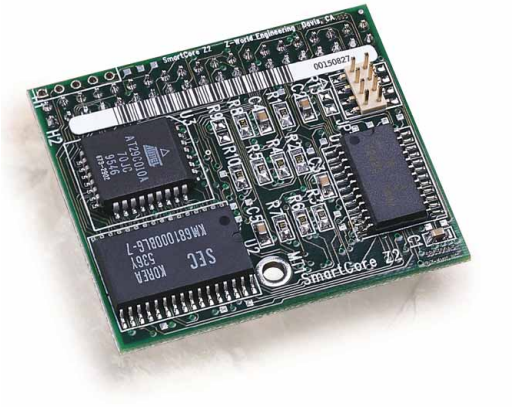

CM7000 Series

C-Programmable Core Module

User's Manual

Revision F

CM7000 Series Core Modules User's Manual

Part Number 019-0018 • Revision F
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When a system failure may cause serious consequences, protecting life and property against such consequences with a backup system or safety device is essential. The buyer agrees that protection against consequences resulting from system failure is the buyer's responsibility.

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All Z-World products are 100 percent functionally tested. Additional testing may include visual quality control inspections or mechanical defects analyzer inspections. Specifications are based on characterization of tested sample units rather than testing over temperature and voltage of each unit. Z-World may qualify components to operate within a range of parameters that is different than the manufacturer's recommended range. This strategy is believed to be more economical and effective. Additional testing or burn-in of an individual unit is available by special arrangement.

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ABOUT THIS MANUAL

This manual describes the CM7000 Series core modules, their subsystems, and the CM7100 Evaluation Kit. For ease of reference, this manual uses "CM7000" as a generic term referring to any of the CM7100 or CM7200 Series modules. "CM7100" refers to any of the CM7100 Series modules, and "CM7200" refers to the CM7200 Series. Specific models are referenced when appropriate.

Instructions are also provided for using Dynamic C functions.

Assumptions

Assumptions are made regarding the user's knowledge and experience in the following areas:

- Ability to design and engineer a target system that uses a CM7000.
- Understanding of the basics of operating a software program and editing files under Windows on a PC.
- Knowledge of the basics of C programming.

For a full treatment of C, refer to the following texts:

The C Programming Language by Kernighan and Ritchie
C: A Reference Manual by Harbison and Steel

- Knowledge of basic Z80 assembly language and architecture.

For documentation from Zilog, refer to the following texts:

Z180 MPU User's Manual
Z180 Serial Communication Controllers
Z80 Microprocessor Family User's Manual

Acronyms

Table 1 is a list of acronyms that may be used in this manual.

Table 1. Acronyms

Acronym	Meaning
EPROM	Erasable Programmable Read Only Memory
EEPROM	Electronically Erasable Programmable Read Only Memory
LCD	Liquid Crystal Display
LED	Light Emitting Diode
NMI	Nonmaskable Interrupt
PIO	Parallel Input / Output Circuit (Individually Programmable Input / Output)
PRT	Programmable Reload Timer
RAM	Random Access Memory
RTC	Real Time Clock
SIB	Serial Interface Board
SRAM	Static Random Access Memory
UART	Universal Asynchronous Receiver Transmitter

Icons

Table 2 displays and defines icons that may be used in this manual.

Table 2. Icons

Icon	Meaning	Icon	Meaning
	Refer to or see		Note
	Please contact		High Voltage
	Caution	Tip	Tip
	Factory Default		

Conventions

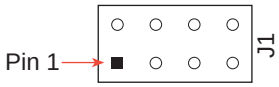
Table 3 lists and defines typographical conventions that may be used in this manual.

Table 3. Typographical Conventions

Example	Description
`while`	Courier font (bold) indicates a program, a fragment of a program, or a Dynamic C keyword or phrase.
`// IN-01…`	Program comments are written in Courier font, plain face.
Italics	Indicates that something should be typed instead of the italicized words (e.g., in place of *filename*, type a file's name).
Edit	Sans serif font (bold) signifies a menu or menu selection.
. . .	An ellipsis indicates that (1) irrelevant program text is omitted for brevity or that (2) preceding program text may be repeated indefinitely.
[ ]	Brackets in a C function's definition or program segment indicate that the enclosed directive is optional.
‹ ›	Angle brackets occasionally enclose classes of terms.
a | b | c	A vertical bar indicates that a choice should be made from among the items listed.

Pin Number 1

A black square indicates pin 1 of all headers.



Measurements

All diagram and graphic measurements are in inches followed by millimeters enclosed in parenthesis.

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CHAPTER 1: OVERVIEW

Introduction

The CM7000 is a microprocessor core module. The CM7000 combines a complete system engine with integrated development software. You build your own controller around the plug-in CM7000.

Features

- Small size: 1.80" × 2.05" (45.7 mm × 52.1 mm)
- Microprocessor: Z180 running at 9.216 MHz or 18.432 MHz, including two DMA channels, two serial ports, and two programmable timers (PRTs)
- SRAM: 32K or 128K (512K factory-installed SRAM is also available)
- EPROM:

  CM7100—32-pin DIP socket accommodates up to 512K EPROM

  CM7200—128K flash EPROM at 128 bytes/sector (256K factory-installed flash EPROM is also available)
- I/O support: six chip-select lines, supporting 64 addresses each, control the application's hardware
- Low electromagnetic interference
- Software written for either CM7100 or CM7200 Series is binary-compatible with the other

Options

The CM7000 is available with two types of memory—CM7100s have ROM and CM7200s have flash EPROM.

CM7100 Series

Table 1-1 lists the features of each model in the CM7100 Series.

Table 1-1. CM7100 Series Features

Model	Features
CM7100	18.432 MHz clock, 128K SRAM, 512-byte EEPROM, real-time clock, and ADM691 supervisor
CM7110	CM7100 with 9.216 MHz clock
CM7120	CM7100 with 9.216 MHz clock and 32K SRAM
CM7130	CM7100 with 9.216 MHz clock and 32K SRAM. Without ADM691 supervisor, real-time clock and EEPROM.

The CM7100 is available in one of the models listed in Table 1-1 or as part of the Evaluation Kit. The Evaluation Kit contains the following items.

- CM7110 with special EPROM containing sample programs.
- Prototyping Board.
- Manual (with schematics), cables, AC adapter, trial version of Dynamic C development software.

The trial version of Dynamic C included with the Evaluation Kit contains only the libraries associated with the Evaluation Kit. Once a decision is made to proceed with normal development, the standard or deluxe version of Dynamic C must be purchased. The Development Board supplied with the Developer's Kit and the development EPROM are also available for separate purchase.

For help with upgrading to a full-scale system, call your Z-World Sales Representative at (530) 757-3737.

A Developer's Kit is available for the CM7100. The Developer's Kit contains the following items.

- Development EPROM.
- Development Board, which plugs into the CM7100 EPROM socket to emulate ROM with RAM to make it easier to develop and debug large programs.
- Manual (with schematics), cables, and AC adapter.

A 128K EPROM and an LCD/Keypad module (the LCD/Keypad module requires a 9.216 MHz clock) are available separately.

Figure 1-1 shows the CM7100 board layout.

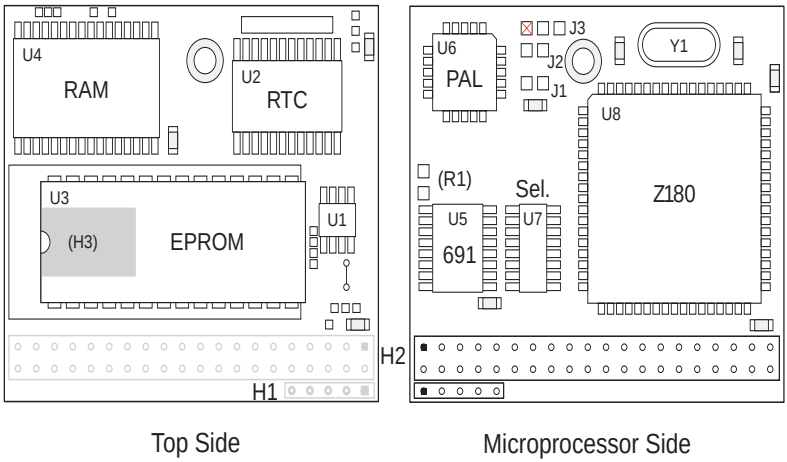

Figure 1-1. CM7100 Board Layout

CM7200 Series

Table 1-2 lists the features of each model in the CM7200 Series.

Table 1-2. CM7200 Series Features

Model	Features
CM7200	18.432 MHz clock, 128K SRAM, real-time clock, ADM691 supervisor, and 128K flash EPROM
CM7210	CM7200 with 9.216 MHz clock
CM7220	CM7200 with 9.216 MHz clock and 32K SRAM
CM7230	CM7200 with 9.216 MHz clock and 32K SRAM. Without ADM691 supervisor and real-time clock.

A Developer's Kit is available for the CM7200. The Developer's Kit contains the following items.

- Prototyping Board.
- Manual (with schematics), cables and AC adapter.
- Serial Interface Board 2.

The following optional accessories are available for the CM7200.

- Flash Programmer to program flash EPROM.
- 256K factory-installed flash EPROM.
- LCD/Keypad module (2 × 20 LCD and 2 × 6 keypad) for use with CM7200 modules with a 9.216 MHz clock.

Figure 1-2 shows the CM7200 board layout.

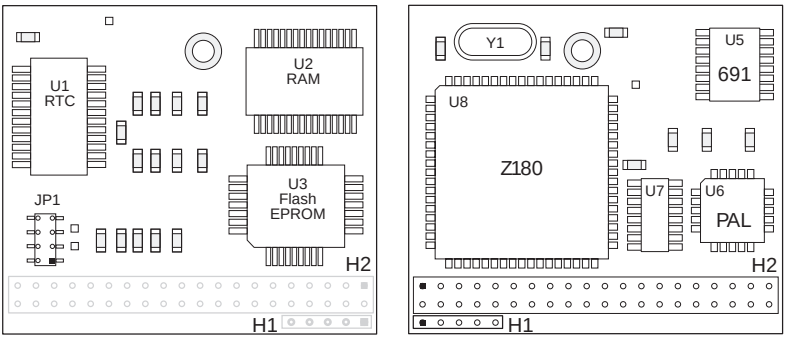

Figure 1-2. CM7200 Board Layout

Software Development and Evaluation Tools

Dynamic C, Z-World's Windows-based real-time C language development system, is used to develop software for the CM7000. The host PC downloads the executable code through the CM7000's RS-232 serial port or through the Serial Interface Board 2 to one of the following places:

- battery-backed RAM,
- ROM written on a separate EPROM programmer and then substituted for the Z-World development EPROM, or
- flash EPROM.

Dynamic C allows fast in-target development and debugging.

Z-World's Dynamic C reference manuals provide complete software descriptions and programming instructions.

For ordering information or more details about the various options and prices, call your Z-World Sales Representative at (530) 757-3737.

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CHAPTER 2: GETTING STARTED

Programming Setup

Dynamic C, Z-World's C-language development system, is used to develop applications for the CM7000. As a program compiles, Dynamic C downloads it directly to the CM7000's memory via one of the PC COM ports. Serial communication is normally at 19,200 bps, and can be as high as 57,600 bps. The CM7000 remains connected to the PC in most instances while a program is undergoing development. The mechanics of connecting a CM7000 and a PC vary depending on the CM7000 version and the programming strategy.

The programming strategy for a CM7100 depends on the hardware setup. Only one programming method is available for the CM7200 regardless of whether the Developer's Kit or in-target development is used.

CM7100

Four methods are available to program the CM7100.

1. Using the Prototyping Board. This method is recommended for programming the CM7110 supplied in the Evaluation Kit. This CM7110 has a special EPROM that contains the BIOS and sample programs.

   Method 1 may also be used to program other CM7100s. Since an EPROM is not normally included with CM7100s, except for the CM7110 in the Evaluation Kit, which comes with a special EPROM, a custom EPROM with the contents of the Dynamic C **2903.BIN** file must first be burned according to the details in the section "Programming EPROMs" in Chapter 3, "System Development."

2. Using the Development Board. The Development Board is included in the Developer's Kit with full Dynamic C, and is also sold separately.

3. Using the Development Board with full Dynamic C, and with the CM7100 embedded in your target system.

4. Directly in your system without a Development Board. This method requires some hardware setup and minor modifications to the Dynamic C EPROM code.

Methods 1 and 2 are normally used for evaluation or experimentation. Method 3 requires some hardware setup, and ultimately must be used to program a working system. Method 4 can be the fastest and most powerful.

Once program development has been completed, recompile the program for EPROM. An EPROM is burned in a separate operation and is then installed in the EPROM socket on the CM7100.

CM7100 Method 1 — Prototyping Board

1. Check to make sure the power to the Prototyping Board is ***not*** connected.
2. Check header J3 on the microprocessor side of the CM7100. The surface-mounted jumper should connect pins 2–3 to reflect the 128K memory of the special EPROM. This factory default setting is shown in Figure 2-1.

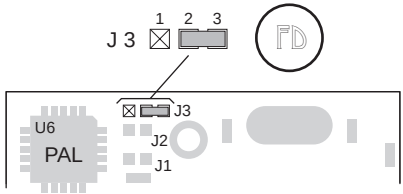


Figure 2-1. CM7100 Header J3 Configured for Special EPROM

3. Plug the CM7100 into the Prototyping Board as shown in Figure 2-2. Plug header H2 of the CM7100 into connector H3 of the Prototyping Board. Pins 1 of the header and connector must match. The CM7100 will hang over the battery on the Prototyping Board. For maximum stability, install the supplied standoff between the CM7100 and the Prototyping Board.

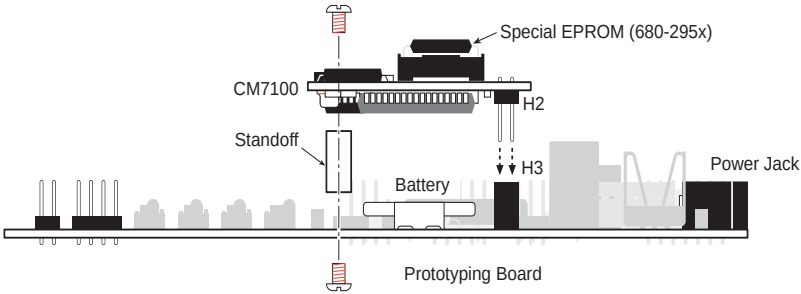


Figure 2-2. Connecting CM7100 to Prototyping Board

4. If using the CM7110 from the Evaluation Kit, make sure the CM7110 has the special 32-pin EPROM (Z-World part number 680-295x) installed at U3 as shown in Figure 2-3. Custom-burned EPROM are also installed at location U3.

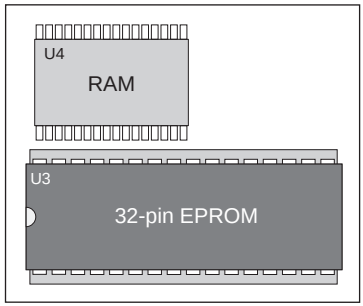


Figure 2-3. Installation of 32-pin EPROM

5. Place jumpers across headers J2, J3, and J4 on the Prototyping Board to enable headers J6–J11 on the Prototyping Board. The Prototyping Board is shown in Figure 2-4.

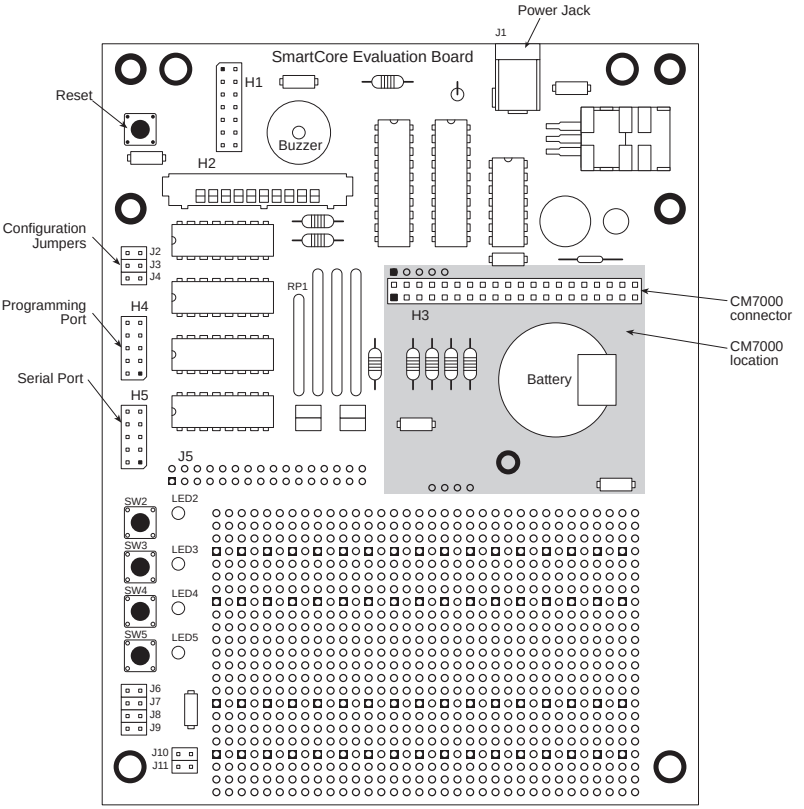


Figure 2-4. CM7100 Prototyping Board

It is necessary to place jumpers across headers J2, J3, and J4 to enable headers J6–J11 on the Prototyping Board. Note that this disables chip selects CS1, CS2, and CS3. The LEDs will not work when CS1 is disabled.

The BIOS on the special EPROM (Z-World part number 680-295x) supplied with the CM7110 in the Evaluation Kit does not support chip selects CS1, CS2, and CS3.

6. Set the Prototyping Board's jumpers. Jumpers across headers J10 and J11 affect the operational mode and the baud rate as shown in Figure 2-5. When both headers J10 and J11 are jumpered, the CM7100 checks headers J6–J9 at startup. If none of these headers is jumpered, the CM7100 will execute the program, if any, stored in RAM. If some of these headers are jumpered, a sample program stored in the special CM7100 EPROM will begin executing.

See Appendix F, "Prototyping Board," for more information on the Prototyping Board and the sample programs in the special EPROM.

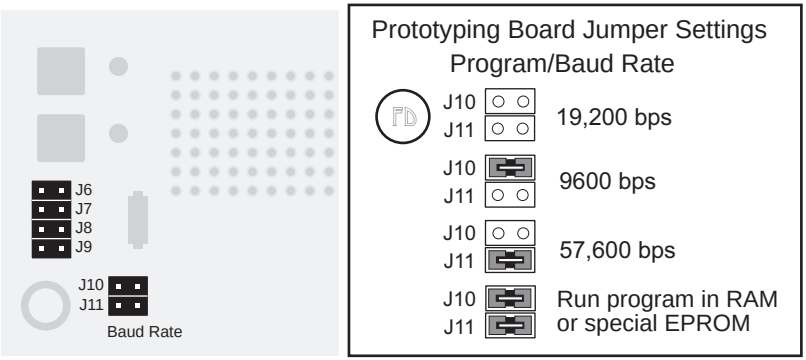


Figure 2-5. CM7100 Prototyping Board Program/Mode Jumper Settings

7. Connect the serial cable. Connect one end to the PC COM port. Then connect the 10-pin end to header H4 of the Prototyping Board as shown in Figure 2-6. Be careful to match the arrow on the connector to the location of pin 1 on header H4.
8. Apply power from the 9 V power supply to the Prototyping Board. The CM7100 is ready for programming, unless the jumpers were set in Step 6 to run a program stored in RAM or to run one of the sample programs stored in the special EPROM.

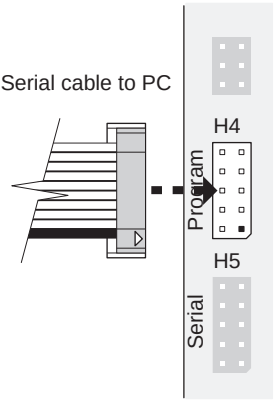


Figure 2-6. Serial Cable Connection to CM7100 Prototyping Board

CM7100 Method 2 — Development Board

1. Check to make sure the power to the Prototyping Board is ***not*** connected.
2. Check header J3 on the microprocessor side of the CM7100. The surface-mounted jumper should connect pins 2–3 to use the Development Board. This factory default setting is shown in Figure 2-1.
3. Plug the CM7100 into the Prototyping Board as shown in Figure 2-7. Plug header H2 of the CM7100 into connector H3 of the Prototyping Board. Pins 1 of the header and connector must match. The CM7100 will hang over the battery on the Prototyping Board. For maximum stability, install the supplied standoff between the CM7100 and the Prototyping Board.

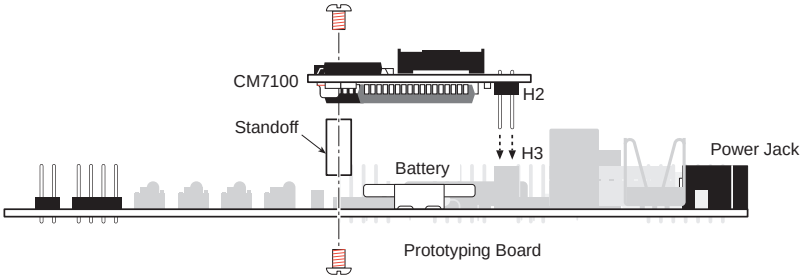


Figure 2-7. Connecting CM7100 to Prototyping Board

4. If an EPROM is installed in socket U3 on the CM7100, remove the EPROM. Plug a Dynamic C development EPROM (Z-World part number 680-290x) into the EPROM socket (U3) of the Development Board. See Figure 2-8.

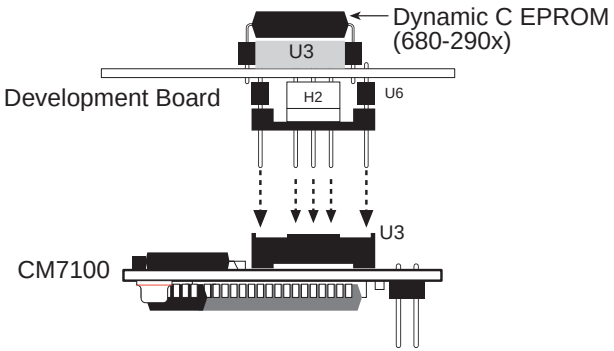


Figure 2-8. Installation of CM7100 Development Board and Development EPROM

5. Plug the Development Board into the EPROM (U3) and H3 sockets on the CM7100 as shown in Figure 2-8. Headers U6 and H2 on the underside of the Development Board must match the CM7100 EPROM and H3 sockets exactly.

