dsruc3            dsruc3
H'00008FC0 - H'00008FF5 H'00000036
             itod3             itod3
H'00008FF6 - H'000092E3 H'000002EE
             muld3             muld3
H'000092E4 - H'00009335 H'00000052
             _duchek           _duchek
H'00009336 - H'00009387 H'00000052
             _lsft             _lsft
H'00009388 - H'00009515 H'0000018E
             _mult             _mult
H'00009516 - H'000095B1 H'0000009C
             _pow10            _pow10

```

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*** LINKAGE EDITOR LINK MAP LIST ***

SECTION NAME	START	END	LENGTH
	UNIT NAME	MODULE NAME	

ATTRIBUTE : CODE NOSHR

P	H'000095B2	- H'000095F9	H'00000048
		_add	_add
	H'000095FA	- H'00009629	H'00000030
		memset	memset

* TOTAL ADDRESS * H'00000200 - H'00009629 H'0000942A

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'00009C84 H'00000285
main main
H'00009C86 - H'00009CB4 H'0000002F
EV_Simulator EV_Simulator
H'00009CB6 - H'00009CC0 H'0000000B
EV_Puls EV_Puls
H'00009CC2 - H'00009CE9 H'00000028
EV_Controller EV_Controller
H'00009CEA - H'00009D4F H'00000066
EV_Input EV_Input
H'00009D50 - H'00009E0F H'000000C0
EV_Display EV_Display
H'00009E10 - H'00009E5B H'0000004C
EV_OpenClose EV_OpenClose
H'00009E5C - H'00009E9E H'00000043
EV_UpDown EV_UpDown
H'00009EA0 - H'00009F11 H'00000072
EV_File EV_File
H'00009F12 - H'00009F19 H'00000008
EV_Time EV_Time
H'00009F1A - H'00009F51 H'00000038
Timer Timer
H'00009F52 - H'00009F5C H'0000000B
Panel Panel
H'00009F5E - H'0000A017 H'000000BA
usb usb

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*** LINKAGE EDITOR LINK MAP LIST ***

SECTION NAME START - END LENGTH
UNIT NAME MODULE NAME

ATTRIBUTE : DATA NOSHR

C H'0000A018 - H'0000A01F H'00000008
_fmtout _fmtout
H'0000A020 - H'0000A11F H'00000100
_ctype _ctype
H'0000A120 - H'0000A1A7 H'00000088
_its _its
H'0000A1A8 - H'0000A1AF H'00000008
_log10 _log10
H'0000A1B0 - H'0000A28F H'000000E0
_pow5 _pow5


```

H'0000A290 - H'0000A393 H'00000104
              _power                _power
H'0000A394 - H'0000A39B H'00000008
              frexp                  frexp
H'0000A39C - H'0000A3A3 H'00000008
              modf                   modf

```

* TOTAL ADDRESS * H'00009A00 - H'0000A3A3 H'000009A4

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'00FFE223 H'00000212
              main                   main
H'00FFE224 - H'00FFE237 H'00000014
              EV_File                EV_File
H'00FFE238 - H'00FFE497 H'00000260
              Timer                  Timer
H'00FFE498 - H'00FFE517 H'00000080
              Panel                  Panel
H'00FFE518 - H'00FFE567 H'00000050
              sci                    sci
H'00FFE568 - H'00FFE5A7 H'00000040
              lcd                    lcd

```

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*** LINKAGE EDITOR LINK MAP LIST ***

SECTION NAME	START	END	LENGTH
	UNIT NAME	UNIT NAME	MODULE NAME

ATTRIBUTE : DATA NOSHR

```

B            H'00FFE5A8 - H'00FFE87B H'000002D4
              usb                    usb
H'00FFE87C - H'00FFE8B7 H'0000003C
              _fmtout                _fmtout
H'00FFE8B8 - H'00FFE8BB H'00000004
              _rnext                 _rnext
H'00FFE8BC - H'00FFE8BD H'00000002