> Be careful! The U6 and H2 pins on the Development Board are delicate and bend easily.

6. Check the jumpers on the Development Board. Figure 2-9 shows the locations of the relevant headers.

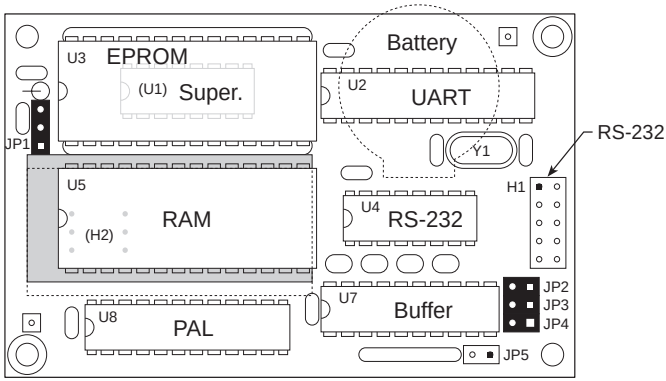


Figure 2-9. CM7100 Development Board

Figure 2-10 shows the jumper settings for different RAM sizes, operational modes, and baud rates.

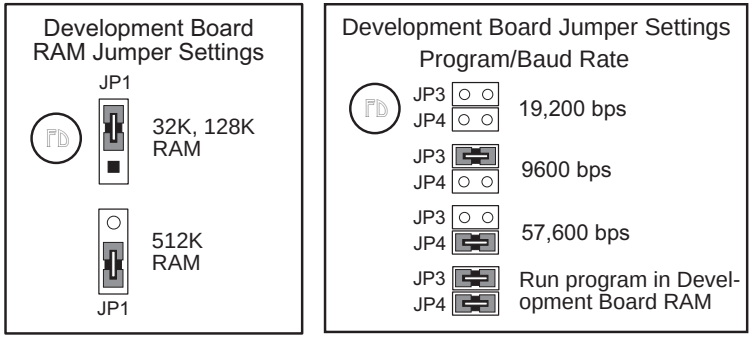


Figure 2-10. CM7100 Development Board Jumper Settings

7. If you are using a 28-pin RAM chip, seat the chip in the RAM socket as shown in Figure 2-11.

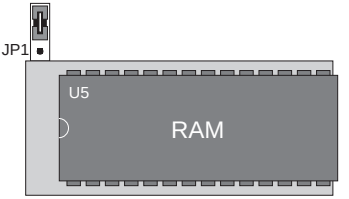


Figure 2-11. Position of 28-Pin Chip in 32-Pin Socket

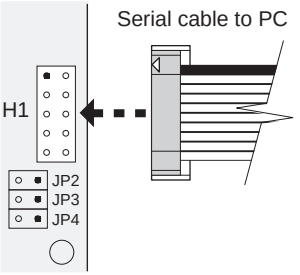


Figure 2-12. Serial Cable Connection to CM7100 Development Board

8. Connect the serial cable. Connect one end to the PC COM port. Then connect the 10-pin end to H1 of the Development Board as shown in Figure 2-12. Be careful to match the arrow on the connector to the location of pin 1 on header H1.

9. Reconnect the 9 V power supply to the Prototyping Board. The CM7100 is ready for programming, unless the jumpers were set in Step 5 to run a program in the Development Board's RAM.

CM7100 Method 3 — Embedded in System

Method 3 assumes that the CM7100 is already mounted in a system and that the CM7100 is properly connected. At a minimum, regulated power (+5 V) and ground must be provided.

The Development Board plugs into the EPROM socket of the CM7100. The Development Board emulates the system EPROM normally installed in the CM7100, providing up to 504K of program space in addition to the RAM on the CM7100 (used as a data space). The Development Board has its own RS-232 port and communicates directly with the PC during program development.

1. Disconnect power from the CM7100.
2. If an EPROM is installed in socket U3 on the CM7100, remove the EPROM. Plug a Dynamic C development EPROM (Z-World part number 680-290x) into the EPROM socket (U3) of the Development Board. See Figure 2-8.
3. Plug the Development Board into the EPROM (U3) and H3 sockets on the CM7100 as shown in Figure 2-8. Headers U6 and H2 on the underside of the Development Board must match the CM7100 EPROM and H3 sockets exactly.

Be careful! The U6 and H2 pins on the Development Board are delicate and bend easily.

4. Check header J3 on the microprocessor side of the CM7100. The surface-mounted jumper should connect pins 2–3 to use the Development Board. This factory default setting is shown in Figure 2-1.
5. Check the jumpers on the Development Board. Figure 2-9 shows the locations of the relevant headers.

   Figure 2-10 shows the jumper settings for different RAM sizes, and for the operational mode and baud rates.
6. If you are using a 28-pin RAM chip, seat the chip in the RAM socket as shown in Figure 2-11.
7. Connect the serial cable. Connect one end to the PC COM port. Then connect the 10-pin end to H1 of the Development Board as shown in Figure 2-12. Be careful to match the arrow on the connector to the location of pin 1 of H1.
8. Reconnect power to the CM7100. The CM7100 is ready for programming, unless the jumpers were set in Step 5 to run a program stored in the Development Board RAM.

CM7100 Method 4 — In-Target Direct Development

It is possible to program directly through a CM7100's built-in serial port without using a Development Board. In this method, the program is held in RAM while the application is under development. At least 128K of RAM is highly recommended. Note that the CTS0 input must be asserted for channel z0 to transmit. Tie CTS0 to ground if RTS/CTS handshake support is not needed.

1. Build an input port into your hardware using one of the **/CS** lines. One bit of the input will specify whether the Dynamic C monitor in the EPROM enters RUN mode or PROGRAM mode.
2. Build a serial driver into your system based on the one on the Prototyping Board (see Figure 2-13).

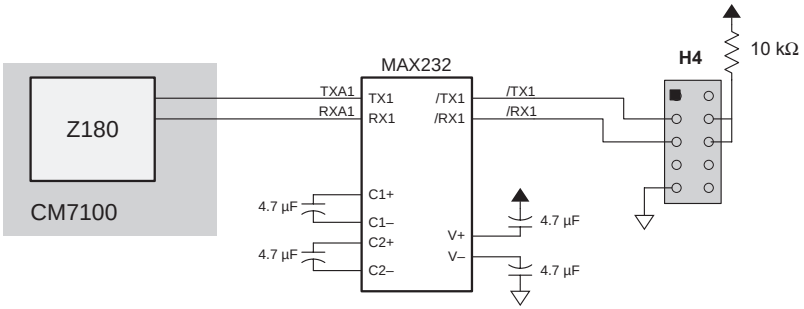


Figure 2-13. CM7100 Prototyping Board Serial Driver

If your serial driver has a 10-pin header that conforms to Z-World's programming cable, you will not need to build another programming cable. CTS and RTS are tied together and pulled up.

3. Six bytes of the Dynamic C EPROM (starting at 0x70 in the EPROM file) are reserved as indicated in Table 2-1.

Table 2-1. Dynamic C EPROM Addresses

Address	Name	Range	Meaning
0x70	channel	0,1	Selects serial programming port.
0x71	baud rate	1–48	Programming baud rate in multiples of 1200 bps: 8 = 9600 bps, 16 = 19,200 bps, 48 = 57,600 bps).
0x72,73	address	0x4000 to 0x417F	Address of input port (corresponds to /CS line), low-order bits in byte 72.
0x74	mask	0x0–FF	Active bit(s) of input byte, one bit suffices.
0x75	polarity	0,1	Polarity of input bit.

Modify the Dynamic C EPROM file (in your Dynamic C directory) and burn a new EPROM with the appropriate new data.

When a system resets, the Dynamic C monitor in the EPROM consults the 6 bytes. If the monitor finds valid data, the system will start operating according to the data. The monitor will attempt to read the specified input port. If it is successful, the monitor will either enter programming mode (communicating with Dynamic C in a PC) or run the program stored in the CM7100's RAM.

For example, the C structure

(70)	0x00	serial channel 0
(71)	0x10	19,200 bps
(72,73)	0x4040	/CS2
(74)	0x80	active bit is bit 7
(75)	0x00	active bit = 0 ® PROGRAM mode else RUN mode

would work and might use an input port such as the one shown in Figure 2-14.

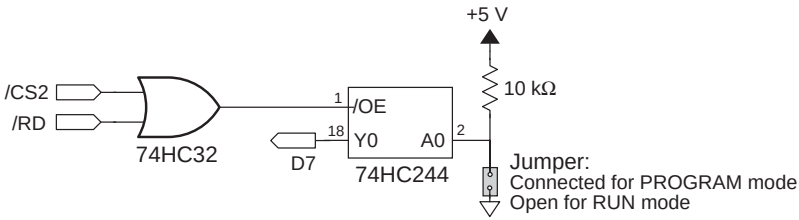


Figure 2-14. Input Port

With the standard CM7100 BIOS (2903 or later), setting the I/O address (bytes 0x72 and 0x73) to 0x0000 will force the CM7100 into development mode. This setting eliminates the need to use a RUN/PROGRAM jumper.

Direct development is not supported by the BIOS of the CM7110 included in the CM7100 Evaluation Kit.

Safeguards

The following safeguards have been adopted.

1. If there is no valid program in RAM, the Dynamic C monitor will repeatedly go into a tight loop, forcing a watchdog timeout.
2. If byte 0x70 is not a 0 or 1, the monitor is forced to RUN mode.
3. If byte 0x71 is not a multiple of 8, the monitor is forced to RUN mode.
4. If bytes 0x72 and 0x73 have an address less than 0x4000 or greater than 0x417F, the monitor is forced to RUN mode.

The Dynamic C development EPROM has the six locations all set to 0xFF.

CM7200

The CM7200 uses its Z180 microprocessor's CSI/O (clocked serial I/O) line for communicating with Dynamic C running on a host PC; Z-World's SIB22 makes the CSI/O port look just like an RS-232 port. Since the CM7200's flash EPROM is electrically reprogrammable in a circuit, the flash EPROM requires no ROM emulation during development. Consequently the CM7200's programming strategy is very simple when compared to the CM7100's.

CM7200 Method 1 — Prototyping Board

1. Check to make sure the power to the Prototyping Board is ***not*** connected.
2. Plug the CM7200 into the Prototyping Board as shown in Figure 2-15. Plug header H2 of the CM7200 into connector H3 of the Prototyping Board. Pins 1 of the header and connector must match. The CM7200 will extend over the battery on the Prototyping Board. For maximum stability, install the supplied standoff between the CM7200 and the Prototyping Board.

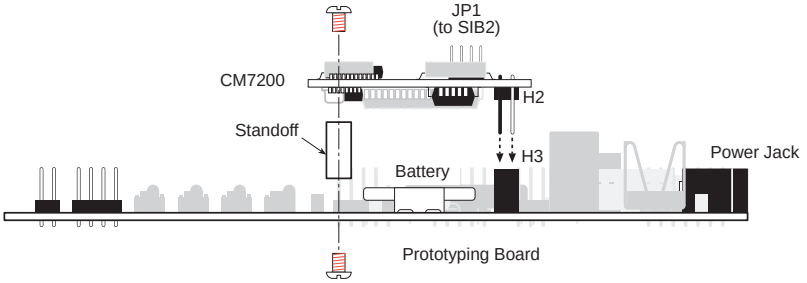


Figure 2-15. Connecting CM7200 to Prototyping Board

3. Connect the 6-conductor RJ-12 cable provided with the Developer's Kit from the PC serial-port adapter to the SIB2 as shown in Figure 2-16. Connect the 2 mm ribbon cable from the SIB2 to header JP1 on the CM7200. Be careful to match the arrow on the connector to Pin 1 of JP1.
4. Set the baud rate of the host PC's COM port to 9600 bps, 19,200 bps, or 57,600 bps.
5. Apply power to the Prototyping Board. As a minimum, the power supply must have regulated +5 V and GND for the CM7200. The CM7200 is now ready for programming.

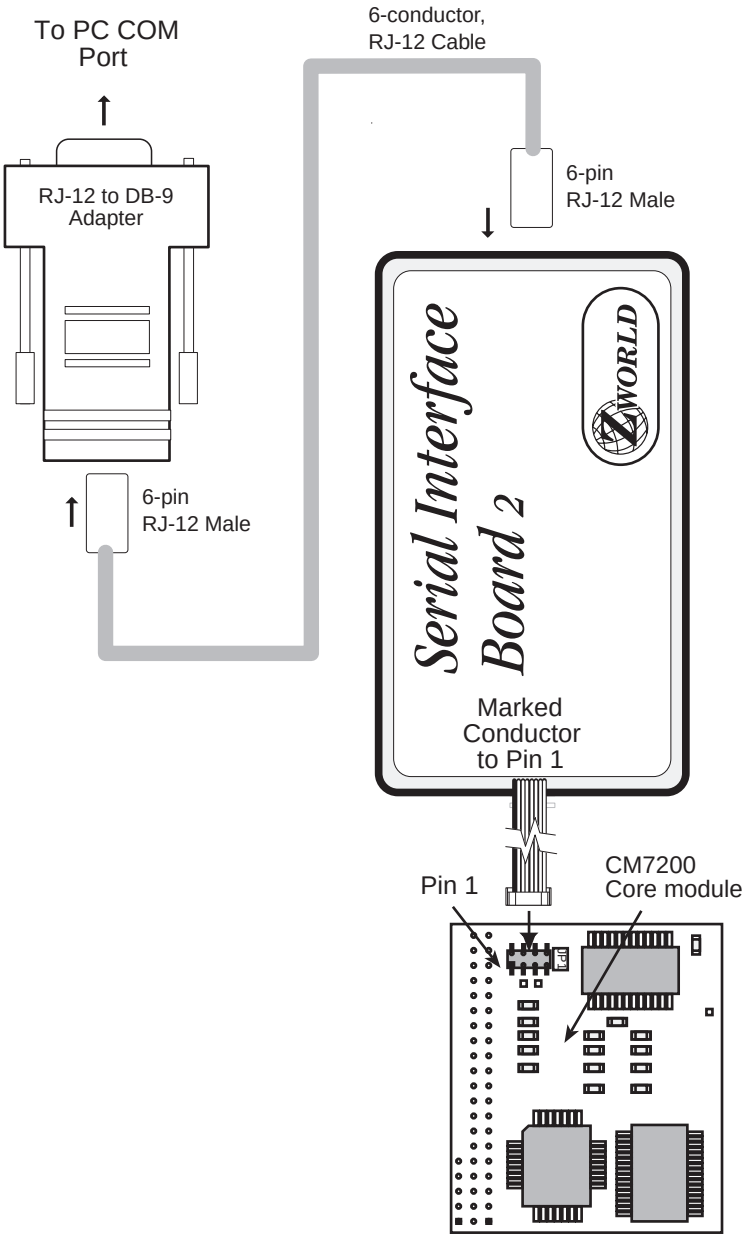


Figure 2-16. CM7200 Connection to Serial Interface Board 2

CM7200 Method 2 — Embedded In System

1. Disconnect power from the system.
2. Connect the 6-conductor RJ-12 cable provided in the Developer's Kit from the PC's serial-port adapter to the SIB2.
3. Connect the 2 mm ribbon cable from the SIB2 to header JP1 on the CM7200. Be careful to match the arrow on the connector to Pin 1 of JP1.
4. Set the baud rate of the host PC's COM port to 9600 bps, 19,200 bps, or 57,600 bps.
5. Reconnect power to the system. As a minimum, the power supply must have regulated +5 V and GND for the CM7200. The system is now ready for programming.

CHAPTER 3: SYSTEM DEVELOPMENT

General Description

The CM7000 is a complete system engine that contains the microprocessor and memory around which a controller is built.

Figure 3-1 shows a block diagram of the CM7100.

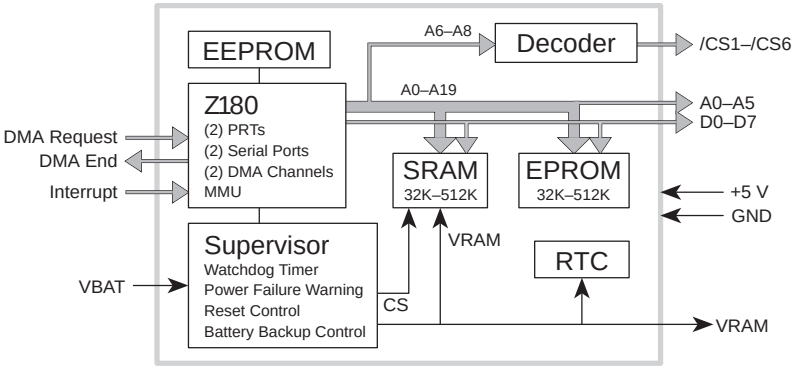


Figure 3-1. CM7100 Block Diagram

Figure 3-2 shows a block diagram of the CM7200.

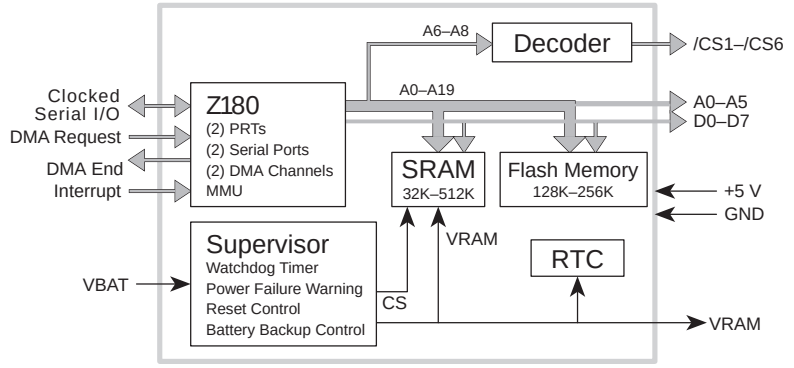


Figure 3-2. CM7200 Block Diagram

The microprocessor is a Z180, running at either 9.216 MHz or 18.432 MHz. The Z180 has two asynchronous serial ports, two DMA channels, and two programmable-reload timers (PRTs). Two of the Z180's interrupt lines are available for use in the system.

The Z180 supports a 1M address space with its internal memory management unit (MMU). It has 20 address lines. The data path is 8 bits wide—lines D0–D7.

Six chip-select lines (/CS1–/CS6) enable one of six groups of 64 input/output addresses. Thus, single-tier addressing can directly access 384 distinct devices or registers.

The optional power-supervisor IC, an ADM691, provides several services. It has a watchdog timer, performs power-failure detection, and supports battery backup. When power fails, it protects the RAM from being accidentally overwritten.

Your application can obtain the time and the date from the optional real-time clock IC, an Epson 72423.

The optional CM7100 EEPROM (24C04) stores 512 bytes of nonvolatile data for system constants and other important values. The upper 256 bytes of the EEPROM can be write-protected by breaking a circuit board trace. The CM7200 simulates the EEPROM in its flash memory. This simulation is software-compatible with the CM7100's Dynamic C EEPROM function calls.

See Appendix D, "EEPROM," for more information on the software function calls and details about write-protecting the CM7100 EEPROM.

Interface Description

The CM7000 physical interface to a controller is a 40-pin header (H2) with a 5-pin extension (H1). Figure 3-3 shows the location of header H2 and extension H1.

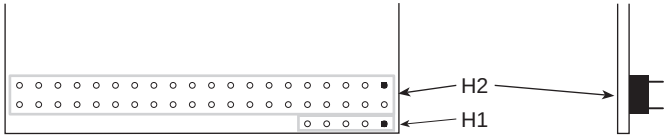


Figure 3-3. Location of Header H2 and Extension H1

The 40-pin header (H2) plugs directly into a 40-pin connector on the controller's printed circuit board. The connector on the Prototyping Board provides an example of this arrangement. The headers use 0.025" square pins on 0.1" centers.

The 5-pin interface extension (H1) comprises five plated through-holes, allowing an additional 5-pin header to be added if needed.

Figure 3-4 provides the pinouts for header H2 and extension H1.

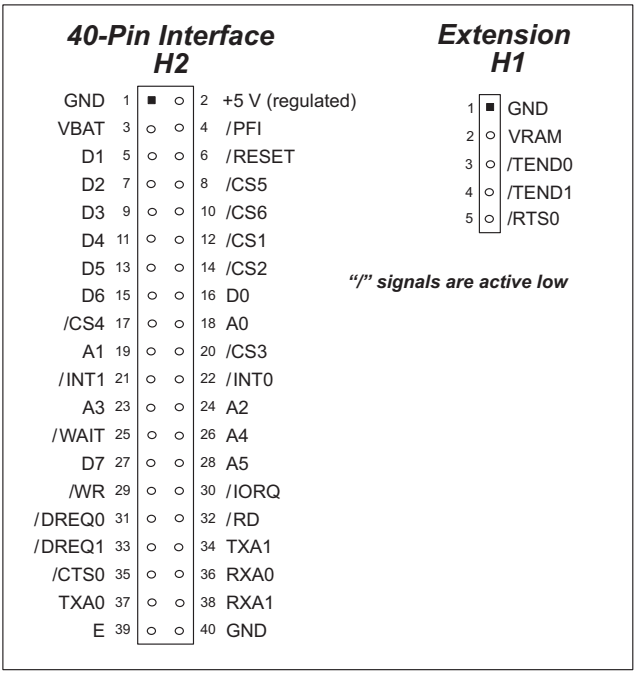


Figure 3-4. CM7000 Pinouts for Header H2 and Extension H1

Table 3-1 lists the CM7000 interface signals.

Table 3-1. CM7000 Interface Signals

Signal Name	Direction	Description
A0–A5	Out	Address lines. CMOS compatible.
D0–D7	Bi.	Data lines. TTL/CMOS compatible.
/RD	Out	Read. Defines a read cycle. Directly connected to Z180. TTL/CMOS compatible.
/WR	Out	Write. Defines a write cycle. Directly connected to Z180. TTL/CMOS compatible.
/INT0	In	Maskable interrupt request 0. TTL/CMOS compatible.
/INT1	In	Maskable interrupt request 1. TTL/CMOS compatible.
/IORQ	Out	I/O Request. Defines an I/O cycle. Directly connected to Z180. TTL/CMOS compatible.
/CS1–/CS6	Out	Chip selects (6). Each selects a group of 64 I/O addresses. TTL/CMOS compatible
/WAIT	In	Wait line. Generates wait states for I/O cycles. Allows access to slow I/O devices. Directly connected to Z180. TTL/CMOS compatible.
/DREQ0, /DREQ1	In	DMA request lines. Requests movement of one byte of data on specified DMA channel (0 or 1). Can be edge- or level-sensitive. Ignored during memory-to-memory and serial-to-memory operations. Directly connected to Z180. TTL/CMOS compatible. /DREQ0 can be a clock input or output for serial port 0, running at 16 × baud rate.
/TEND0, /TEND1	Out	DMA "transfer-end" lines. Signals the end of a DMA transfer on channel 0 or 1. Directly connected to Z180. TTL/CMOS compatible.
TXA0, TXA1	Out	Transmit. Serial data for channels 0 and 1. Directly connected to Z180. TTL/CMOS compatible.
RXA0, RXA1	In	Receive. Serial data for channels 0 and 1. Directly connected to Z180. TTL/CMOS compatible.
/CTS0	In	Clear-to-send, channel 0. Serial-control signal. Channel 0 will not transmit when this line is high. Directly connected to Z180. TTL/CMOS compatible.
/RTS0	Out	Request-to-send, channel 0. Serial control signal. Directly connected to Z180. TTL/CMOS compatible.

continued…

Table 3-1. CM7000 Interface Signals (concluded)

Signal Name	Direction	Description
VBAT	In	Battery voltage. Connects to the ADM691 supervisor. Must be grounded if no battery installed.
VRAM	Out	Battery-backed supply voltage for RAM, real-time clock, and other devices.
PFI	In	Power failure input. Connects to the ADM691 supervisor, which generates a nonmaskable interrupt (NMI) when this line falls below 1.3 V ± 0.05 V.
/RESET	Bi.	System reset. Driven by the ADM691 supervisor. Must be pulled up when supervisor is not installed.
E	Out	6800-compatible timing reference. Directly connected to Z180. TTL/CMOS compatible.

CM7000 Subsystems

This section describes the various subsystems and their signals. Source-code software drivers are available for most of these subsystems. Sample programs (included with Dynamic C) are provided.

See Appendix J, "Sample Applications," for sample circuits to illustrate the use of the CM7000.

DMA

Two DMA channels are accessible on the CM7000 interface and support memory-memory and memory-I/O transfers. The transfer modes supported by the Z180 are request, burst, and cycle-steal. DMA transfers can access the full 1M address range with a block length of 64K, and can cross over 64K boundaries. Transfers can occur every 6 clock cycles. The DMA channels can also function as high-speed counters, operating at up to 500 kHz (on the 9.216 MHz CM7000) by using the request line as a counter input.

The signals /DREQ0 and /DREQ1 are the DMA-request lines. The DMA channels monitor these lines to determine when an external device is ready for a read or write operation. The signals /TEND0 and /TEND1 are the "transfer end" lines. A DMA device asserts these outputs during the last write cycle of a DMA operation. By monitoring these lines, a system can detect the end of a DMA transfer.

The DMA channel can be programmed to be either edge or level sensitive. If a DMA channel is edge triggered, a single byte gets transferred over the DMA channel when the DMA device asserts the request line. If the DMA channel is level sensitive, multiple bytes will continue to transfer as long as the DMA device asserts the request line (that is, holds it low).

Channel 0 performs memory-memory and memory-I/O transfers. Such transfers include memory-mapped I/O and transfers to and from the serial channels. The transfer modes for Channel 0 are burst and cycle-steal. Channel 0 has memory-address increment, decrement and no-change modes.

Channel 1 performs only memory-I/O transfers. It supports memory address increment and decrement.

Channel 0 has a higher priority than Channel 1.

DMA Registers

Table 3-2 lists the registers associated with the DMA channels.

Table 3-2. DMA Registers

Register	Address	Description
Channel 0		
SAR0	0x20–22	Source Address
DAR0	0x23–25	Destination Address
BCR0	0x26–27	Byte Count
Channel 1		
MAR1	0x28–2A	Memory Address
IAR1	0x2B–2C	I/O Address
BCR1	0x2E–2F	Byte Count
Both Channels		
DSTAT	0x30	DMA Status
DMODE	0x31	DMA Mode
DCNTL	0x32	DMA Control

Memory-address registers span 20 bits. I/O-address registers, on the other hand, span only 16 bits. The byte-count register has 16 bits. The higher order bits of the registers are stored in the bytes with higher addresses.

For details on DMA registers and timing, refer to the Zilog ***Z180 MPU User's Manual*** and the sample Dynamic C programs **`SC1DM232.C`** and **`SC1DMAPW.C`**.

Software

Table 3-3 lists Dynamic C functions that support the DMA channels.

Table 3-3. DMA Library Functions

Function	Description	Library
DMA0Count **DMA1Count**	DMA channel acts as a high-speed counter, interrupting when done.	**DRIVERS.LIB**
DMASnapShot	Reads the number of pulses a DMA channel has counted.	**DRIVERS.LIB**
DMA0_Off **DMA1_Off**	Turns DMA channel off.	**DMA.LIB**
DMA0_SerialInit	Initializes a serial port (0 or 1) for DMA transfer.	**DMA.LIB**
DMA0_Rx **DMA0_Tx**	Initiates a DMA transfer (Rx = receive, Tx = transmit) from a serial port.	**DMA.LIB**
DMA0_MIO **DMA1_MIO**	Initiates a DMA transfer from memory to an I/O port. The external device must generate a negative pulse to request each byte transferred.	**DMA.LIB**
DMA0_MM	Initiates a memory-to-memory transfer.	**DMA.LIB**
DMA0_IOM **DMA1_IOM**	Initiates a DMA transfer from an I/O port to memory. The external device must generate a negative pulse to request each byte transferred.	**DMA.LIB**

The ***Dynamic C Function Reference*** manual describes these functions in detail.

Programmable Timers

The Z180 has a two-channel programmable reload timer (PRT). Each channel (PRT0 and PRT1) has a 16-bit down-counter, TMDR, and a 16-bit reload register, RLDR. A single 8-bit timer-control register, TCR, sets up both timers. The down counters decrement every 20 clocks (2.17 µs at 9.216 MHz). When the counters reach 0, they automatically reinitialize with the value stored in their respective reload registers.

The two channels are disabled at system reset. By manipulating the bits of the TCR, the timers can be made to cause an interrupt when they time out. Counting can also be enabled and disabled.

When reading the TMDR registers, read the low byte first, then read the high byte. The accuracy of the reading depends on this order. Before writing to a TMDR, you must stop the channel by setting the appropriate bits in the TCR. In general, do not set a reload register unless you have first stopped its timer channel.

Refer to the ***Z180 MPU User's Manual*** for details on the operation of the PRT.

Software

Table 3-4 lists Dynamic C functions that support the programmable reload timer.

Table 3-4. Programmable Timer Library Functions

Function	Description	Library
init_timer0 **init_timer1**	Places a count in the timer's reload register.	**DRIVERS.LIB**
timer0_isr	Timer 0 interrupt service routine. Runs RTK (Real-Time Kernel).	**DRIVERS.LIB**
int_timer1	Timer 1 interrupt service routine. Drives a beeper and keypad. Runs RTK if **RUNKERNEL** is defined.	**KDM.LIB**
Tdelay	Waits specified number of milliseconds using timer 1.	**DRIVERS.LIB**
lk_tdelay	Similar to **Tdelay**.	**KDM.LIB**
lk_int_timer1	Similar to **int_timer1**.	**KDM.LIB**
lg_init_keypad	Initializes timer 1, KDM keypad driver, and graphic LCD.	**KDM.LIB**

The ***Dynamic C Function Reference*** manual describes these functions in detail.

EPROM

CM7100

The CM7100 has a 32-pin socket (U3) that accepts 32K to 512K EPROM. The socket accepts either 28-pin or 32-pin EPROM chips. The access time must be less than 70 ns at 18 MHz, or less than 100 ns at 9 MHz.

Figure 3-5 shows how to seat the EPROM chip in the socket according to the number of pins.

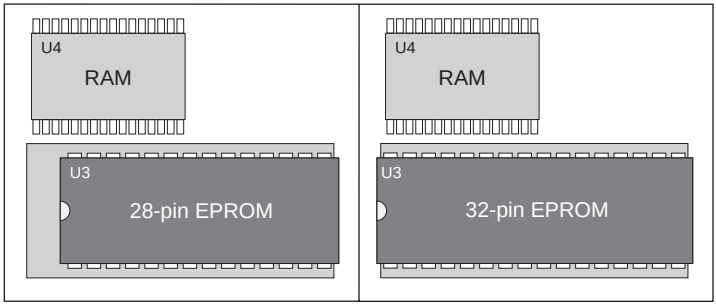


Figure 3-5. Placement of 28-pin and 32-pin EPROM on CM7100

Header J3 on the microprocessor side of the CM7100 reflects the EPROM size, as shown in Figure 3-6.

The standard EPROM for the CM7100, Z-World part number 680-290x, supports the full Dynamic C software-development system. This standard EPROM has 28 pins.

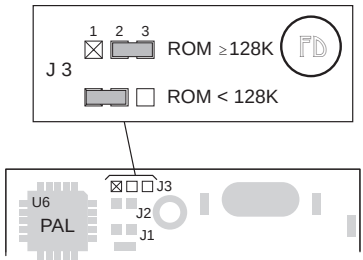


Figure 3-6. CM7100 Header J3 Configurations for Different EPROM Sizes

A special 32-pin 128K EPROM (Z-World part number 680-295x) comes with the CM7100 Evaluation Kit. This special EPROM supports the trial version of Dynamic C that comes with the kit, and contains eight sample programs.

When using the CM7100 Development Board (ROM emulator), header J3 on the CM7100 must have pins 2–3 connected. This configuration is the factory default. Also note that the connection on header J3 is a ***soldered*** jumper consisting of a 0 Ω resistor.

Programming EPROMs

Dynamic C can be used to create a file for programming an EPROM by selecting the **Compile to File** option in the **COMPILE** menu with the standard EPROM (Z-World part number 680-290x) installed. The CM7100 must be connected to the PC running Dynamic C during this step because essential library routines must be uploaded from the standard EPROM and linked to the resulting file. The output is a binary file (optionally an Intel hex format file) that can be used to build an application EPROM. The application EPROM is then programmed with an EPROM programmer that reads either a binary image or the Intel hex format file. The resulting application EPROM can then replace the standard EPROM.

When doing program development with Dynamic C, it is best to use a 128K SRAM or larger. Dynamic C will work with a 32K SRAM, but the total program space will be limited to 16K of root and 16K of extended memory. This is enough for many programs, but it is inconvenient to run out of memory during development. Once a program is burned into EPROM, there is no reason to use SRAM larger than 32K unless the data space is larger than 32K.

Choosing EPROMs

Socket U3 can accommodate several different types of EPROMs, including the following.

27C256	32K	28 pins
27C512	64K	28 pins
27C010	128K	32 pins
27C020	256K	32 pins

Copyrights

The Dynamic C library is copyrighted. Place a label containing the following copyright notice on the EPROM whenever an EPROM that contains portions of the Dynamic C library is created.

Your own copyright notice may also be included on the label to protect your portion of the code.

Z-World grants purchasers of the Dynamic C software and the copyrighted CM7100 EPROM permission to copy portions of the EPROM library as described above, provided that:

1. The resulting EPROMs are used only with the CM7100 cores manufactured by Z-World, and
2. Z-World's copyright notice is placed on all copies of the EPROM.

CM7200

The CM7200 has a 32-pin flash EPROM soldered to the board at U3, as shown in Figure 3-7.

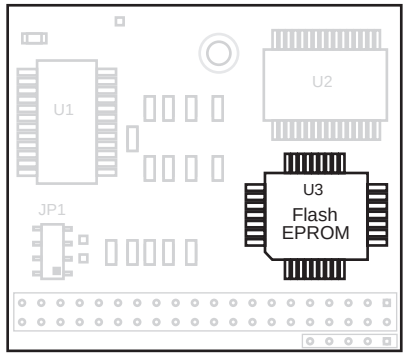


Figure 3-7. Location of CM7200 Flash EPROM

The standard flash EPROM for the CM7200 is a 128K AT29C010A. A 256K AT29C020 chip is available as an option.

Unlike most memory devices, which program a bit or byte at a time, flash EPROM programs a *sector* at a time. That is, even if only a single byte within a sector needs updating, the CM7200 overwrites the entire sector. All bytes not specified in the sector being programmed will erase to 0xFF.

Write cycles execute under both software and hardware data protection. These extra measures prevent invalid write cycles to the flash EPROM that would otherwise possibly corrupt a program or data.

Read operations access the flash EPROM just like an EPROM. The access time must be less than 70 ns for the 18 MHz CM7200, or less than 90 ns for 9 MHz versions.

The CM7200 uses a portion of its flash EPROM to simulate the 512 bytes of EEPROM. However, the access times for the flash EPROM are different from EEPROM. The CM7200 executes the same Dynamic C EEPROM function calls as the CM7100, accommodating hardware differences in its BIOS. An 8-byte section of the flash EPROM contains the CM7200 BIOS.

Dynamic C software drivers handle the read and write operations.

Flash EPROM is rated for 10,000 writes. In practice, flash EPROM has performed for up to 100,000 writes. Z-World recommends that any writes to the flash EPROM be made by the programmer rather than automatically by the software to maximize the life of the flash EPROM.

If you modify the driver software, do not overwrite the sections of the flash EPROM that contain the BIOS and that simulate the EEPROM.

SRAM

The RAM is not socketed, but is soldered to the board as shown in Figure 3-8. CM7000s may be ordered with 32K or 128K RAM already installed. CM7000s with 512K RAM are also available.

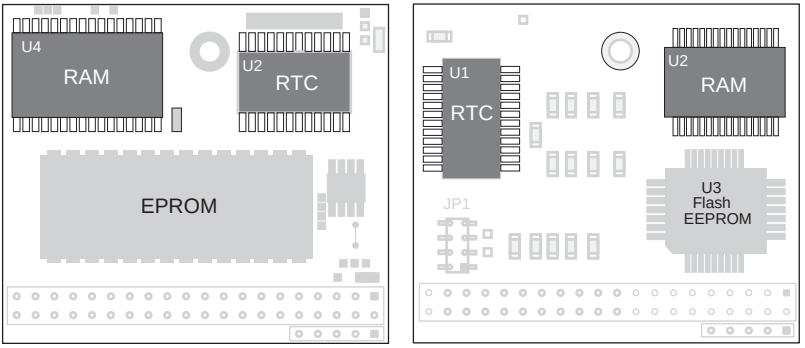


Figure 3-8. Locations of CM7100 and CM7200 SRAM and RTC

The ROM addresses range from 0x0 to 0x7FFFF. The range of RAM addresses depends on the RAM chip as shown in Table 3-5.

Table 3-5. SRAM Addresses

SRAM Size	Address Range
32K	0x80000 to 0x87FFF
128K	0xA0000 to 0xBFFFF
512K	0x80000 to 0xFFFFF

The CM7000 address decoder makes data *appear* to be replicated. Data in 32K RAM appear to be replicated 16 times throughout the range 0x80000–FFFFF. Data in 128K RAM appear to be replicated throughout the range 0xE0000–FFFFF.

EEPROM

The CM7100 has an optional 512-byte EEPROM at location U1. The EEPROM is nonvolatile memory and holds system constants. The CM7200 emulates this EEPROM in its flash EPROM, and executes all of Dynamic C's EEPROM function calls. Consequently, despite the dissimilar hardware, the memory map for both versions is exactly the same.

See Appendix D, "EEPROM," for more information on the software function calls and details about the EEPROM.

Real-Time Clock (RTC)

The CM7000 has an optional Epson 72423 chip as shown in Figure 3-8. The chip stores time and date, and accounts for the number of days in a month, and for leap year. A user-supplied backup battery will allow the values in the RTC to be preserved if a power failure occurs.

The Dynamic C function library **DRIVERS.LIB** provides the following RTC functions.

- **tm_rd**

  Reads time and date values from the RTC.

- **tm_wr**

  Writes time and date values into the RTC.

The ***Dynamic C Function Reference*** manual describes these functions and the associated data structure **tm**.

The following points apply when using the RTC.

1. The AM/PM bit is 0 for AM, 1 for PM. The RTC also has a 24-hour mode.
2. Set the year to 96 for 1996, 97 for 1997, and so on.

Constantly reading the RTC in a tight loop will result in a loss of accuracy.

Power Management

The CM7000 has an optional ADM691 supervisor chip, whose location is shown in Figure 3-9.

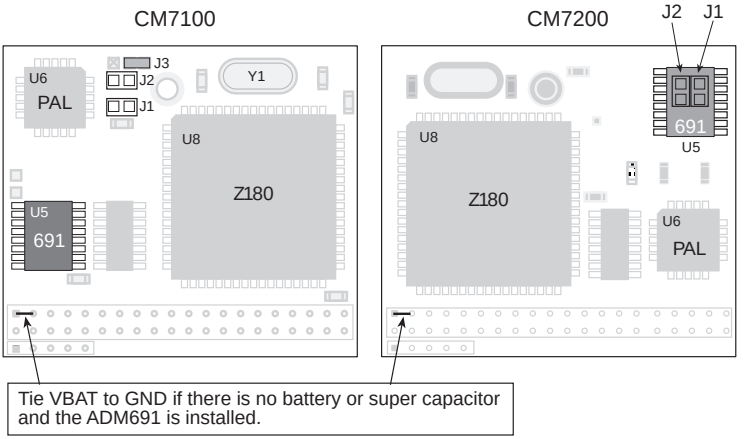


Figure 3-9. Locations of ADM691 Supervisor Chip and Associated Headers

If the ADM691 supervisor chip is installed, and there is no battery or super capacitor, connect the VBAT input to ground using the VBAT pin of header H2 as shown in Figure 3-9. Alternatively for the CM7100, a jumper may be soldered across header J1. The grounding keeps the ADM691 VIN from floating.

If the CM7100 ADM691 supervisor chip is removed, solder a jumper across header J2. J2 connects the **/RAMCS** signal to the RAM. Further, you must connect VRAM to +5 V. One way to make this connection is to solder together pads 2 and 3 at U5.

Figure 3-10 provides a schematic representation of these connections.

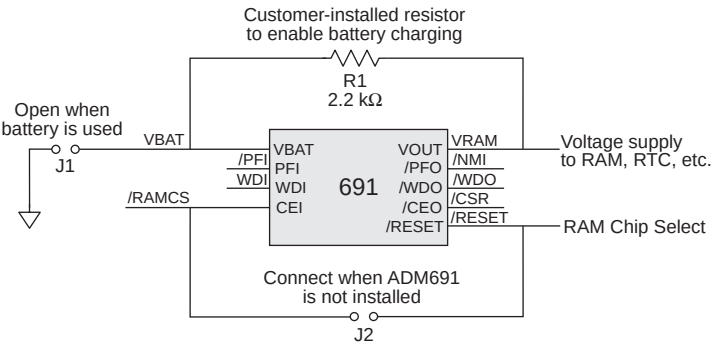


Figure 3-10. CM7100 Power Management Circuit

For the CM7200, solder a jumper across headers J1 and J2, located under the ADM691 chip (U5). J1 connects the **/RAM** signal to the RAM, and J2 provides power to the RAM. Further, you must connect VRAM to +5 V. One way to make this connection is to solder together pads 2 and 3 at U5.

Conversely, if a supervisor IC is installed on a CM7000 shipped from the factory without one, you would first have to remove the jumpers at headers J1 and J2 on the CM7200, and from header J2 on the CM7100.

Be sure ***not*** to connect VBAT to ground if the ADM691 is present ***and*** a battery or a super capacitor has been included in the system.

The ADM691 chip performs the following services.

- Watchdog timer resets the microprocessor if software "hangs."
- Performs a power-failure shutdown and reset.
- Generates an "early warning" power-failure interrupt (PFI) that lets the system know when power is about to fail.
- Memory protection feature prevents writes to RAM when power is low.
- Supports battery or super capacitor backup.

Handling Power Fluctuations

During a normal power-down, an interrupt service routine is used in response to a nonmaskable interrupt (NMI) to save vital state information for the application for when power recovers. The amount of code that the interrupt service routine can execute depends on the rate of decrease of voltage to the controller.

Theoretically, a power failure would cause a single NMI. Then, the interrupt service routine would restore the previous state data when the voltage recovers.

However, fluctuations in the DC input line could cause the supervisor IC to see multiple crossings of the 1.3 V input power-reset threshold. These multiple negative-edge transitions would, in turn, cause the processor to see multiple NMIs.

When the Z180 generates an NMI, it saves the program counter (PC) on the processor's stack. It next copies the maskable interrupt flag, IEF1, to IEF2 and zeroes IEF1. The Z180 will restore saved state information when it executes a RETN (return from nonmaskable interrupt) instruction.

See Appendix C, "Memory, I/O Map, and Interrupt Vectors," for more information on interrupts.

Ideally, the processor should be able to pop the stack and return to the location where the program was first interrupted. But the original IEF1 flag is not recoverable because the second and subsequent NMIs will have saved IEF1 = 0 to IEF2. Also, depending on the number of fluctuations of the DC input (and hence, the number of stacked NMIs), the processor's stack can overflow, possibly into your program's code or data.

The following sample program shows how to handle an NMI. This program assumes that the controller monitors power failures and that the CM7000's watchdog timer is enabled.

```
main(){
   ...
}

...
char dummy[24];

...
#define NMI_BIT      0   ; bit 0

#JUMP_VEC NMI_VEC myint

#asm
  myint::
    ld   sp,dummy+24     ; force stack pointer
                         ; to top of dummy vector
                         ; to prevent overwriting
                         ; code or data
```

do whatever service, within allowable execution time

```
  loop:
    call hitwd       ; make sure no watchdog reset
                     ; while low voltage
    ld   bc,NMI      ; load the read NMI register
                     ; to bc
    in   a,(c)       ; read the read NMI register
                     ; for /PFO
    bit  NMI_BIT, a  ; check for status of /PFO
    jr   z,loop      ; wait until the brownout
                     ; clears
  timeout:           ; then...a tight loop to
                     ; force a watchdog timeout,
    jp   timeout     ; resetting the Z180
#endasm
```

If the watchdog is not enabled, the following sample program can be used to force the processor to restart execution at 0x0000.

```
char dummy[24];

...

#define NMI_BIT      0   ; bit 0

...

#JUMP_VEC NMI_VEC myint

#asm
  myint::
    ld   sp,dummy+24     ; reset stack pointer
                         ; to top of dummy array
                         ; to prevent overwriting
                         ; user code/data space
```

do whatever service, within allowable execution time

```
  loop:
    ld   bc,NMI      ; load the read NMI register
                     ; to bc
    in   a,(c)       ; read the read NMI register
                     ; for /PF0
    bit  NMI_BIT,a   ; check for status of /PF0
    jr   z,loop      ; wait until the brownout
                     ; clears

  restart:
    ld   a,0xE2      ; make sure 0x0000 points
                     ; to start of EPROM BIOS
    out0 (CBAR),a    ; set the CBAR
    jp   0000h       ; jump to logical (also
                     ; physical) address 0x0000
#endasm
```

Of course, if the DC input voltage continues to decrease, then the controller will just power down.