```

_errno

_errno

* TOTAL ADDRESS * H'00FFE010 - H'00FFE8BD H'000008AE

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

SYMBOL NAME	ADDR	TYPE
\$ADDD\$3	H'00005AC2	DAT
\$CMPD\$3	H'00007E3C	DAT
\$DIVD\$3	H'00005D6C	DAT
\$DIVL\$3	H'00007EF8	DAT
\$DIVUL\$3	H'00008522	DAT
\$DSL\$3	H'00008F7C	DAT
\$DSRUC\$3	H'00008F9E	DAT
\$DTOL\$3	H'00005F04	DAT
\$EQD\$3	H'00005F7E	DAT
\$GED\$3	H'00005F8A	DAT
\$ITOD\$3	H'00008FC0	DAT
\$LTD\$3	H'00005F9A	DAT
\$LTOD\$3	H'00005FAA	DAT
\$MULD\$3	H'000090AC	DAT
\$MULL\$3	H'00007F1E	DAT
\$MV8\$3	H'00005FF0	DAT
\$MVN\$3	H'0000600E	DAT
\$NED\$3	H'00006036	DAT
\$SUBD\$3	H'00005A92	DAT
\$sp_regld\$3	H'00006044	DAT
\$sp_regsv\$3	H'00006066	DAT
_Checkfmove	H'000043C4	ENT
_Clear	H'00004976	ENT
_ClearLCD	H'00004CBC	ENT
_Close	H'00003626	ENT
_CloseMotor	H'000030DA	ENT
_Cnt	H'00FFE012	DAT
_Command_Read	H'000040C0	ENT
_Command_Write	H'0000410C	ENT
_Destroy	H'00001128	ENT
_DisableInterrupt	H'000002AC	DAT
_Disp	H'00002E04	ENT
_DispInput	H'00002DB4	ENT
_DispUSBPort	H'00004EEC	ENT
_Door	H'00002E06	ENT
_Down	H'00003E6E	ENT
_DownMotor	H'00003942	ENT
_EV_AddressDataSet	H'000018CE	ENT
_EV_AddressSet	H'000017EA	ENT
_EV_Controller	H'00001AFA	ENT
_EV_DataSet	H'0000185C	ENT
_EV_EnableSet	H'000017D4	ENT
_EV_File	H'00003F0A	ENT
_EV_Input	H'000024E2	ENT
_EV_Puls	H'0000199E	ENT

_EV_Set	H'0000177E	ENT
_EV_Simulator	H'000012BE	ENT
_EV_Time	H'000042AA	ENT
_EnableInterrupt	H'000002A8	DAT
_GetChar	H'00002476	ENT
_GetCurrentTime	H'0000430C	ENT

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

SYMBOL NAME	ADDR	TYPE
_GetPermit	H'000043A6	ENT
_GetSCI	H'00004AFC	ENT
_GetSW	H'0000126C	ENT
_H8init	H'00001292	ENT
_Init	H'00000E94	ENT
_InitITU	H'000048FA	ENT
_InitLCD	H'00004C4C	ENT
_InitSCI	H'00004ACC	ENT
_InitUSB	H'00004DF2	ENT
_InterruptITU0	H'00004930	ENT
_LCDOut4	H'00004BF4	ENT
_Limit_Read	H'00004266	ENT
_LocateLCD	H'00004CFC	ENT
_Motor_Read	H'00004218	ENT
_Motor_Write	H'000041E0	ENT
_OnCloseMotor	H'000030F6	ENT
_OnController	H'00001C9A	ENT
_OnDownMotor	H'0000395E	ENT
_OnInitWaitDoorChangeLog	H'00003362	ENT
_OnInitWaitPositionChangeLog	H'00003BBC	ENT
_OnInput	H'0000260E	ENT
_OnOpenMotor	H'00002E96	ENT
_OnPuls	H'000019DC	ENT
_OnSimulator	H'000013A8	ENT
_OnUpMotor	H'000036FE	ENT
_OnWaitCloseDoorChangeLog	H'0000350A	ENT
_OnWaitDownPositionChangeLog	H'00003D58	ENT
_OnWaitOpenDoorChangeLog	H'00003436	ENT
_OnWaitUpPositionChangeLog	H'00003C8A	ENT
_Open	H'000035DE	ENT
_OpenMotor	H'00002E7A	ENT
_PermitCommand_Read	H'00004030	ENT
_PermitCommand_Write	H'0000407C	ENT
_PermitTurnOpen_Read	H'00004150	ENT
_PermitTurnOpen_Write	H'0000419C	ENT
_Position	H'0000366E	ENT
_PrintF	H'0000499E	ENT
_PrintLCD	H'00004D20	ENT
_PrintSCI	H'00004B1C	ENT
_PutLCD	H'00004CD0	ENT
_PutSCI	H'00004AEC	ENT
_Read	H'00003F9E	ENT

_ReadString	H'00003FF8	ENT
_Repaint	H'000004C0	ENT
_Run	H'0000052C	ENT
_ScanSCI	H'00004B0C	ENT
_SetCurrentTime	H'000042EE	ENT
_SetLED	H'0000121E	ENT
_SetPermit	H'00004372	ENT
_SleepMSec	H'00004414	ENT
_Start	H'000046E6	ENT

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

SYMBOL NAME	ADDR	TYPE
_Stop	H'00004714	ENT
_Thread_Start	H'000047AC	ENT
_Thread_Toggle	H'000047EA	ENT
_Thread_checkAllDelete	H'00004732	ENT
_Thread_checkStayAnother	H'0000474C	ENT
_Thread_getThread	H'00004772	ENT
_Up	H'00003E26	ENT
_UpMotor	H'000036E2	ENT
_WaitDoorChangeLog	H'0000333A	ENT
_WaitPositionChangeLog	H'00003BA2	ENT
_WaitSecond	H'00004350	ENT
_Wait_ms	H'000043E6	ENT
_Write	H'00003F14	ENT
_WriteString	H'00003F66	ENT
__add	H'000095B2	ENT
__allzero	H'0000855E	ENT
__calcpw	H'00008586	ENT
__ctype	H'0000A020	DAT
__dti	H'00007F3E	ENT
__duchek	H'000092E4	ENT
__errno	H'00FFE8BC	DAT
__fmtout	H'0000608E	ENT
__its	H'00008324	ENT
__log10	H'0000867E	ENT
__lsft	H'00009336	ENT
__lsfts	H'00008722	ENT
__mult	H'00009388	ENT
__mult64	H'000089D0	ENT
__pow10	H'00009516	ENT
__pow5	H'0000879A	ENT
__power	H'00008A58	ENT
__rnd	H'00008BBA	ENT
__rnext	H'00FFE8B8	DAT
__rsfts	H'000087C8	ENT
__setsbit	H'00008CA4	ENT
__sub	H'00008842	ENT
__unpack	H'000088EE	ENT
_cntl	H'00FFE090	DAT
_countUpNextRun	H'000044EA	ENT

delete	H'000046B2	ENT
_frexp	H'00008D40	ENT
_getClock	H'00004402	ENT
_get_inbufflen	H'000058A6	ENT
_get_outbufflen	H'000058BA	ENT
_i_cnt	H'00FFE016	DAT
_in	H'00FFE052	DAT
_initWOVI	H'0000495C	ENT
_init_usbbuff	H'0000570A	ENT
_j_cnt	H'00FFE018	DAT
_main	H'000002B0	ENT
_memcpy	H'00008992	ENT

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

SYMBOL NAME	ADDR	TYPE
_memcpy	H'000084C8	ENT
_memset	H'000095FA	ENT
_modf	H'00008E46	ENT
_new_EV_Status	H'00003EB6	ENT
_new_Thread	H'0000450A	ENT
_nextRun	H'000044A6	ENT
_puls	H'00FFE188	DAT
_rand	H'000058CE	ENT
_read_buff	H'00005848	ENT
_read_outbuff	H'000057EA	ENT
_s	H'00FFE04E	DAT
_simu	H'00FFE19C	DAT
_sprintf	H'00005908	ENT
_status	H'00FFE224	DAT
_strcmp	H'00005966	ENT
_strcpy	H'00005990	ENT
_strlen	H'000059AC	ENT
_th	H'00FFE01A	DAT
_th1	H'00FFE022	DAT
_th101	H'00FFE27C	DAT
_th102	H'00FFE29A	DAT
_th111	H'00FFE2B8	DAT
_th112	H'00FFE2D6	DAT
_th113	H'00FFE2F4	DAT
_th114	H'00FFE312	DAT
_th119	H'00FFE330	DAT
_th120	H'00FFE34E	DAT
_th121	H'00FFE36C	DAT
_th122	H'00FFE38A	DAT
_th123	H'00FFE3A8	DAT
_th130	H'00FFE3C6	DAT
_th131	H'00FFE3E4	DAT
_th141	H'00FFE402	DAT
_th142	H'00FFE420	DAT
_th143	H'00FFE43E	DAT
_th144	H'00FFE45C	DAT

_th145	H'00FFE47A	DAT
_th19	H'00FFE032	DAT
_th20	H'00FFE036	DAT
_th41	H'00FFE03A	DAT
_th42	H'00FFE03E	DAT
_th43	H'00FFE042	DAT
_th44	H'00FFE046	DAT
_th45	H'00FFE04A	DAT
_usb_int	H'00004F50	ENT
_vsprintf	H'000059C8	ENT
_wovi	H'00004958	ENT
_woviClock	H'00FFE238	DAT
_woviInit	H'000048C8	ENT
_woviRun	H'0000482E	ENT
_woviThreadFirst	H'00FFE240	DAT

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

SYMBOL NAME	ADDR	TYPE
_woviThreadLast	H'00FFE25E	DAT
_write_buff	H'00005784	ENT
_write_inbuff	H'00005728	ENT

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

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

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:

```
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
```

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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_Display.c
```

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

EV_Display.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_Puls.c
```

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

EV_Puls.c:

警告 W8057 EV_Puls.c 53: パラメータ 'addressDataSet' は一度も使用されない(関数 EV_Set)

警告 W8057 EV_Puls.c 53: パラメータ 'dataSet' は一度も使用されない(関数 EV_Set)

警告 W8057 EV_Puls.c 53: パラメータ 'addressClockSet' は一度も使用されない(関数 EV_Set)

警告 W8057 EV_Puls.c 53: パラメータ 'clockSet' は一度も使用されない(関数 EV_Set)

警告 W8057 EV_Puls.c 182: パラメータ 'th' は一度も使用されない(関数 EV_Puls)

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

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

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
```

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

main.c:

警告 W8004 main.c 309: '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_Display.obj EV_Input.obj EV_Controller.obj EV_Puls.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_Puls, EV_Controller, EV_Input, EV_Display, 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

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