If the watchdog timer is enabled, call the Dynamic C function **hitwd** during the power-failure service routine to make sure that the watchdog timer does not time out and thereby reset the processor. The controller can continue to run at low voltages, and so it might not be able to detect the low-voltage condition after the watchdog timer resets the processor.

The Watchdog Timer

To increase reliability, the ADM691's watchdog timer forces a system reset if a program does not notify the supervisor nominally every second. The assumption is that if the program fails to "hit" the watchdog, the program must be stuck in a loop or halted. The Dynamic C function for hitting the watchdog timer is **hitwd**. To hold the watchdog timer at bay, make a call to **hitwd** in a routine that runs periodically at the lowest software priority level.

A program can read the state of the **/WDO** line with a call to **wderror**. This makes it possible to determine whether a watchdog timeout occurred. The following sample program shows how to do this when a program starts or restarts.

```
main(){
  if( wderror() ) wd_cleanup();
  hitwd();
  ...
}
```

Power Shutdown and Reset

When V_{CC} (+5 V) drops below V_{MIN} (between 4.5 V and 4.75 V), the ADM691 supervisor asserts **/RESET** and holds it until V_{CC} goes above V_{MIN} and stays that way for at least 50 ms. This delay allows the system's devices to power up and stabilize before the CPU starts.

PFI "Early Warning"

A power supply like that of the Prototyping Board (Figure 3-11) allows power failures to be detected before they cause operational failures. Connect the signals PFI and V_{CC} (+5 V) to the CM7000 via header H2.

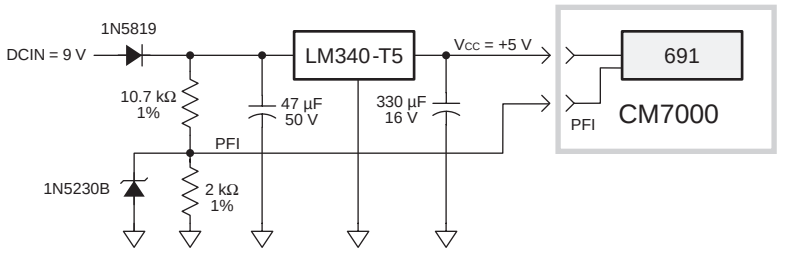


Figure 3-11. Prototyping Board Power Supply

When PFI drops below 1.3 V ± 0.05 V (i.e., DCIN drops below ~7.5 V), the supervisor asserts **/NMI** (nonmaskable interrupt), and allows the program to clean up and get ready for shutdown. The underlying assumption is that **PFI** will cause the interrupt during a power failure before the ADM691 asserts **/RESET**.

If the CM7000 has no ADM691 supervisor, solder together pads 9 and 10 at U5 to connect **PFI** directly to **/NMI** for a nonmaskable interrupt line.

Memory Protection

When **/RESET** is active, the ADM691 supervisor disables the RAM chip-select line, preventing accidental writes.

Battery/Super Capacitor Backup

You can connect a battery or super capacitor to protect data in the RAM and RTC. Solder a connector across pins 1–3 on header H2. Connect the battery or the super capacitor across VBAT and ground, as shown in Figure 3-12. Use a resistor to recharge the battery (if it is rechargeable) or the super cap. Make sure jumper J1 on the CM7100 is not connected.

The RAM cannot be battery-backed unless the ADM691 or a similar supervisor chip is present.

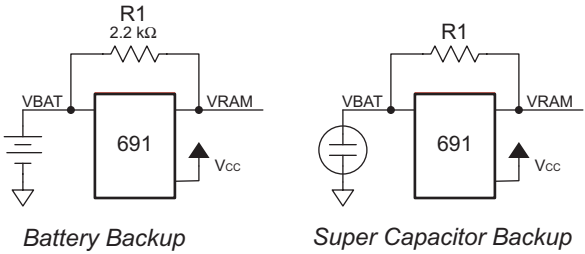


Figure 3-12. Battery or Super Capacitor Installation

VRAM, the voltage supplied to the RAM and RTC, can also protect other devices attached to the system against power failures. The ADM691 supervisor switches VRAM to VBAT or V_{CC}, whichever is greater. (To prevent "hunting," the switchover actually occurs when V_{cc} is 50 mV higher than VBAT.)

Both the RAM and the RTC require 2 V or more to retain data. A 3 V lithium battery (such as the coin-type CR2325 from Panasonic) works well. The RTC draws 3 µA during powerdown; the RAM draws only 1 µA. The CR2325 is rated at 185 mA·h, and will provide current for a total downtime of 46,250 hours or 5.27 years.

The circuit draws no current from the battery once regular power is applied. The standby current for the RAM depends strongly on the storage temperature.

An alternative to a battery is a large capacitor and resistor that create an RC discharge circuit on the VBAT line. When power is applied, the capacitor will charge up until it reaches VRAM. When power is removed, the capacitor will power the RAM and RTC until discharged. As stated above, the RAM and RTC require a total of 4 µA. This current draw means that the capacitor's full backup time is approximately 725 ks/F.

The larger the value of this capacitor, the longer the available backup time. Connect this capacitor between the VBAT line and ground, as shown in Figure 3-12. The CM7000 provides a resistor location (R1) to add a series resistor to complete an RC charging circuit. The value of this resistor affects the recharge time and limits the load on the power supply as the capacitor recharges. The resistor has an insignificant effect during discharge because the resistance from VBAT to VRAM on the ADM691 is typically 15 Ω.

The capacitor will recharge to 98 percent of its nominal capacity in about four time constants (4 × RC). This recharge time limits the system's ability to withstand closely spaced power outages. Panasonic sells a line of gold capacitors ideally suited for this application with capacitance up to 10 F.

Table 3-6 provides backup times for several scenarios.

Table 3-6. Representative Backup Times for Various Capacitors

Capacitance (F)	Resistance (Ω)	5 V load* (mA)	Charge Time (to 98%)	Backup Time** (4.9 V to 2.0 V)
0.00047	2200	2.3	4.1 s	5.67 min
0.1	1000	5	6.67 min	20 h
0.25	510	10	8.5 min	50 h
0.5	510	10	17 min	100 h
1.0	220	23	15 min	200 h
3.3	220	23	49 min	27 d

* Current for a load at 5 V at initial power-up. The current will decrease as the capacitor charges up.

** The backup time at a discharge of 4 µA with RAM and RTC.

Connect VBAT to ground if there is no backup circuit. This connection prevents VBAT on the ADM691 from floating, which could cause the switchover circuitry to malfunction.

System Reset

The **/RESET** line located on pin 6 of header H2 connects directly to the CPU, and synchronizes external devices. When the ADM691 chip is present, it drives the **/RESET** line. The **/RESET** line is not pulled up internally. The interface circuitry must manage this line if the ADM691 chip is not installed.

The CM7000 Prototyping Board provides a 10 kΩ pull-up resistor on this line.

See Chapter 4, “Design Considerations,” for more information about power-on and reset management.

Serial Communication

Two serial channels support asynchronous communication at baud rates from 300 bps to 57,600 bps (115,200 bps with the 18.432 MHz cores). Serial communication provides a simple and robust means for networking controllers and other devices.

Table 3-7 lists the RS-232 signals.

Table 3-7.. RS-232 Signals

Signal Name	Description
RX0	Receive, Channel 0
RX1	Receive, Channel 1
TX0	Transmit, Channel 0
TX1	Transmit, Channel 1
/CTS0	Clear to send, Channel 0
/RTS0	Request to send, Channel 0

Figure 3-13 illustrates a configuration of two 3-wire RS-232 channels.

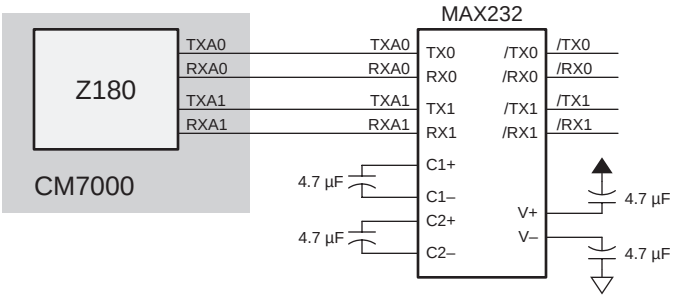


Figure 3-13. Configuration of Two 3-wire RS-232 Channels

With the appropriate driver chips, it is possible to construct two 3-wire RS-232 ports or one 5-wire RS-232 port (with RTS and CTS) and one half-duplex RS-485 port. An RS-485 channel can provide half-duplex asynchronous communication over twisted pair wires for distances up to 3 km. Other kinds of serial channels are possible.

Figure 3-14 illustrates a configuration of one 5-wire RS-232 channel and one half-duplex RS-485 channel.

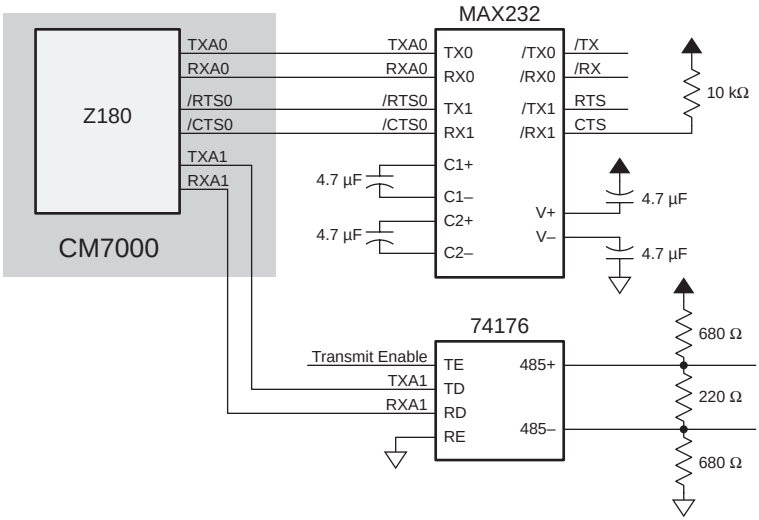


Figure 3-14. Configuration of One 5-wire RS-232 Channel and One Half-Duplex RS-485 Channel

/RTS0 is on the optional H1 header, not on the 40-pin header. If additional handshaking lines are needed, these are easy to provide using registers and input buffers.

RS-232 Communication

Z-World has RS-232 support libraries for Z180 Port 0 and Port 1. The following functional support for serial communication is included.

- Initialing the serial ports.
- Monitoring and reading a circular receive buffer.
- Monitoring and writing to a circular transmit buffer.
- An echo option.
- CTS (clear to send) and RTS (request to send) control.
- XMODEM protocol for downloading and uploading data.
- A modem option.

Receive and Transmit Buffers

Serial communication is easier with a background interrupt routine that updates receive and transmit buffers. Every time a port receives a character, the interrupt routine places it into the receive buffer. A program can read the data one character at a time or as a string of characters terminated by a special character.

A program sends data by writing characters into the transmit buffer. If the serial port is not already transmitting, the write functions will automatically initiate transmission. Once the last character of the buffer is sent, the transmit interrupt is turned off. A high-level application can write data one character at a time or in a string.

Echo Option

If the echo option is turned on during initialization of the serial port, any character received is automatically echoed back (transmitted out). This feature is ideal for use with a dumb terminal and also for checking the characters received.

CTS/RTS Control

The Z180's hardware constrains its Port 0 to have the CTS (clear to send) pulled low by the RS-232 device to which it is talking. The CM7000 does not support CTS for the Z180's Port 1.

If the CTS/RTS option is selected, the support software will pull the RTS (request to send) line high when the receive buffer has reached 80% of its capacity. This stops the transmitting device (if its CTS is enabled). The RTS line goes low again when the receive buffer has drops below 20% of its capacity.

If the device with which your software is communicating does not support CTS and RTS, tie the CTS and RTS lines on the CM7000 side together to make communication possible.

If /CTS0 is not used, ground it.

XMODEM File Transfer

The CM7000 supports the XMODEM protocol for downloading and uploading data. Currently, the library supports downloading an array of data in multiples of 128 bytes.

An application writes data to be uploaded to a specified area in RAM. The targeted area for writing should not conflict with the current resident program or data.

Echo is automatically suspended during XMODEM transfer.

Modem Communication

Modems and telephone lines facilitate RS-232 communication across great distances. If you choose the software's modem option, character streams that are read from the receive buffer are automatically scanned for modem commands. When a modem command is found, the software takes appropriate action. Normally, the communication package would be in COMMAND mode while waiting for valid modem commands or messages. Once a link is established, the communication is in DATA mode (regular RS-232). However, the software continues to monitor the modem for a **NO_CARRIER** message.

The software assumes that modem commands are terminated with **‹CR›**, that is, a carrier return (0x0D). The modem option is easiest to use when the user protocol also has **‹CR›** as the terminating character. Otherwise, the software has to check for two different terminating characters. The user's terminating character cannot be any of the ASCII characters used in modem commands, nor can it be a line-feed character.

The Dynamic C RS-232 library supports communication with a Hayes Smart Modem or compatible. The CTS, RTS and DTR lines of the modem are not used. If the modem used is not truly Hayes Smart Modem compatible, tie the CTS, RTS and DTR lines on the modem side together. The CTS and RTS lines on the controller also have to be tied together. A "NULL-modem" cable is also required for the TX and RX lines. A commercial NULL-modem cable would have its CTS and RTS lines tied together already on both sides.

Figure 3-15 shows the correct modem-to-controller wiring.

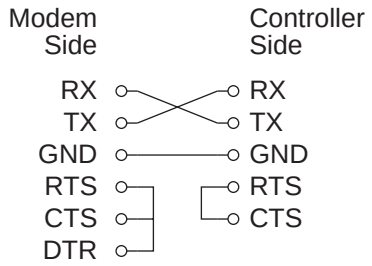


Figure 3-15. Connections Between Controller and Modem

Interrupt Handling for Z180 Port 0

Normally, a serial interrupt-service routine is declared in an application program with the following compiler directive.

```
#INT_VEC SER0_VEC routine
```

However, if the same serial port is used for Dynamic C programming, the program has to be downloaded first with Dynamic C before the address of the serial interrupt service routine is loaded into the interrupt-vector table.

That is, the service routine must be loaded at runtime. The function

```
reload_vec( int vector, int(*serv_function)() )
```

will load the address of the service function into the specified location in the interrupt vector table. In this case, do not use the **#INT_VEC** directive. Once the service routine takes over, the program can no longer be debugged in Dynamic C.

If you communicate with a serial device other than the Dynamic C programming port on the PC, the program has to make sure that the hardware is properly configured before sending any serial messages.

When you recompile your application programs for EPROM or for download to RAM, they will not need to communicate with Dynamic C. At this point, you may use the compile-time directive **#INT_VEC** freely.

Software Support

This section lists functions for Port 0 of the Z180. For Z180 Port 1, simply substitute "**z1**" for "**z0**" in the function name. For example, the initialization routine for Z180 Port 0 is called **Dinit_z0**. The equivalent function for Z180 Port 1 would be **Dinit_z1**.

Z0232.LIB, **Z1232.LIB**, **MODEM232.LIB**, **AASCZ0.LIB**, and **AASCZ1.LIB** contain the functions to support serial communication. Refer to the ***Dynamic C Function Reference*** manual for details.

Master-Slave Networking

Z-World has library functions for master-slave 2-wire half-duplex RS-485 9th-bit binary communication. This protocol is supported only on Z180 Port 1. A network may only have one master, which has a board identification address of 0. Slaves should each have their own distinct board number from 1 to 255.

Functional support for master-slave serial communication follows this scheme.

1. Initialize Z180 Port 1 for RS-485 communication.
2. The master sends an inquiry and waits for a response from a slave.
3. Slaves monitor for their address during the 9th-bit transmission. The targeted slave replies to the master.

The binary-command message protocol is similar to that used for the new Opto 22 binary protocol. The following format is used for a master message.

```
[slave id] [len] [ ] [ ]...[ ] [CRC hi][CRC lo]
```

The following format is used for a slave's response.

```
[len] [ ] [ ]...[ ] [CRC hi] [CRC lo]
```

The term **len** is the length of the message that follows.

During a transfer from the master, the address byte is transferred in 9th-bit address mode, and only the slave that has this address will listen to the rest of the message, which is sent in regular 8-bit data mode.

Software Support

Table 3-8 lists function calls from **NETWORK.LIB** for use with RS-485 networks.

Table 3-8. RS-485 Network Software Functions

Function	Description
op_init_z1	Initializes Z180 Port 1 for RS-485 9th-bit binary communication.
check_opto_command	Checks for a valid and completed command or reply in the receive buffer.
sendOp22	Master sends a message and waits for a reply.
ReplyOpto22	Slave replies to the master's inquiry.
misticware	Gateway for RS-485 9th-bit binary communication.
optodelay	Produces a delay of ~50 ms (uses the **suspend** function if the RTK is in use).
rbuf_there	Monitors the receive buffer for a completed command or reply.
op_send_z1	Called by **misticware** to initiate transmission.
op_rec_z1	Called by **misticware** to ready the receiver for data reception.
op_kill_z1	Kills Z180 Port 1.
Z1_op_int	Interrupt service routine for Z180 Port 1, used in master-slave networking.

Refer to the ***Dynamic C Function Reference*** manual for more information on these functions.

Use of the Serial Ports

If you plan to use the serial ports extensively, or if you intend to use synchronous communications, Z-World recommends that you obtain copies of the following Zilog technical manuals, available from Zilog, Inc, in Campbell, California.

Z180 MPU User's Manual

Z180 SIO Microprocessor Family User's Manual

To get started, Z-World provides these low-level utility functions.

```
int sysclock()
int z180baud( int clock, int baud )
```

The **sysclock** function returns the clock frequency in multiples of 1200 bps, as read from the EEPROM. The clock frequency was stored at location 0x108 at the factory. The **z180baud** function returns the byte to be stored in CNTLB0 or CNTLB1, considering only the bits needed to set the baud rate. You must supply the clock and baud rate in multiples of 1200 Hz. Thus, 7680 specifies a 9.216 MHz clock, and 16 specifies a baud rate of 19,200 bps. The return value is –1 if the function cannot derive the baud rate from the given clock frequency.

Each serial port appears to the CPU as a set of registers. Each port can be accessed directly with the **inport** and **outport** library functions using the symbolic constants shown in Table 3-9.

Table 3-9. Z180 Serial Port Registers

Address	Name	Description
00	CNTLA0	Control Register A, Serial Channel 0
01	CNTLA1	Control Register A, Serial Channel 1
02	CNTLB0	Control Register B, Serial Channel 0
03	CNTLB1	Control Register B, Serial Channel 1
04	STAT0	Status Register, Serial Channel 0
05	STAT1	Status Register, Serial Channel 1
06	TDR0	Transmit Data Register, Serial Channel 0
07	TDR1	Transmit Data Register, Serial Channel 1
08	RDR0	Receive Data Register, Serial Channel 0
09	RDR1	Receive Data Register, Serial Channel 1

Attainable Baud Rates

The serial ports built into the Z180 can generate standard baud rates when the clock frequency is 9.216 MHz or 18.432 MHz.

Z180 Serial Ports

The Z180's two independent, full-duplex asynchronous serial channels have a separate baud-rate generator for each channel. The baud rate can be divided down from the microprocessor clock, or from an external clock for either or both channels.

The serial ports have a multiprocessor communications feature. When enabled, this feature adds an extra bit to the transmitted character (where the parity bit would normally go). Receiving Z180s can be programmed to ignore all received characters except those with the extra multiprocessing bits enabled. This provides a 1-byte attention message that can be used to wake up a processor without the processor having to intelligently monitor all traffic on a shared communications link.

The block diagram in Figure 3-16 shows Serial Channel 0. Serial Channel 1 is similar, but control lines for /RTS and /DCD do not exist. The five unshaded registers shown in Figure 3-16 are directly accessible as internal registers.

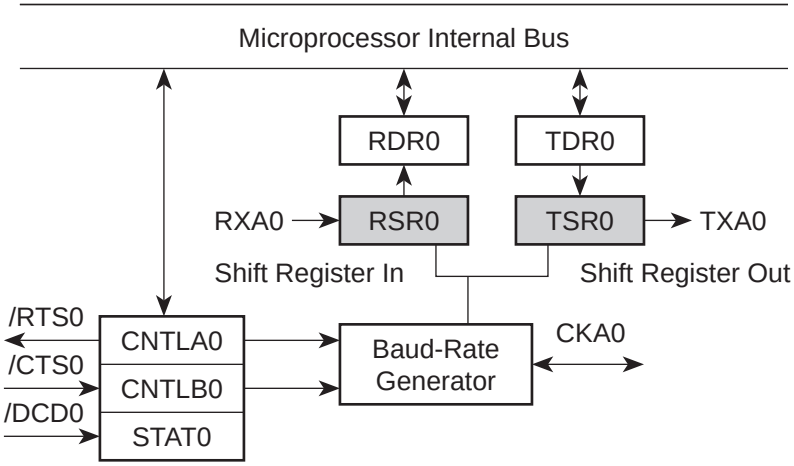


Figure 3-16. Z180 Serial Channel 0

The serial ports can be polled or interrupt-driven.

A *polling* driver tests the ready flags (TDRE and RDRF) until a ready condition appears (transmitter data register empty or receiver data register full). If an error condition occurs on receive, the routine must clear the error flags and take appropriate action, if any. If the **/CTS** line is used for flow control, transmission of data is automatically stopped when **/CTS** goes high because the TDRE flag is disabled. This prevents the driver from transmitting more characters because it thinks the transmitter is not ready. The transmitter will still function with **/CTS** high, but exercise care because TDRE is not available to synchronize loading the data register (TDR) properly.

An *interrupt-driven* port works as follows. The program enables the receiver interrupt as long as it wants to receive characters. The transmitter interrupt is enabled only while characters are waiting in the output buffer. When an interrupt occurs, the interrupt routine must determine the cause: receiver data register full, transmitter data register empty, receiver error, or **/DCD0** pin high (channel 0 only). None of these interrupts is edge-triggered. Another interrupt will occur immediately if interrupts are re-enabled without disabling the condition causing the interrupt. The signal **/DCD0** is grounded on the CM7000.

Table 3-10 lists the interrupt vectors.

Table 3-10. Serial Port Interrupt Vectors

Address	Name	Description
0E	**SER0_VEC**	Z180 Serial Port 0 (higher priority)
10	**SER1_VEC**	Z180 Serial Port 1

Asynchronous Serial Communication Interface

The Z180 incorporates an asynchronous serial communication interface (ACSI) that supports two independent full-duplex channels.

ASCI Status Registers

A status register for each channel provides information about the state of

STAT0 (04H)

7	6	5	4	3	2	1	0
RDRF	OVRN	PE	FE	RIE	/DCD0	TDRE	TIE
R	R	R	R	R / W	R	R	R / W

STAT1 (05H)

7	6	5	4	3	2	1	0
RDRF	OVRN	PE	FE	RIE	CTS1E	TDRE	TIE
R	R	R	R	R / W	R	R	R / W

each channel and allows interrupts to be enabled and disabled.

/DCD0 (Data Carrier Detect)

This bit echoes the state of the **/DCD0** input pin for Channel 0. However, when the input to the pin switches from high to low, the data bit switches low only after STAT0 has been read. The receiver is held to reset as long as the input pin is held high. This function is not generally useful because an interrupt is requested as long as **/DCD0** is a 1. This forces the programmer to disable the receiver interrupts to avoid endless interrupts. A better design would cause an interrupt only when the state of the pin changes. This pin is tied to ground in the CM7000.

TIE (Transmitter Interrupt Enable)

This bit masks the transmitter interrupt. If set to 1, an interrupt is requested whenever TDRE is 1. The interrupt is not edge-triggered. Set this bit to 0 to stop sending. Otherwise, interrupts will be requested continuously as soon as the transmitter data register is empty.

TDRE (Transmitter Data Register Empty)

A 1 means that the channel is ready to accept another character. A high level on the **/CTS** pin forces this bit to 0 even though the transmitter is ready.

CTS1E (CTS Enable, Channel 1)

The signals RXS and CTS1 are multiplexed on the same pin. A 1 stored in this bit makes the pin serve the CTS1 function. A 0 selects the RXS function. (The pin RXS is the CSI/O data receive pin.) When RXS is selected, the CTS line has no effect.

RIE (Receiver Interrupt Enable)

A 1 enables receiver interrupts and 0 disables them. A receiver interrupt is requested under any of the following conditions: **/DCD0** (Channel 0 only), RDRF (read data register full), OVRN (overrun), PE (parity error), and FE (framing error). The condition causing the interrupt must be removed before the interrupts are re-enabled, or another interrupt will occur. Reading the receiver data register (RDR) clears the RDRF flag. The EFR bit in CNTLA is used to clear the other error flags.

FE (Framing Error)

A stop bit was missing, indicating scrambled data. This bit is cleared by the EFR bit in CNTLA.

PE (Parity Error)

Parity is tested only if MOD1 in CNTLA is set. This bit is cleared by the EFR bit in CNTLA.

OVRN (Overrun Error)

Overrun occurs when bytes arrive faster than they can be read from the receiver data register. The receiver shift register (RSR) and receiver data register (RDR) are both full. This bit is cleared by the EFR bit in CNTLA.

RDRF (Receiver Data Register Full)

This bit is set when data is transferred from the receiver shift register to the receiver data register. It is set even when one of the error flags is set, in which case defective data is still loaded to RDR. The bit is cleared when the receiver data register is read, when the **/DCD0** input pin is high, and by RESET and IOSTOP.

ASCI Control Register A

Control Register A affects various aspects of the asynchronous channel operation.

CNTLA0 (00H)

7	6	5	4	3	2	1	0
MPE	RE	TE	/RTS0	MPBR/ EFR	MOD2	MOD1	MOD0
R / W	R / W	R / W	R / W	R / W	R / W	R / W	R / W

CNTLA1 (01H)

7	6	5	4	3	2	1	0
MPE	RE	TE	CKA1D	MPBR/ EFR	MOD2	MOD1	MOD0
R / W	R / W	R / W	R / W	R / W	R / W	R / W	R / W

MOD0–MOD2 (Data Format Mode Bits)

MOD0 controls stop bits: 0 ⇒ 1 stop bit, 1 ⇒ 2 stop bits. If 2 stop bits are expected, then 2 stop bits must be supplied.

MOD1 controls parity: 0 ⇒ parity disabled, 1 ⇒ parity enabled. (See PEO in ASCI Control Register B for even/odd parity control.)

MOD2 controls data bits: 0 ⇒ 7 data bits, 1 ⇒ 8 data bits.

MPBR/EFR (Multiprocessor Bit Receive/Error Flag Reset)

Reads and writes on this bit are unrelated. Storing a byte when this bit is 0 clears all the error flags (OVRN, FE, PE). Reading this bit obtains the value of the MPB bit for the last read operation when the multiprocessor mode is enabled.

/RTS0 (Request to Send, Channel 0)

Store a 1 in this bit to set the RTS0 line from the Z180 high. This bit is essentially a 1-bit output port without other side effects.

CKA1D (CKA1 Disable)

This bit controls the function assigned to the multiplexed pin (CKA1/ ~TEND0): 1 ⇒ ~TEND0 (a DMA function) and 0 ⇒ CKA1 (external clock I/O for Channel 1 serial port).

TE (Transmitter Enable)

This bit controls the transmitter: 1 ⇒ transmitter enabled, 0 ⇒ transmitter disabled. When this bit is cleared, the processor aborts the operation in progress, but does not disturb TDR or TDRE.

RE (Receiver Enable)

This bit controls the receiver: 1 ⇒ enabled, 0 ⇒ disabled. When this bit is cleared, the processor aborts the operation in progress, but does not disturb RDRF or the error flags.

MPE (Multiprocessor Enable)

This bit (1 ⇒ enabled, 0 ⇒ disabled) controls multiprocessor communication mode which uses an extra bit for selective communication when a number of processors share a common serial bus. This bit has effect only when MP in Control Register B is set to 1. When this bit is 1, only bytes with the MP bit on will be detected. Others are ignored. If this bit is 0, all bytes received are processed. Ignored bytes do not affect the error flags or RDRF.

ASCI Control Register B

Control Register B configures the multiprocessor mode, parity and baud rate for each channel.

CNTLB0 (02H) and CNTLB1 (03H)

7	6	5	4	3	2	1	0
MPBT	MP	/CTS PS	PEO	DR	SS2	SS1	SS0
R / W	R / W	R / W	R / W	R / W	R / W	R / W	R / W

SS (Source/Speed Select)

Coupled with the prescaler (PS) and the divide ratio (DR), the SS bits select the source (internal or external clock) and the baud rate divider, as shown in Table 3-11.

Table 3-11. Baud Rate Divide Ratios for Source/Speed Select Bits

SS2	SS1	SS0	Divide Ratio
0	0	0	÷ 1
0	0	1	÷ 2
0	1	0	÷ 4
0	1	1	÷ 8
1	0	0	÷ 16
1	0	1	÷ 32
1	1	0	÷ 64
1	1	1	external clock*

* May not exceed system clock ÷ 40

The prescaler (PS), the divide ratio (DR), and the SS bits form a baud-rate generator, as shown in Figure 3-17.

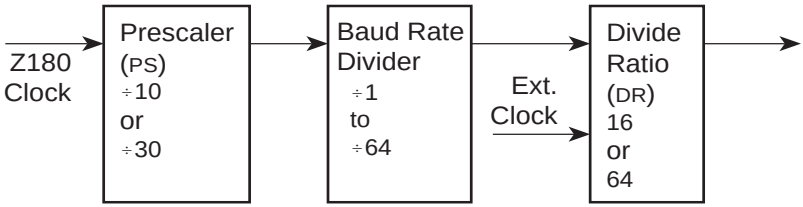


Figure 3-17. Z180 Baud-Rate Generator

DR (Divide Ratio)

This bit controls one stage of frequency division in the baud-rate generator. If 1 then divide by 64. If 0 then divide by 16. This is the only control bit that can affect the external clock frequency.

PEO (Parity Even/Odd)

This bit affects parity: 0 ⇒ even parity, 1 ⇒ odd parity. It is effective only if MOD1 is set in CNTLA (parity enabled).

/CTS/PS (Clear to Send/Prescaler)

When read, this bit gives the state of external pin **/CTS**: 0 ⇒ low, 1 ⇒ high. When **/CTS** is high, RDRF is inhibited so that incoming receive characters are ignored. When written, this bit has an entirely different function. If a 0 is written, the baud-rate prescaler is set to divide by 10. If a 1 is written, it is set to divide by 30.

MP (Multiprocessor Mode)

When this bit is set to 1, the multiprocessor mode is enabled. The multiprocessor bit (MPB) is included in transmitted data as shown here.

start bit, data bits, MPB, stop bits

The MPB is 1 when MPBT is 1 and 0 when MPBT is 0.

MPBT (Multiprocessor Bit Transmit)

This bit controls the multiprocessor bit (MPB). When MPB is 1, transmitted bytes will get the attention of other units listening only for bytes with MPB set.

Table 3-12 relates the Z180's ASCI Control Register B to the baud rate.

Table 3-12. Baud Rates for ASCI Control Register B

ASCI B Value	Baud Rate at 9.216 MHz (bps)	Baud Rate at 18.432 MHz (bps)	ASCI B Value	Baud Rate at 9.216 MHz (bps)	Baud Rate at 18.432 MHz (bps)
00	57,600	115,200	20	19,200	38,400
01	28,800	57,600	21	9600	19,200
02 or 08	14,400	28,800	22 or 28	4800	9600
03 or 09	7200	14,400	23 or 29	2400	4800
04 or 0A	3600	7200	24 or 2A	1200	2400
05 or 0B	1800	3600	25 or 2B	600	1200
06 or 0C	900	1800	26 or 2C	300	600
0D	450	900	2D	150	300
0E	225	450	2E	75	150

CHAPTER 4: DESIGN CONSIDERATIONS

Bus Loading

When designing an interface, pay close attention to the capacitive loading of each CM7000 signal. Tables 4-1 and 4-2 give the loading (in picofarads) for the CM7100 and CM7200, for the Prototyping Board, and for the

Table 4-1. CM7100 Capacitive Loading

Signal	Capacitative Load (pF)								
	CM7100		Prototyping Board		Development Board		7100 + Proto Board	7100 + Dev Board	7100 + Both Boards
	Typ.	Max.	Typ.	Max.	Typ.	Max.			
A00	26	44	12	40	19	30	38	45	57
A01	26	44	3	10	19	30	29	45	48
A02	26	44	3	10	19	30	29	45	48
A03	26	44	0	0	14	20	26	40	40
A04	14	20	0	0	14	20	14	28	28
A05	14	20	0	0	14	20	14	28	28
D0	33	54	9	30	29	52	42	62	71
D1	28	46	6	20	29	52	34	57	63
D2	28	46	6	20	24	42	34	52	58
D3	28	46	6	20	24	42	34	52	58
D4	16	22	6	20	21	32	32	37	43
D5	16	22	6	20	21	32	32	37	43
D6	16	22	6	20	21	32	32	37	43
D7	16	22	6	20	21	32	32	37	43
/RD	17	32	3	10	10	20	20	27	30
/WR	17	32	3	10	10	20	20	27	30
/CS1	0	0	3	10	—	—	3	0	3
/CS2	0	0	3	10	—	—	3	0	3

continued…

Development Board. Be sure to add the loads for the devices you are using in your custom system to these numbers to determine the total load. When loads exceed specifications, degraded performance will occur, and timing requirements might not be met.

Table 4-1. CM7100 Capacitive Loading (concluded)

Signal	Capacitative Load (pF)								
	CM7100		Prototyping Board		Development Board		7100 + Proto Board	7100 + Dev Board	7100 + Both Boards
	Typ.	Max.	Typ.	Max.	Typ.	Max.			
/CS3	0	0	3	10	—	—	3	0	3
/CS4	0	0	0	0	—	—	0	0	3
/CS5	0	0	0	0	—	—	0	0	3
/CS6	0	0	0	0	—	—	0	0	3
/IORQ	8	18	0	0	5	10	8	13	13
E	0	0	3	10	—	—	3	0	3
/WAIT	0	0	0	0	—	—	0	0	0
RXA1	0	0	5	10	—	—	5	0	5
TXA1	0	0	5	10	—	—	5	0	5
RXA0	0	0	5	10	—	—	5	0	5
TXA0	0	0	5	10	—	—	5	0	5
/REQ0	0	0	0	0	—	—	0	0	0
/REQ1	0	0	0	0	—	—	0	0	0
/RESET	12	24	3	10	—	—	15	12	15
/CTS0	0	0	5	10	—	—	5	0	5
/INT1	0	0	0	0	—	—	0	0	0
/INT0	0	0	0	0	—	—	0	0	0
PFI	27	36	0	0	—	—	27	27	27
VBAT	5	10	0	0	—	—	5	5	5

Table 4-2. CM7200 Capacitive Loading

Signal	Capacitative Load (pF)				
	CM7200		Prototyping Board		7200 + Proto Board
	Typ.	Max.	Typ.	Max.	
A00	26	44	12	40	38
A01	26	44	3	10	29
A02	26	44	3	10	29
A03	26	44	0	0	26
A04	14	20	0	0	14
A05	14	20	0	0	14
D0	33	54	9	30	42
D1	28	46	6	20	34
D2	28	46	6	20	34
D3	28	46	6	20	34
D4	16	22	6	20	32
D5	16	22	6	20	32
D6	16	22	6	20	32
D7	16	22	6	20	32
/RD	17	32	3	10	20
/WR	17	32	3	10	20
/CS1	0	0	3	10	3
/CS2	0	0	3	10	3

continued…

Table 4-2. CM7200 Capacitive Loading (concluded)

Signal	Capacitative Load (pF)				
	CM7200		Prototyping Board		7200 + Proto Board
	Typ.	Max.	Typ.	Max.	
/CS3	0	0	3	10	3
/CS4	0	0	0	0	0
/CS5	0	0	0	0	0
/CS6	0	0	0	0	0
/IORQ	8	18	0	0	8
E	0	0	3	10	3
/WAIT	0	0	0	0	0
RXA1	0	0	5	10	5
TXA1	0	0	5	10	5
RXA0	0	0	5	10	5
TXA0	0	0	5	10	5
/REQ0	0	0	0	0	0
/REQ1	0	0	0	0	0
/RESET	12	24	3	10	15
/CTS0	0	0	5	10	5
/INT1	0	0	0	0	0
/INT0	0	0	0	0	0
PFI	27	36	0	0	27
VBAT	5	10	0	0	5

The timing specifications for the Z180's outputs assume driving no more than a 100 pF load. Each 50 pF above this nominal load adds a 10 ns delay for the signal to switch, up to 200 pF for data lines, and 100 pF for address and control lines. The timing is measured to a 1.5 V transition for the Z180.

All measurements were made with an additional load of 100 pF added to each address and data line. This allows you to add up to 100 pF with your interface hardware and realize the performance specified in Tables 4-1 and 4-2.

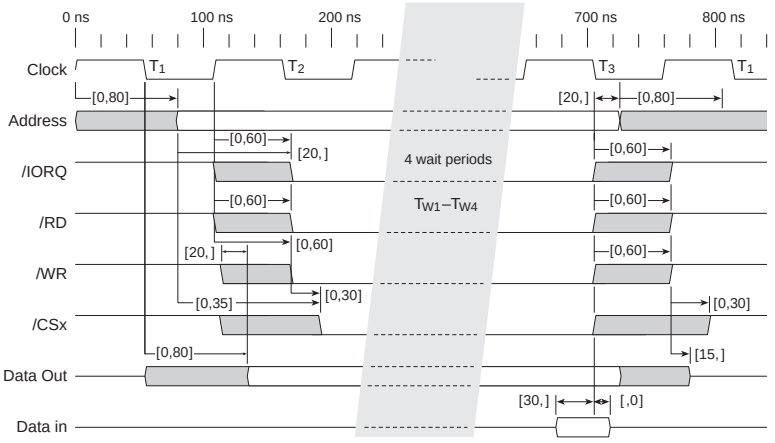
Bus Timing

Hardware used with the CM7000 must meet the timing requirements of the CM7000's I/O cycles to ensure reliability. The I/O cycles have four wait states by default. Four wait states are the maximum number programmable in the Z180. Normally there is no need to change this default. Custom hardware can insert more wait states by pulling the **/WAIT** line low on header H2.

The ***Z180 MPU User's Manual*** provides more detailed information on hardware-generated wait-states.

Standard I/O Cycles

The standard (four wait states) I/O cycle timing shown in Figure 4-1 is for the 9.216 MHz CM7000. Figure 4-2 shows the standard I/O cycle timing for 18.432 MHz. The format for numbers in parenthesis on the drawing is [min,max] in nanoseconds. The grey areas indicate where the signals may change.

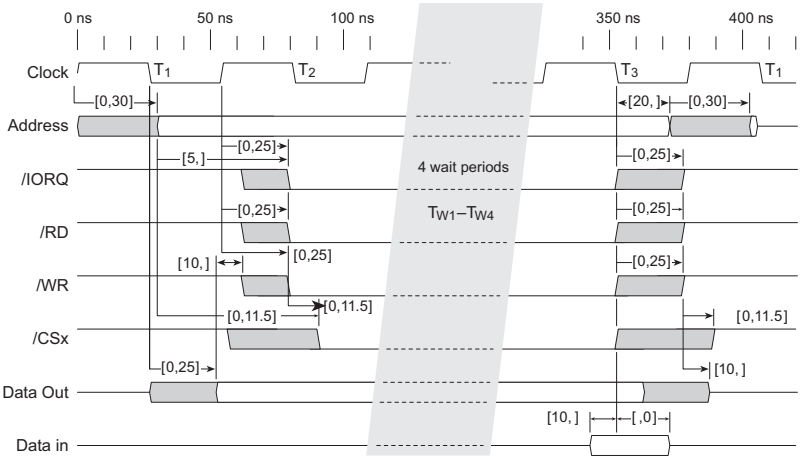


9.216 MHz I/O Read & Write Timing
CPU = 8 MHz
Period = 108.507 ns
Note: /IOC = 0

For I/O read cycles, data must have a minimum setup time of 30 ns before the falling edge of T_3. Wait states must be added if this condition cannot be satisfied.

For CPU and DMA cycles that access external I/O, 1 to 4 wait states are automatically inserted, depending on the programmed value of DCNTL bits 4 and 5.

Figure 4-1. Standard Cycle Timing at 9.216 MHz (4 wait states)



18.432 MHz I/O Read & Write Timing
CPU = 20 MHz
Period = 54.253 ns

For I/O read cycles, data must have a minimum setup time of 10 ns before the falling edge of T_3. Wait states must be added if this condition cannot be satisfied.

For CPU and DMA cycles that access external I/O, 1 to 4 wait states are automatically inserted, depending on the programmed value of DCNTL bits 4 and 5.

Figure 4-1. Standard Cycle Timing at 18.432 MHz (4 wait states)

Wait State Insertion

The **/WAIT** line inserts wait states into an I/O request cycle under the control of the custom hardware. The Z180 CPU samples the **/WAIT** line at the falling edge of T_2 or T_{WAIT} clock cycles.

System Power

The CM7000 requires a regulated +5 V power source to operate. Depending on the amount of current required by the application, different regulators can be used supply this voltage. The Prototyping Board has an onboard LM340-T5 to provide the necessary +5 V.

The LM340-T5 is an inexpensive linear regulator that is easy to use. Its major drawback is its inefficiency, which is directly proportional to the voltage drop across it. This voltage drop causes heat and wastes power. The LM340-T5 regulator comes in several packages having different heat-dissipation characteristics. TO-220 packages are most typical.

Appendix E, “Sample Applications,” provides an example of using an LM340.

A switching power supply may be used in applications where better efficiency is desirable. The LM2575 is an example of an easy-to-use switcher. This part greatly reduces the heat dissipation of the regulator. The drawback in using a switcher is the increased cost.

Power-On and Reset Management

The designer employing the CM7130 or CM7230 needs to provide a supervisory circuit that monitors the power supply and develops a power-on reset signal, **/RESET**.

Upon power up, **/RESET** needs to remain low for at least 50 ms after V_{cc} rises above an appropriate reset threshold. This delay allows time for the power supply and microprocessor to stabilize. The nominal reset threshold is 4.65 V. Figure 4-3 illustrates the reset sequence.

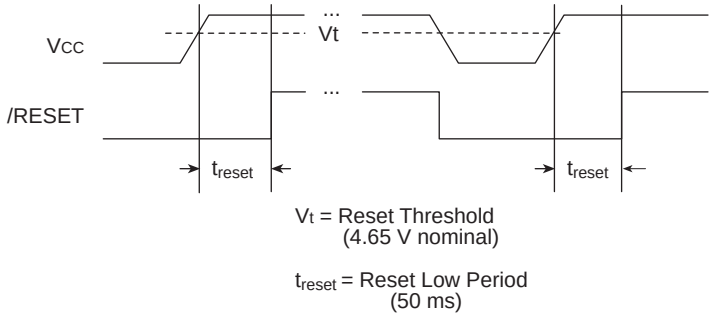


Figure 4-3. CM7000 Reset Sequence

On powerdown, the **/RESET** signal should remain low until V_{cc} drops below 1 V. Keeping **/RESET** low until the power supply voltage drops below 1 V to ensure that the microprocessor stays in a stable condition, preventing it from emitting spurious outputs.

The VBAT line on all versions of the CM7000 needs to be grounded if VBAT is not used. The battery-switchover circuit in the ADM691 supervisor IC compares V_{cc} to the VBAT input, and connects VRAM to whichever is higher (the switchover occurs when V_{cc} is 50 mV higher than VBAT). Allowing VBAT to float by not connecting it can cause erratic operation.

The CM7130 and CM7230 have no ADM691 supervisor IC, and so the SRAM and the real-time clock (RTC) cannot be battery-backed.

Watchdog Timer

The watchdog timer will time out after a nominal 1.0 second (1.0 second minimum, 2.25 seconds maximum). “Hitting” the watchdog timer every second is, therefore, a conservative method of avoiding a watchdog timeout.

I/O Addressing

When software places an address (0x4000–0x41FF) on the address lines, the decoder (CM7100 = U7, CM7200 = U6) and PAL (CM7100 = U6, CM7200 = U4) decode the address. Address bits 0–5 appear on the header. Address bits 6–8 select one of eight output lines, which are listed in Table 4-3.

Table 4-3. Output Addresses

Address Range	Output Line
0x4000–403F	**/CS1**
0x4040–407F	**/CS2**
0x4080–40BF	**/CS3**
0x40C0–40FF	**/CS4**
0x4100–413F	**/CS5**
0x4140–417F	**/CS6**
0x4180–41BF	RTC (real-time clock)
0x41C0–41FF	WDI (Watchdog)

The selector decodes ***all*** addresses in the range 0x4000–7FFF, that is, addresses 0x4200–423F, 0x4400–443F ... 0x7E00–7E3F all select **/CS1**. Addresses 0x4240–427F select **/CS2**, and so on. Whichever range is selected, the program can select exactly 384 I/O addresses using the following bits.

15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
0	1	–	–	–	–	–	c	c	c	a	a	a	a	a	a

where “c” represents chip select, “a” represents address bits, and “–” bits can be ignored (for your I/O addresses).

All chip selects must be **/RD** and/or **/WR** qualified if **/INT0** is used. Failure to qualify chip selects can result in false input/output cycles because of the unqualified **/IOE** cycle (that is, **/IOE** without **/RD** or **/WR**), which occurs during the interrupt acknowledge of **/INT0**.

APPENDIX A: TROUBLESHOOTING

Appendix A provides procedures for troubleshooting system hardware and software. The sections include the following topics.

- Out of the Box
- Dynamic C Will Not Start
- Dynamic C Loses Serial Link
- CM7000 Repeatedly Resets
- Common Programming Errors

Out of the Box

Check the items mentioned in this section before starting development.

- Verify that the CM7000 runs in standalone mode before connecting any devices.
- Verify that the entire host system has good, low-impedance, separate grounds for analog and digital signals. Often the CM7000 is connected between the host PC and another device. Any differences in ground potential from unit to unit can cause serious problems that are hard to diagnose.
- Do not connect analog ground to digital ground anywhere.
- Double-check the connecting ribbon cables to ensure that all wires go to the correct screw terminals on the CM7000.
- Verify that the host PC's COM port works by connecting a good serial device to the COM port. Remember that COM1/COM3 and COM2/COM4 share interrupts on a PC. User shells and mouse drivers, in particular, often interfere with proper COM port operation. For example, a mouse running on COM1 can preclude running Dynamic C on COM3.
- Use the supplied Z-World power supply. If another power supply must be used, verify that it has enough capacity and filtering to support the CM7200.
- Use the supplied Z-World cables. The most common fault of user-made cables is failure to properly assert CTS. Without CTS being asserted, the CM7000's RS-232 port will not transmit. Assert CTS by either connecting the RTS signal of the PC's COM port or looping back the CM7000's RTS.
- Experiment with each peripheral device connected to the CM7000 to determine how it appears to the CM7000 when powered up, powered down, and/or when its connecting wiring is open or shorted.

Dynamic C Will Not Start

In most situations, when Dynamic C will not start, an error message announcing a communication failure will be displayed. The following list describes situations causing an error message and possible resolutions.

- *Wrong Baud Rate* — Either Dynamic C's baud rate is not set correctly, or the CM7000's baud rate is not set correctly.
- *Wrong Communication Mode* — Both sides must be talking RS-232.
- *Wrong COM Port* — A PC generally has two serial ports, COM1 and COM2. Specify the one being used in the Dynamic C "Target Setup" menu. Use trial and error, if necessary.
- *Wrong Operating Mode* — Communication with Dynamic C will be lost when the CM7000 is configured for standalone operation. Reconfigure the board for programming mode as described in Chapter 2, "Getting Started."
- *Wrong Memory Size* — Jumper J3 on the CM7100 and jumper JP1 on the Development Board set the size of the EPROM and SRAM respectively.

If all else fails, connect the serial cable to the CM7000 after power up. If the PC's RS-232 port supplies a large current (most commonly on portable and industrial PCs), some RS-232 level converter ICs go into a nondestructive latch-up. Connect the RS-232 cable after powerup to eliminate this problem.

Dynamic C Loses Serial Link

If the application disables interrupts for a period greater than 50 ms, Dynamic C will lose its serial link with the application. Make sure that interrupts are not disabled for a period greater than 50 ms.

CM7000 Repeatedly Resets

The CM7000 resets every 1.0 second if the watchdog timer is not "hit." If a program does not "hit" the watchdog timer, then the program will have trouble running in standalone mode. To "hit" the watchdog, make a call to the Dynamic C library function **`hitwd`**.

Common Programming Errors

- Values for constants or variables out of range. Table A-1 lists acceptable ranges for variables and constants.

Table A-1. Ranges of Dynamic C Function Types

Type	Range
`int`	–32,768 (-2^{15}) to +32,767 ($2^{15} - 1$)
`long int`	–2,147,483,648 (-2^{31}) to +2147483647 ($2^{31} - 1$)
`float`	-6.805646×10^{38} to $+6.805646 \times 10^{38}$
`char`	0 to 255

- Mismatched "types." For example, the literal constant **3293** is of type **int** (16-bit integer). However, the literal constant **3293.0** is of type **float**. Although Dynamic C can handle some type mismatches, avoiding type mismatches is the best practice.
- Counting up from, or down to, one instead of zero. In software, ordinal series often begin or terminate with zero, not one.
- Confusing a function's definition with an instance of its use in a listing.
- Not ending statements with semicolons.
- Not inserting commas as required in functions' parameter lists.
- Leaving out ASCII space character between characters forming a different legal—but unwanted—operator.
- Confusing similar-looking operators such as **&&** with **&**, == with =, and // with /.
- Inadvertently inserting ASCII nonprinting characters into a source-code file.

APPENDIX B: ***SPECIFICATIONS***

Appendix B provides comprehensive CM7000 physical, electronic and environmental specifications.

Electrical and Mechanical Specifications

Table B-1 lists electrical, mechanical, and environmental specifications for the CM7100 and CM7200 cores.

Table B-1. CM7100 and CM7200 General Specifications

Parameter		Specification
Board Size	CM7100	1.80" × 2.05" × 0.85" (46 mm × 52 mm × 22 mm)
	CM7200	1.80" × 2.05" × 0.63" (46 mm × 52 mm × 18 mm)
Operating Temperature		-40°C to 70°C
Humidity		5% to 95%, noncondensing
Power		5 V DC, 100 mA @ 9.216 MHz 5 V DC, 130 mA @ 18.432 MHz
Configurable I/O		Six groups of 64 I/O addresses
Digital Inputs		See Configurable I/O
Digital Outputs		See Configurable I/O
Analog Inputs		No
Analog Outputs		No
Resistance Measure-ment Input		No
Processor		Z180
Clock		18.432 MHz
SRAM		128K standard, surface-mounted
EPROM		CM7100 option up to 512K
Flash EPROM		CM7200 128K
EEPROM		CM7100 512 bytes
Counters		Two, using DMA channels
Serial Ports		Two TTL-level UARTs
Serial Rate		Up to 57,600 bps
Watchdog		Yes
Time/Date Clock		Yes
Backup Battery		Header H2 pin 3 provides connection for user-supplied backup battery on main controller

Mechanical Dimensions

Figure B-1 shows the mechanical dimensions for the CM7100 and the CM7200.

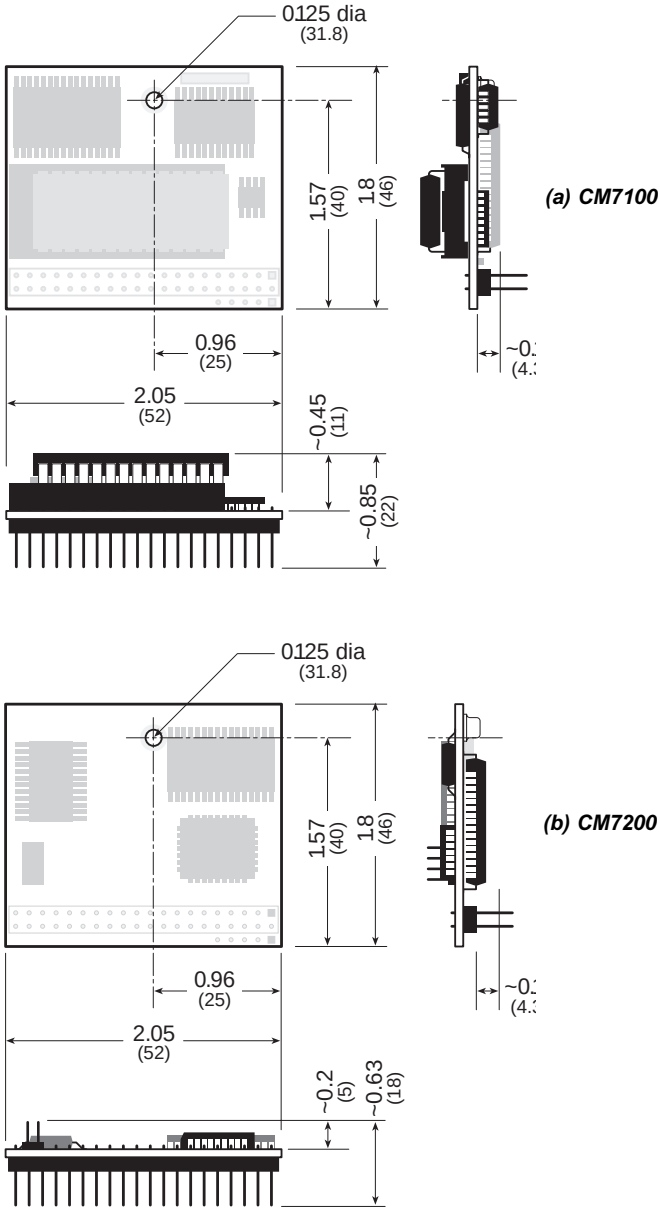


Figure B-1. Mechanical Dimensions

Jumpers and Headers

CM7100

Table B-2 lists the roles of the headers and presents the jumper configurations for the CM7100. The header locations are shown in Figure B-2.

Table B-2. CM7100 Headers and Jumpers

Header	Description	
H1	5-point interface extension with plated through-holes for easy soldering.	
H2	40-pin interface (fits in socket H3 on the Prototyping Board).	
H3	6-pin connector located underneath EPROM position (U3), used only for the Development Board with EPROM removed.	
J1	Generally, disregard J1. However, if a backup battery or super capacitor is used, make sure J1 is not connected. J1 may be jumpered to ground VBAT only when the ADM691 supervisor is not installed. [Factory default (except CM7130)—not connected.]	
J2	Connect only when there is no ADM691 supervisor, otherwise RAM will not operate. [Factory default (except CM7130)—not connected.]	
J3	1–2	Connect for any other use.
	2–3	Connect for EPROM ≥ 128K or when the Development Board is in use (factory default—pins 2–3 connected).

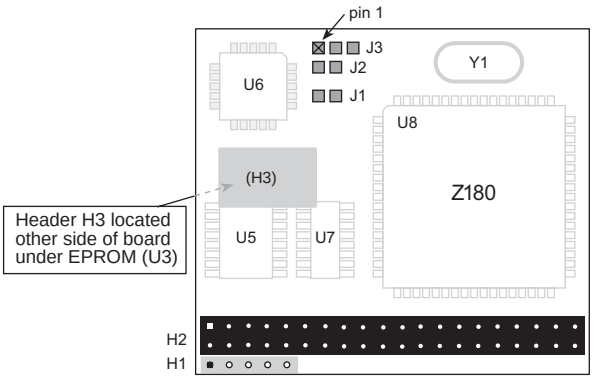


Figure B-2. Locations of CM7100 Headers

CM7200

Table B-3 lists the roles of the headers and presents the jumper configurations for the CM7200. The header locations are shown in Figure B-3.

Table B-3. CM7200 Headers and Jumpers

Header	Description
H1	5-point interface extension with plated through-holes for easy soldering.
H2	40-pin interface (fits in socket H3 on the Prototyping Board).
H3	6-pin connector located underneath EPROM position (U3), used only for the Development Board with EPROM removed.
J1	Generally, disregard J1. However, if a backup battery or super capacitor is used, make sure J1 is not connected. J1 may be jumpered to ground VBAT only when the ADM691 supervisor is not installed. [Factory default (except CM7230)—not connected.]
J2	Connect only when there is no ADM691 supervisor, otherwise RAM will not operate. [Factory default (except CM7230)—not connected.]
JP1	8-pin header for SIB2 connection.

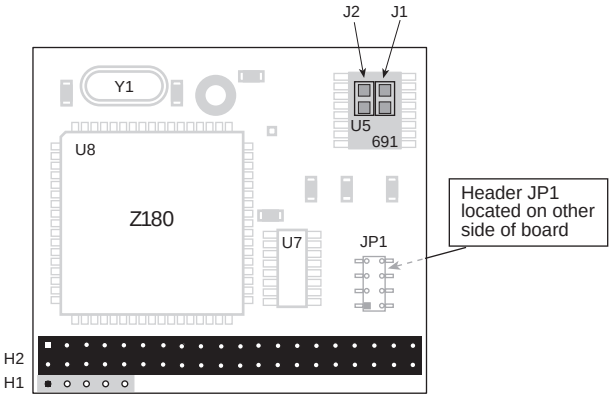


Figure B-2. Locations of CM7200 Headers

Blank

APPENDIX C: MEMORY, I/O MAP, AND INTERRUPT VECTORS

Appendix C provides detailed information on memory, provides an I/O map, and lists the interrupt vectors.

CM7000 Memory

Figure C-1 shows the memory map of the 1M address space.

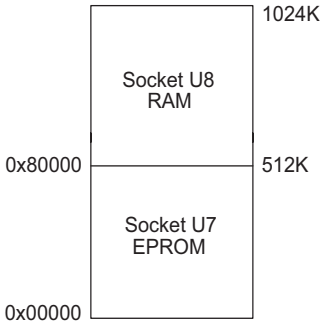


Figure C-1. Memory Map of 1M Address Space

Figure C-2 shows the memory map within the 64K virtual space.

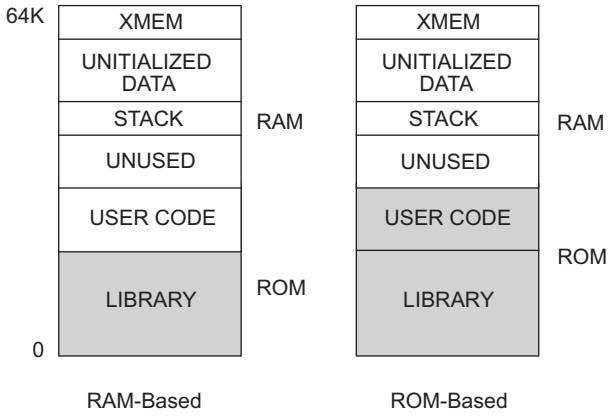


Figure C-2. Memory Map of 64K Virtual Space

The various registers in the input/output (I/O) space can be accessed in Dynamic C by the symbolic names listed below. These names are treated as unsigned integer constants. The Dynamic C library functions **inport** and **outport** access the I/O registers directly.

```
data_value = inport( CNTLA0 );
outport( CNTLA0, data_value );
```

Execution Timing

The times reported in Table C-1 were measured using Dynamic C and they reflect the use of Dynamic C libraries. The time required to fetch the arguments from memory, but not to store the result, is included in the timings. The times are for a 9.216 MHz clock with 0 wait states.

Table C-1. CM7000 Execution Times for Dynamic C

Operation	Execution Time (µs)
DMA copy (per byte)	0.73
Integer assignment (`i=j;`)	3.4
Integer add (`j+k;`)	4.4
Integer multiply (`j*k;`)	18
Integer divide (`j/k;`)	90
Floating add (`p+q;`) (typical)	85
Floating multiply (`p*q;`)	113
Floating divide (`p/q;`)	320
Long add (`l+m;`)	28
Long multiply (`l*m;`)	97
Long divide (`l/m;`)	415
Floating square root (`sqrt(q);`)	849
Floating exponent (`exp(q);`)	2503
Floating cosine (`cos(q);`)	3049

The execution times can be adjusted proportionally for clock speeds other than 9.216 MHz. Operations involving one wait state will slow the execution speed about 25%.

Memory Map

Input/Output Select Map

The Dynamic C library functions **IBIT**, **ISET** and **IRES** in the **BIOS.LIB** library allow bits in the I/O registers to be tested, set, and cleared. Both 16-bit and 8-bit I/O addresses can be used.

Z180 Internal Input/Output Register Addresses 0x00-0x3F

The internal registers for the I/O devices built into to the Z180 processor occupy the first 40 (hex) addresses of the I/O space. These addresses are listed in Table C-2.

Table C-2. Z180 Internal I/O Registers Addresses 0x00–0x3F

Address	Name	Description
0x00	CNTLA0	Serial Channel 0, Control Register A
0x01	CNTLA1	Serial Channel 1, Control Register A
0x02	CNTLB0	Serial Channel 0, Control Register B
0x03	CNTLB1	Serial Channel 1, Control Register B
0x04	STAT0	Serial Channel 0, Status Register
0x05	STAT1	Serial Channel 1, Status Register
0x06	TDR0	Serial Channel 0, Transmit Data Register
0x07	TDR1	Serial Channel 1, Transmit Data Register
0x08	RDR0	Serial Channel 0, Receive Data Register
0x09	RDR1	Serial Channel 1, Receive Data Register
0x0A	CNTR	Clocked Serial Control Register
0x0B	TRDR	Clocked Serial Data Register
0x0C	TMDR0L	Timer Data Register Channel 0, least
0x0D	TMDR0H	Timer Data Register Channel 0, most
0x0E	RLDR0L	Timer Reload Register Channel 0, least
0x0F	RLDR0H	Timer Reload Register Channel 0, most
0x10	TCR	Timer Control Register
0x11–0x13	—	Reserved
0x14	TMDR1L	Timer Data Register Channel 1, least
0x15	TMDR1H	Timer Data Register Channel 1, most
0x16	RLDR1L	Timer Reload Register Channel 1, least
0x17	RLDR1H	Timer Reload Register Channel 1, most

continued…

Table C-2. Z180 Internal I/O Registers Addresses 0x00–0x3F (concluded)

Address	Name	Description
0x18	FRC	Free-running counter
0x19–0x1F	—	Reserved
0x20	SAR0L	DMA source address Channel 0, least
0x21	SAR0H	DMA source address Channel 0, most
0x22	SAR0B	DMA source address Channel 0, extra bits
0x23	DAR0L	DMA destination address Channel 0, least
0x24	DAR0H	DMA destination address Channel 0, most
0x25	DAR0B	DMA destination address Channel 0, extra bits
0x26	BCR0L	DMA Byte Count Register Channel 0, least
0x27	BCR0H	DMA Byte Count Register Channel 0, most
0x28	MAR1L	DMA Memory Address Register Channel 1, least
0x29	MAR1H	DMA Memory Address Register Channel 1, most
0x2A	MAR1B	DMA Memory Address Register Channel 1, extra bits
0x2B	IAR1L	DMA I/O Address Register Channel 1, least
0x2C	IAR1H	DMA I/O Address Register Channel 1, most
0x2D	—	Reserved
0x2E	BCR1L	DMA Byte Count Register Channel 1, least
0x2F	BCR1H	DMA Byte Count Register Channel 1, most
0x30	DSTAT	DMA Status Register
0x31	DMODE	DMA Mode Register
0x32	DCNTL	DMA/WAIT Control Register
0x33	IL	Interrupt Vector Low Register
0x34	ITC	Interrupt/Trap Control Register
0x35	—	Reserved
0x36	RCR	Refresh Control Register
0x37	—	Reserved
0x38	CBR	MMU Common Base Register
0x39	BBR	MMU Bank Base Register
0x3A	CBAR	MMU Common/ Bank Area Register
0x3B–0x3D	—	Reserved
0x3E	OMCR	Operation Mode Control Register
0x3F	ICR	I/O Control Register

Epson 72423 Timer Registers 0x4180–0x418F

Table C-3 lists the Epson 72423 timer registers.

Table C-3. Epson 72423 Timer Registers 0x4180–0x418F

Address	Name	Data Bits	Description
4180	SEC1	D0–D7	seconds
4181	SEC10	D0–D7	10 seconds
4182	MIN1	D0–D7	minutes
4183	MIN10	D0–D7	10 minutes
4184	HOUR1	D0–D7	hours
4185	HOUR10	D0–D7	10 hours
4186	DAY1	D0–D7	days
4187	DAY10	D0–D7	10 days
4188	MONTH1	D0–D7	months
4189	MONTH10	D0–D7	10 months
418A	YEAR1	D0–D7	years
418B	YEAR10	D0–D7	10 years
4180C	WEEK	D0–D7	weeks
418D	TREGD	D0–D7	Register D
418E	TREGE	D0–D7	Register E
418F	TREGF	D0–D7	Register F

Other Addresses

Table C-4 lists the other registers.

Table C-4. Other I/O Addresses

Address	Name	Data Bits	Description
2000	**SCL**	D0	EEPROM serial clock (CM7100)
4000–403F	**CS1**		Chip Select 1
4040–407F	**CS2**		Chip Select 2
4080–40BF	**CS3**		Chip Select 3
40C0–40FF	**CS4**		Chip Select 4
4100–413F	**CS5**		Chip Select 5
4140–417F	**CS6**		Chip Select 6
41C0–41FF	**WDOG**	D0	Watchdog
8000	**SDA_R**, **SDA_W**	D0	EEPROM serial data (CM7100)
8000	**FSHWE**		Flash EPROM write enable (CM7200)
A000	**NMI**	D0	Bit 0 is the power-failure (NMI) state.
C000	**WDO**		Watchdog output (CM7200)

I/O Addressing

Six "chip select" lines (**/CS1**–**/CS6**) and six address lines (A0–A5) appear on header H2. These lines give six groups of 64 (2^6) addresses, or 384 addresses. When an application places an address (0x4000–0x41FF) on the address lines, the decoder and the PAL decode the address.

Address bits 0–5 appear on header H2. Address bits 6–8 select one of eight output lines, the first six of which are **/CS1** to **/CS6**.

The selector decodes all addresses in the range 0x4000–7FFF, that is, I/O addresses 0x4200–423F, 0x4400–443F ... 0x7E00–7E3F all select **/CS1** too. Addresses 0x4240–427F select **/CS2**, and so on.

Whichever range is selected, the range provides exactly 384 addresses using the following bits.

15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
0	1	–	–	–	–	–	c	c	c	a	a	a	a	a	a

Here "c" represents chip select, "a" represents address bits, and "–" bits can be ignored (for I/O addresses).

Interrupt Vectors

Table C-5 presents a suggested interrupt vector map. Most of these interrupt vectors can be altered under program control. The addresses are given here in hex, relative to the start of the interrupt vector page, as determined by the contents of the I-register. These are the default interrupt vectors set by the boot code in the Dynamic C EPROM.

Table C-5. Interrupt Vectors for Z180 Internal Devices

Address	Name	Description
—	**NMI_VEC**	Used for power-failure detection
—	**INT0**	Available for use.
0x00	**INT1_VEC**	Available for use as expansion bus attention INT1 vector
0x02	**INT2_VEC**	Reserved for Development Board (CM7100), not available for use on CM7200
0x04	**PRT0_VEC**	PRT Timer Channel 0
0x06	**PRT1_VEC**	PRT Timer Channel 1
0x08	**DMA0_VEC**	DMA Channel 0
0x0A	**DMA1_VEC**	DMA Channel 1
0x0C	**CSI/O_VEC**	Available for programming (CM7200), not available for use on CM7100
0x0E	**SER0_VEC**	Asynchronous Serial Port Channel 0
0x10	**SER1_VEC**	Asynchronous Serial Port Channel 1

To "vector" an interrupt to a user function in Dynamic C, use a directive such as the following.

```
#INT_VEC 0x10 myfunction
```

The above example causes the interrupt at offset 10H (Serial Port 1 of the Z180) to invoke the function **myfunction()**. The function must be declared with the **interrupt** keyword, as shown below.

```
interrupt myfunction() {
      ...
}
```

Refer to the Dynamic C manuals for further details on interrupt functions.

Nonmaskable Interrupts

The **/NMI** line normally connects to the power-failure output of the ADM691 supervisor. A nonmaskable interrupt (NMI) occurs when **PFI** falls to 1.25 V ± 0.05 V. This advanced warning allows the program to perform some emergency processing before an unwanted power-down occurs.

The NMI is edge-sensitive and cannot be masked by software. When activated, the NMI disables all other interrupts (except TRAP), and begins execution from logical address 0x66.

If there is no ADM691 supervisor, connect **PFI** to **/NMI** directly by soldering U5 pads 9 and 10 together.

The following function shows how to handle a power-failure interrupt.

```
#JUMP_VEC NMI_VEC myint

interrupt retn myint(){
  body of interrupt routine
  while(!IBIT(WDO,0)){}
    // input voltage is still below the threshold
    // that triggered the NMI
  return;      // if just a power glitch, return
}
```

INT0

/INT0 is available for use and appears on header H2. **/INT0** has a 10 kΩ pull-up resistor. **/INT0** is set up in Mode 1. This setup requires a jump vector at address 0x0038 to identify its service routine.

INT1

/INT1 is available for use and appears on header H2. **/INT1** has a 10 kΩ pull-up resistor. **/INT1** is referenced by an interrupt vector at address 0x0.

INT2

/INT2 is reserved for the Development Board and does not appear on header H2. **/INT2** has a 10 kΩ pull-up resistor. An interrupt vector at address 0x2 points to **/INT2**.

Jump Vectors

These special interrupts occur in a different manner. Instead of loading the address of the interrupt routine from the interrupt vector, these interrupts cause a jump directly to the address of the vector, which will contain a jump instruction to the interrupt routine. This example illustrates a jump vector.

0x66 nonmaskable power-failure interrupt

Since nonmaskable interrupts (NMI) can be used for Dynamic C communications, an interrupt vector for power failure is normally stored just in front of the Dynamic C program. Use the command

```
#JUMP_VEC NMI_VEC name
```

to store the vector here.

The Dynamic C communication routines relay to this vector when the NMI is caused by a power failure rather than by a serial interrupt.

Interrupt Priorities

Table C-6 lists the interrupt priorities.

Table C-6. Interrupt Priorities

Interrupt Priorities	
(Highest Priority)	Trap (illegal instruction)
	NMI (nonmaskable interrupt)
	INT 0 (maskable interrupts, Level 0; three modes)
	INT 1 (maskable interrupts, Level 1; PLCBus attention line interrupt)
	INT 2 (maskable interrupts, Level 2)
	PRT Timer Channel 0
	PRT Timer Channel 1
	DMA Channel 0
	DMA Channel 1
	Z180 Serial Port 0
(Lowest Priority)	Z180 Serial Port 1

APPENDIX D: EEPROM

The CM7100 has a 512-byte EEPROM at location U1. The EEPROM is a nonvolatile memory and holds system constants. The CM7200 emulates this EEPROM in its flash EPROM, and executes all of Dynamic C's EEPROM function calls. Consequently, despite the dissimilar hardware, the memory map for both versions is exactly the same.

Table D-1 lists the constants that are stored and their locations.

Table D-1. EEPROM Arguments

Address	Definition
0x000	Operating mode: 0x1 = RS-232 0x2 = RS-485 with NMI 0x4 = execute user program on startup.
0x001	Baud rate code in multiples of 1200 bps.
0x100	Unit "serial number," BCD time and date with the following format: seconds, minutes, hours, day, month, year.
0x108	Microprocessor clock speed in multiples of 1200 Hz (16 bits). This value is 7680 for a 9.216 MHz clock, and is 15,360 for a 18.432 MHz clock.
0x16C	Long coefficient relating the clock speed of the microprocessor clock relative to the speed of the real-time clock. A nominal value is 107,374,182, which is 1/40 of a second where 232 is 1 second. This constant requires 4 bytes of EEPROM, stored least byte first.

The EEPROM has 512 bytes. Bytes 0–255 can be written to at any time, but the upper 256 bytes can be write-protected. To write-protect the upper 256 bytes of the CM7100's EEPROM, cut the trace shown in Figure D-1.

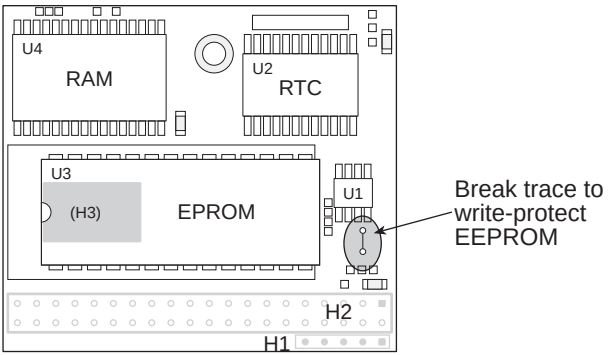


Figure D-1. Location of CM7100 Write-Protect Trace

Library Routines

The following library routines can be used to read and write the EEPROM:

```
int ee_rd( int address );
int ee_wr( int address, byte data );
```

The function **ee_rd** returns a data value or, if a hardware failure occurred, –1. The function **ee_wr** returns –1 if a hardware failure occurred, –2 if an attempt was made to write to the upper 256 bytes with the write-protect trace cut (enabled), or 0 to indicate a successful write. A write-protection violation does not wear out the EEPROM. These routines each require about 2 ms to execute. They are not re-entrant, that is, only one routine at a time will run.

The EEPROM has a rated lifetime of only 10,000 writes (unlimited reads). Do not write the EEPROM from within a loop. The EEPROM should be written to only in response to a human request for each write.

Blank

APPENDIX E: SERIAL INTERFACE BOARD 2

Appendix E provides technical details and baud rate configuration data for Z-World's Serial Interface Board 2 (SIB2).

Introduction

The Serial Interface Board 2 (SIB2) is an interface adapter used to program the CM7200. The SIB2 is contained in an ABS plastic enclosure, making it rugged and reliable. The SIB2 enables the CM7200 to communicate with Dynamic C via the Z180's clocked serial I/O (CSI/O) port, freeing the CM7200's serial ports for use by the application during programming and debugging.

The SIB2's 8-pin cable plugs into the target CM7200's processor through an aperture in the backplate, and a 6-conductor RJ-12 phone cable connects the SIB2 to the host PC. The SIB2 automatically selects its baud rate to match the communication rates established by the host PC (9600, 19,200, or 57,600 bps). However, the SIB2 determines the host's communication baud rate only on the first communication after reset. To change baud rates, change the COM baud rate, reset the target CM7200 (which also resets the SIB2), then select **Reset Target** from Dynamic C.

Chapter 2 provides detailed information on connecting the SIB2 to the CM7200.

The SIB2 receives power and resets from the target CM7200 via the 8-pin connector J1. Therefore, do not unplug the SIB2 from the target CM7200 while power is applied. To do so could damage both the CM7200 and the SIB2; additionally, the target may reset.

Never connect or disconnect the SIB2 with power applied to the CM7200.

The SIB2 consumes approximately 60 mA from the +5 V supply. The target-system current consumption therefore increases by this amount while the SIB2 is connected to the CM7200.

External Dimensions

Figure E-1 illustrates the external dimensions for the SIB2.

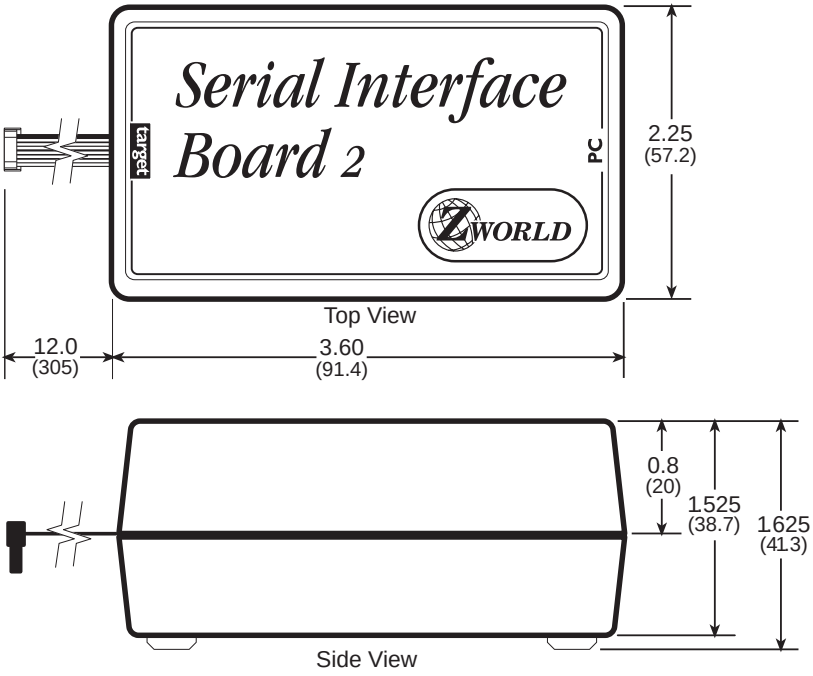


Figure E-1. SIB2 External Dimensions

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APPENDIX F: PROTOTYPING BOARD

Appendix F provides technical details for Z-World's Prototyping Board.

Description

The Prototyping Board is a 4.7" × 6.0" (119 mm × 152 mm) circuit board with the following features.

- A 2.2" × 3.3" (56 mm × 84 mm) prototyping area with 5 V and GND power rails.
- Power jack and voltage regulator.
- Backup battery
- Sample circuits.
- A 40-pin socket (H3) that accommodates either a CM7100 or a CM7200.
- Supports an optional 2 × 20 LCD and 2 × 6 keypad.

The CM7100 is programmed using the Prototyping Board's serial port, header H4. The Prototyping Board is also used with the CM7200, but programming is done via the CM7200 CSI/O port and a SIB2.

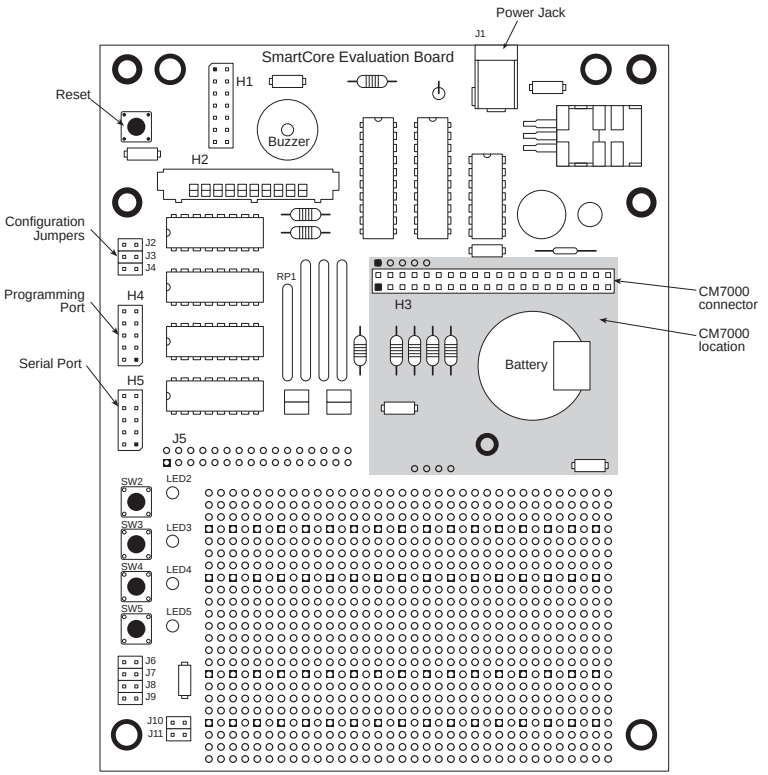

Figure F-1. Prototyping Board

Interfaces

Besides the 40-pin socket (header H3) where the CM7000 is plugged in, the Prototyping Board has two sets of plated through-holes for easy soldering. One set, J5, near the prototyping area, provides most of the signals from the CM7000. The other set, indicated "optional," comprises four signals that correspond to the interface extension H1 of the CM7000. Figure F-2 shows the location of the through-holes and provides a pinout.

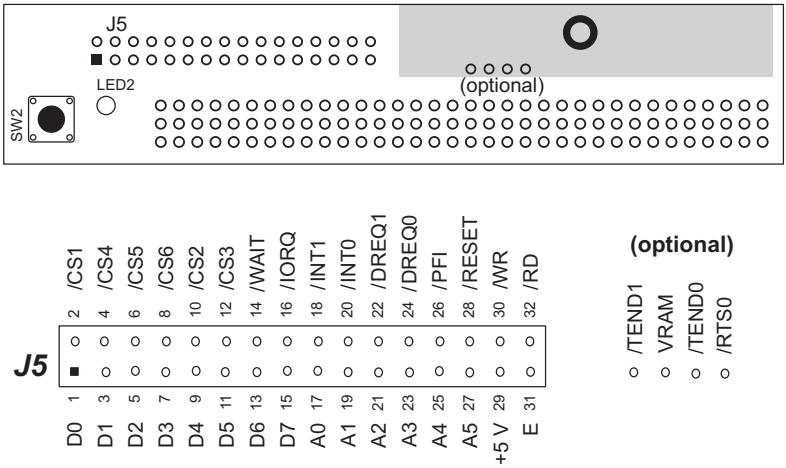

Figure F-2. Prototyping Board Interfaces

The Prototyping Board has two serial ports, H4 and H5, shown schematically in Figure F-3. A PC is connected to header H4 during program development for a CM7100. CM7200s are always connected to the host PC via the SIB2.

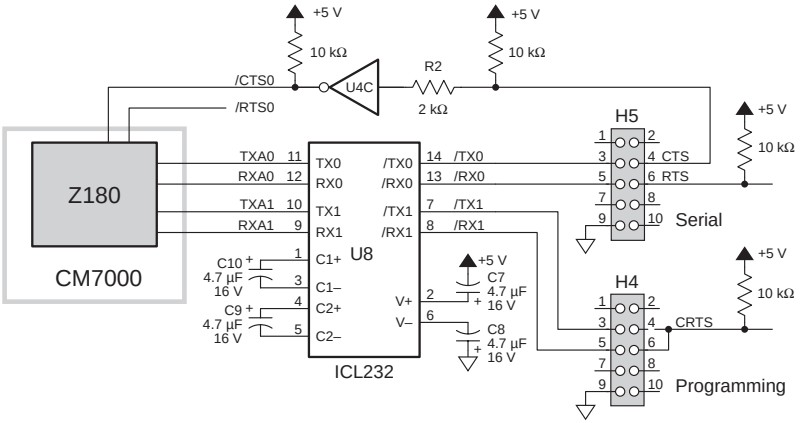

Figure F-3. Prototyping Board Serial Ports

Power

Power (9 V DC from the wall transformer) comes in through the DC input jack (J1) and goes to the LM340 regulator (U3), which supplies +5 V to the CM7000 and other circuits on the Prototyping Board. **DCIN** also feeds a resistor divider, R1 and R8, which develops the power-failure interrupt signal **PFI**. Figure F-4 shows a schematic of the power supply.

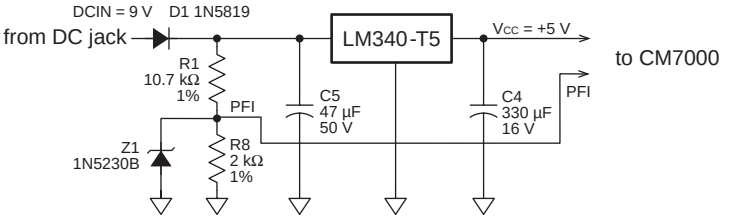

Figure F-4. Prototyping Board Power Supply

When **DCIN** goes below ~8 V, PFI goes below ~1.3 V, the threshold at which the CM7000's ADM691 supervisor generates a nonmaskable interrupt (**/NMI**). An application can take advantage of the **PFI** "early warning" to perform cleanup and shutdown before the supervisor causes a reset because of low power.

The Prototyping Board typically draws ~110 mA with the CM7000 attached. The maximum allowed current draw for the entire board is ~400 mA.

Prototyping Area

The 2.2"×3.3" prototyping area consists of plated through-holes spaced on 0.1" centers. The area has four power rails. Holes near the power rails are connected, facilitating the soldering of 300-mil and 600-mil DIPs. Figure F-5 shows the prototyping area.

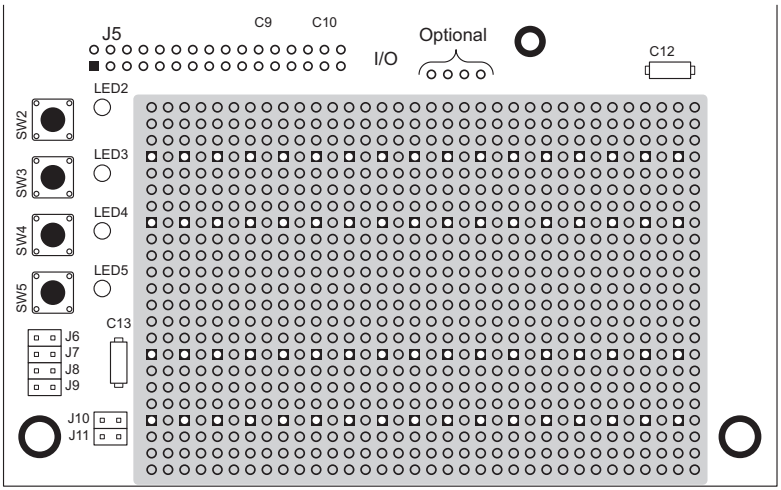

Figure F-5. Prototyping Area

Each power rail consists of alternating power and ground pads. The ground pads are square (see Figure F-6).

Figure F-7 shows how to solder in various DIPs near the power and ground pads.

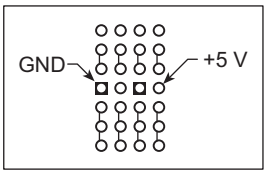

Figure F-6. Prototyping Board Power and Ground Bads

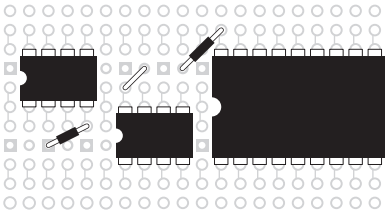

Figure F-7. Soldering DIPs to Power and Ground Pads

Reset

The Prototyping Board has a reset button, SW1, that is used to restart the entire system on the Protoyping Board. The CM7000's ADM691 supervisor will also generate a reset when the regulated +5 V goes below V_{MIN} (4.5 V to 4.75 V).

Figure F-8 illustrates the reset schematically.

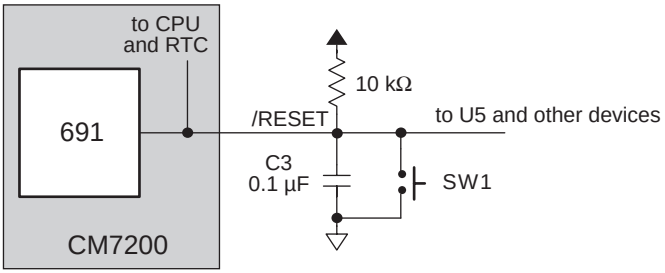

Figure F-8. Reset Operation

Dimensions

Figure F-9 shows the Prototyping Board's dimensions.

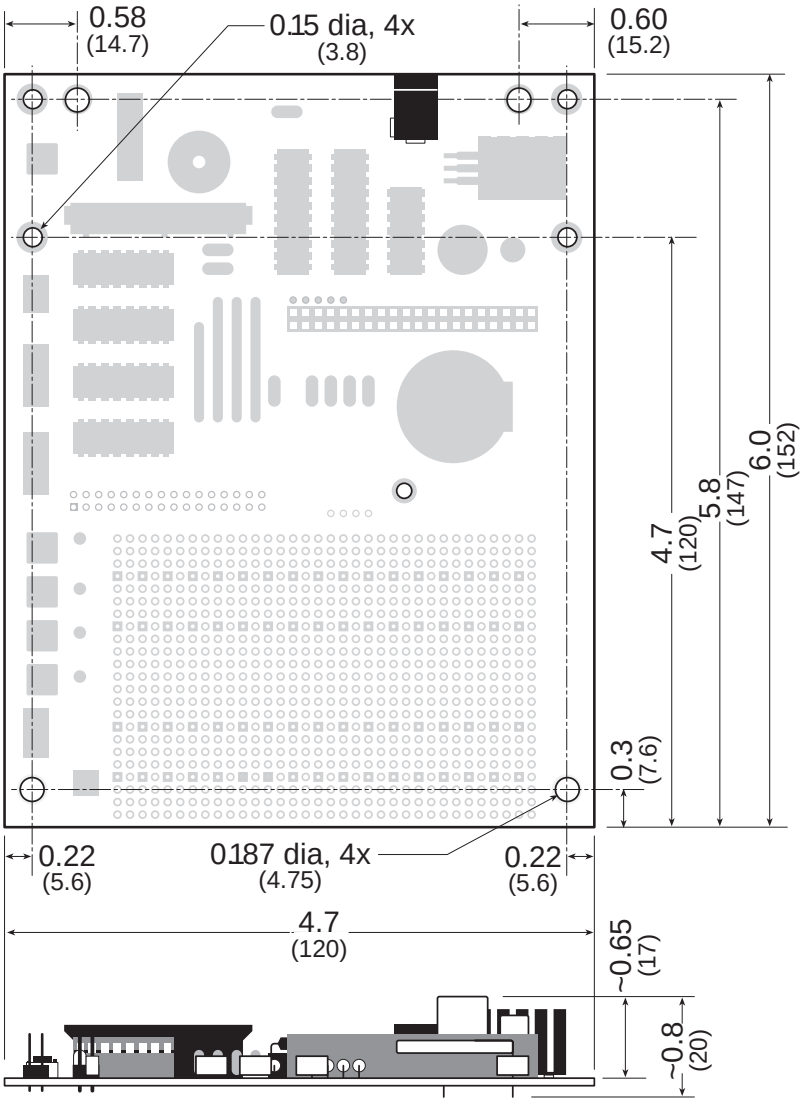

Figure F-9. Prototyping Board Dimensions

Jumpers and Headers

Figure F-10 shows the location of headers on the Prototyping Board.

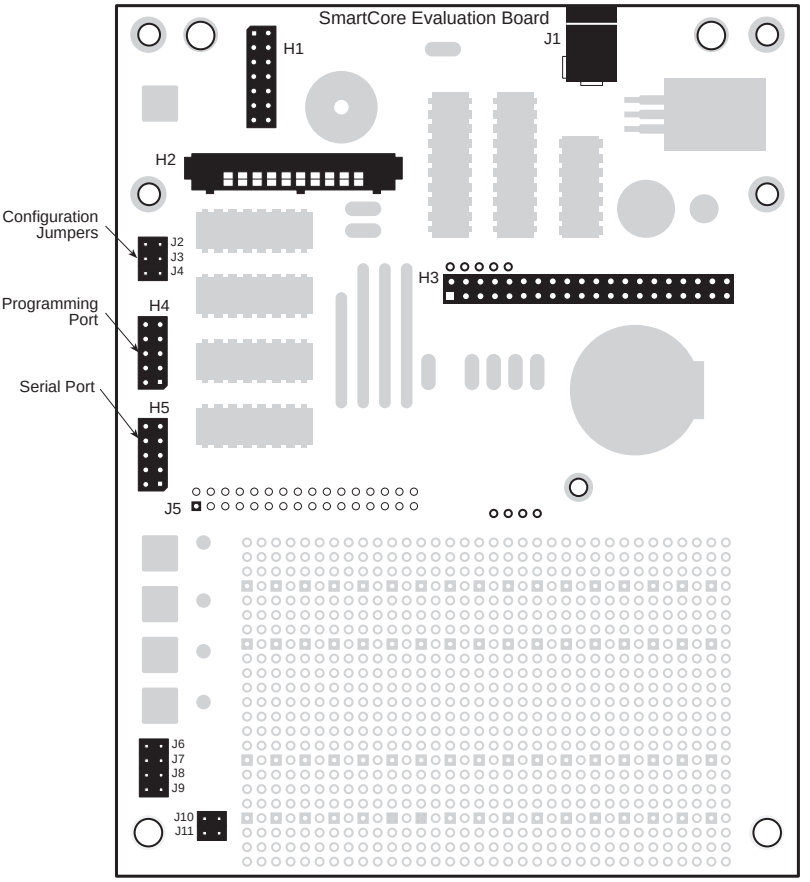

Figure F-10. Prototyping Board Headers

Table F-1 describes the headers.

Table F-1. Prototyping Board Headers

Header	Description
H1	LCD display on LCD/Keypad module
H2	Keypad on LCD/Keypad module
H3	Connection for header H2 on CM7000
H4	RS-232 programming port
H5	RS-232 serial port
J1	Power supply input jack

Headers J2–J4 are used to configure the Prototyping Board when developing an application for the CM7100. Table F-2 provides the jumper configurations.

Table F-2. Prototyping Board Configuration Jumper Settings for CM7100

Header	Description
J2	Connected (factory default): enables output to the LEDs and buzzer, two keypad drive lines are also enabled. Uses **/CS1**.
J3	Connected (factory default): enables input from the four pushbutton switches (SW2–SW5), the six keypad sense lines, and jumpers J6-J11. **U**ses **/CS2**.
J4	Connected (factory default): enables the LCD. Uses **/CS3**.

To use the associated chip selects **/CS1**, **/CS2**, or **/CS3** for other purposes, disconnect the corresponding jumpers across header J2, J3, or J4, according to Table F-2. Remember to disable the associated components on the Prototyping Board.

When headers J10 and J11 are configured for the "run program" mode, jumpers across headers J6–J9 are used to select a sample program in the special EPROM supplied in the Evaluation Kit for the CM7100. The CM7100 checks headers J6–J9 at startup. The CM7100 will execute the program, if any, stored in RAM when J6–J9 are all unjumpered.

Table F-3 identifies which headers to connect to run a program in RAM or to run one of the sample programs in the special EPROM.

Table F-3. Prototyping Board Jumper Settings for Sample Programs in Special EPROM

Operation	Header Configuration
Run sample program 1.	Jumper header J6.
Run sample program 2.	Jumper header J7.
Run sample program 3.	Jumper headers J6 and J7.
Run sample program 4.	Jumper header J8.
Run sample program 5.	Jumper headers J6 and J8.
Run sample program 6.	Jumper headers J7 and J8.
Run sample program 7.	Jumper headers J6, J7, and J8.
Run sample program 8.	Jumper header J9.
Run program in RAM.	No headers jumpered.

Header J3 must be jumpered to run the sample programs in the special EPROM or in RAM.

Headers J10 and J11 are used to set the operating mode or the programming baud rate for the CM7000 connected to the Prototyping Board. Table F-4 lists the jumper configurations.

Table F-4. Prototyping Board Configuration Jumper Settings for CM7100

Headers	Connections	Description
J10 J11	No connections.	Program at 19,200 bps.
	J10 connected, J11 not connected.	Program at 9600 bps.
	J10 not connected, J11 connected.	Program at 57,600 bps.
	J10 connected, J11 connected.	Run program in RAM or in EPROM.

Header J3 must be jumpered to be able to set the programming rate or run mode with headers J10 and J11.

Sample Circuits

The Prototyping Board contains a few sample circuits. The settings of headers J2–J4 affect these circuits, as described earlier in this appendix.

Digital Input

Four pushbutton switches (SW2–SW5) on the Prototyping Board simulate asynchronous inputs. Four readable headers, J6–J9, simulate fixed conditions. The Prototyping Board multiplexes these signals with the keypad-sense lines and the baud-rate headers as shown in Figure F-11.

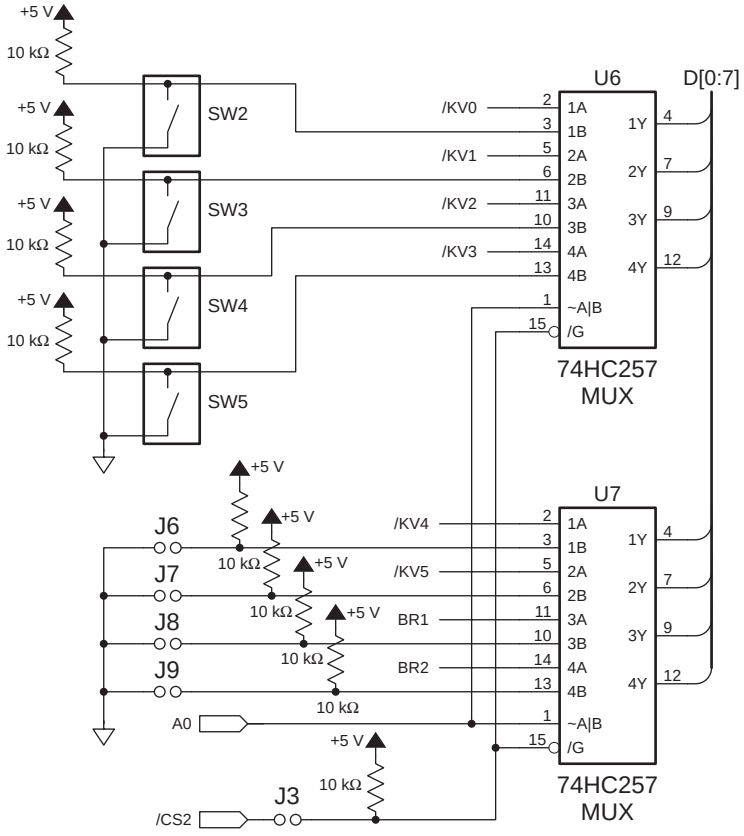

Figure F-11. Sample Digital Input Circuit on Prototyping Board

The multiplexers are enabled when J3 is connected (this is the factory default setting). When enabled, **/CS2** governs the circuit. (**/CS2** represents addresses from 0x4040 to 0x407F.) Address line 0 selects A or B in the multiplexers. Thus, reading address 0x4040 retrieves the state of the

keypad-sense lines and the baud-rate jumper configuration, whereas reading address 0x4041 gets the state of the pushbuttons and the settings of headers J6–J9. The C expression **`CS2+1`** is equivalent to 0x4041.

The pushbutton values return in the low order bits (0–3) of the data byte. The jumper settings return values in bits 4–7.

Digital Output

The Prototyping Board provides four LEDs (D2–D5) and a self-resonating buzzer to simulate outputs. The Prototyping Board also drives the keypad with the selector chip that drivers the LEDs and the buzzer. The sample circuit is shown in Figure F-12.

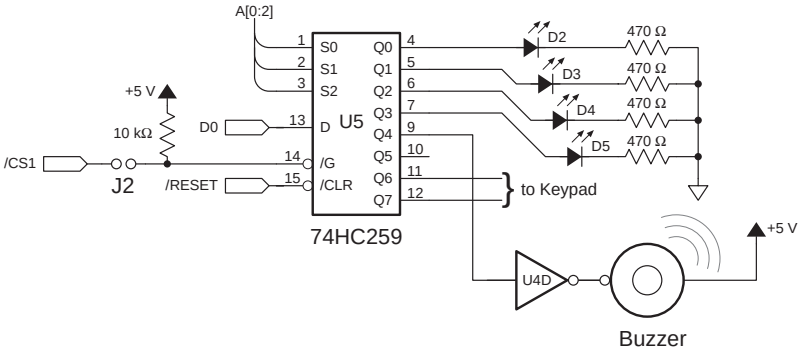

Figure F-12. Sample Digital Output Circuit on Prototyping Board

The selector is enabled when header J2 is connected (this is the factory default setting). When enabled, **/CS1** governs the circuit. (**/CS1** represents addresses from 0x4000 to 0x403F.) Address lines 0–3 select one of the eight outputs. Thus, writing address 0x4000 selects the first LED (D2). Writing address 0x4004 selects the buzzer. The C expression **`CS1+4`** is equivalent to 0x4004.

The only data bit of interest is bit 0. Writing a 1 to bit 0 turns on the selected output; writing a 0 turns it off.

APPENDIX G: DEVELOPMENT BOARD

Appendix G provides technical details for Z-World's Development Board used with the CM7100.

A Development Board is included with the CM7100 Developer's Kit. The Development Board plugs into the EPROM (U3) and H3 sockets of the CM7100 when an application is being developed.

The Evaluation Kit includes the Prototyping Board and a trial version of Dynamic C with a CM7110. The standard or deluxe version of Dynamic C and a Development Board are needed to have a complete development system.

Figure G-1 shows the board layout for the Development Board.

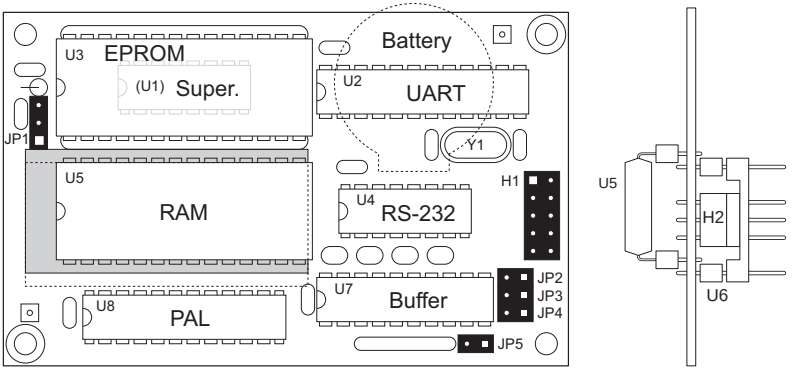

Figure G-1. Development Board Layout

Table G-1 lists the functions of the Development Board's headers and their jumper settings.

Table G-1. Development Board Headers and Jumpers

Header	Pins	Description
H1	—	RS-232 programming port.
H2	—	Connects to H3 on the CM7100. This header has no I/O.
JP1	1–2	Connect for 512K SRAM.
	2–3	Connect for 32K or 128K (factory default) SRAM.
JP2	—	Not used.
JP3 JP4	No connections	Program at 19,200 bps (factory default).
	JP3 connected, JP4 not connected	Program at 9600 bps.
	JP3 not connected, JP4 connected	Program at 57,600 bps.
	JP3 connected, JP4 connected	Run program in Development Board RAM.
JP5	—	Not used.
U6	—	Connects to socket U3 on the CM7100.

Figure G-2 shows the dimensions of the Development Board.

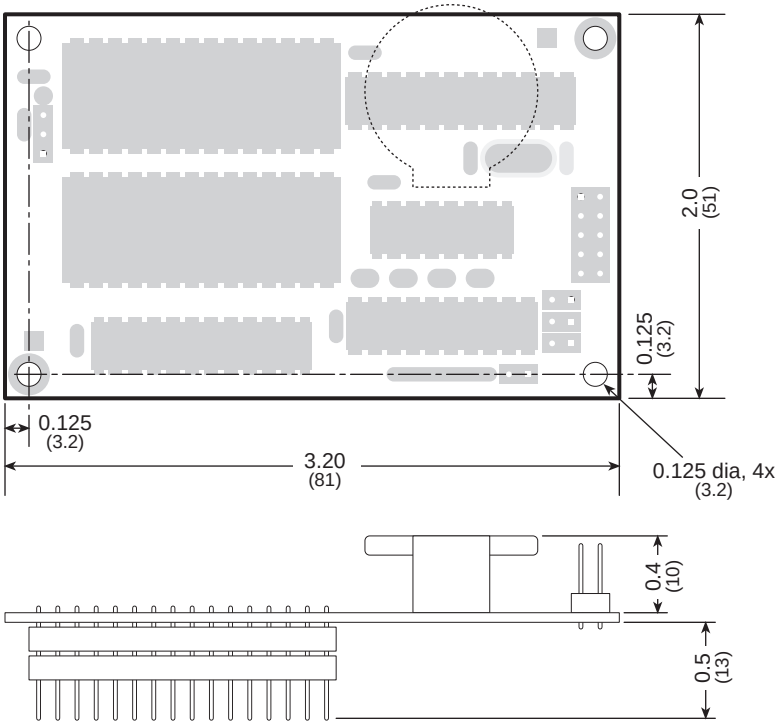

Figure G-2. Development Board Dimensions

APPENDIX H: LCD / KEYPAD MODULE

Appendix H provides technical details for Z-World's LCD / Keypad Module used with 9 MHz versions of the CM7000.

The optional LCD /keypad module comes with standoffs for mounting on the Prototyping Board. The LCD has two rows of 20 characters. The keypad has two rows of six keys. Figure H-1 shows the LCD/keypad module and provides its dimensions.

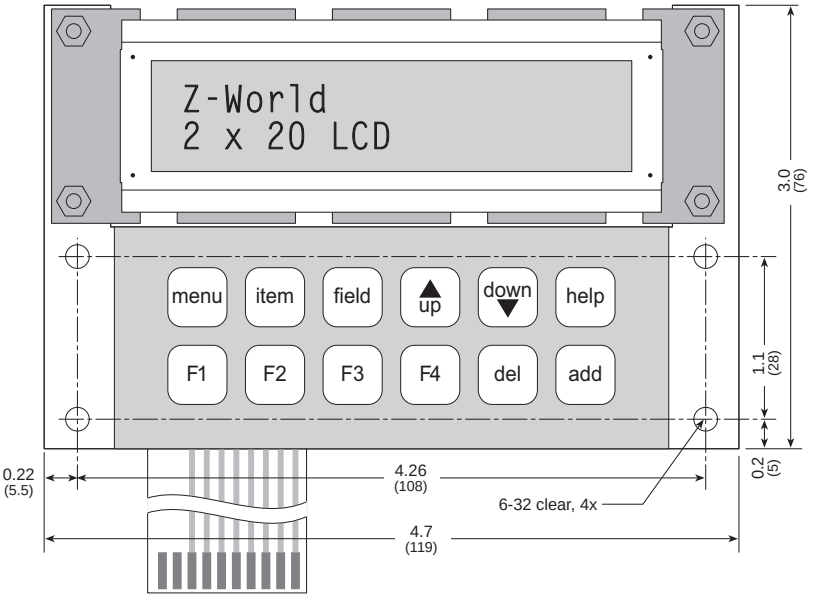

Figure H-1. LCD/Keypad Module

The mounting holes of the module match the indicated mounting holes on the Prototyping Board as shown in Figure H-2.

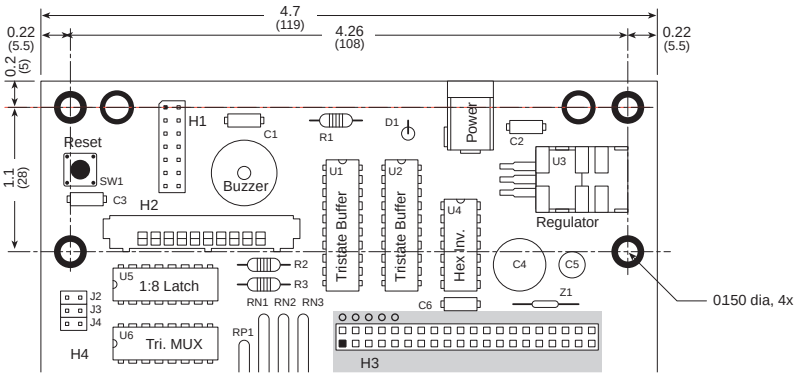

Figure H-2. Mounting LCD/Keypad Module on Prototyping Board

Connect the cables from the LCD/keypad module to the Prototyping Board before mounting the LCD/keypad module on the Prototyping Board. First, put the keypad flat cable in socket H2. Clamp it securely. Then connect the short 14-wire ribbon cable from the header under the LCD (the arrow matches pin 13) to header H1 of the Prototyping Board (the arrow must match pin 1). When installed, the LCD/keypad module will extend out from the Prototyping Board as shown in Figure H-3.

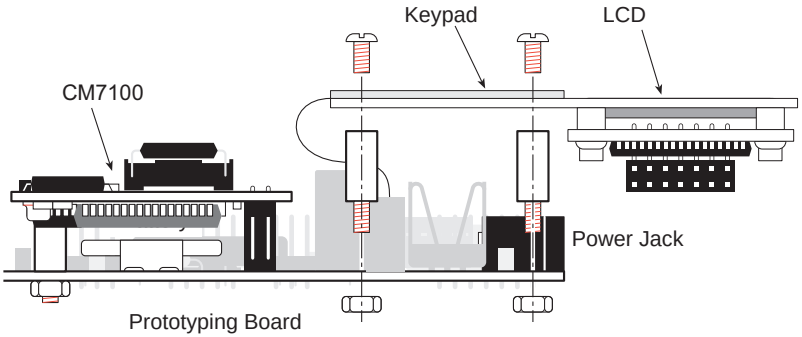

Figure H-3. LCD/Keypad Module Mounted on Prototyping Board

The LCD Driver

Two three-state buffers drive the LCD from header H1 on the Prototyping Board. The buffers are shown in Figure H-4.

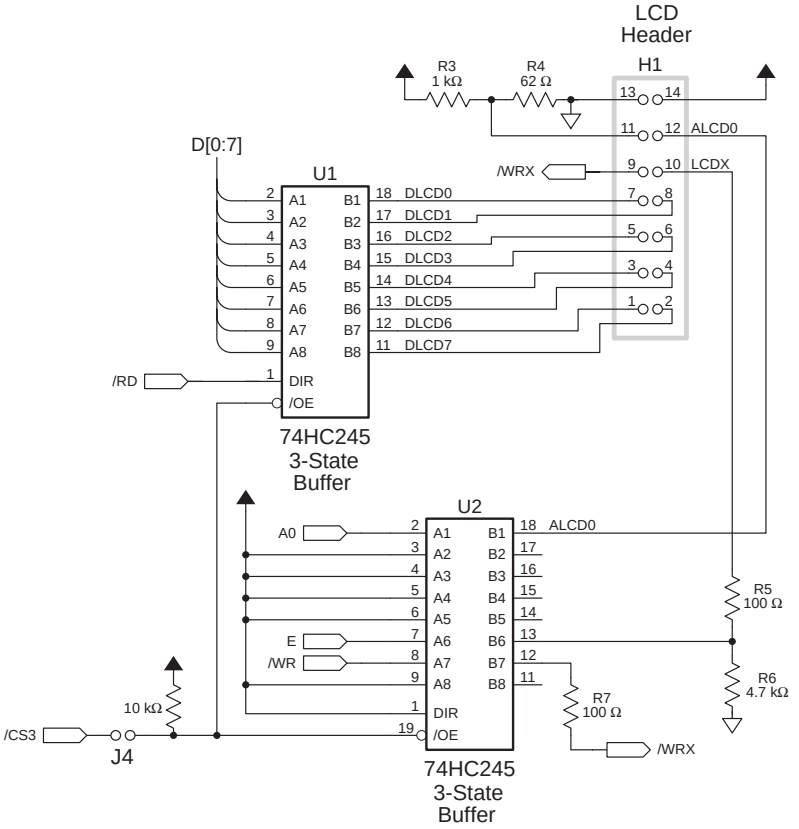

Figure H-4. Prototyping Board LCD Buffers

The buffers are enabled when header J4 on the Prototyping Board is jumpered (this is the factory default setting). When enabled, **/CS3** governs the circuit (**/CS3** represents addresses from 0x4080 to 0x40BF). The C expression **`CS3+1`** is equivalent to 0x4081.

See Appendix F, "Prototyping Board," for more information on header configurations.

The Dynamic C library **`CM71_72.LIB`** provides routines to operate the LCD and keypad. These functions are described in the ***Dynamic C Function Reference*** manual.

The Keypad Driver

To operate the keypad, low-level software first negates a keypad row line (**/KH0** or **/KH1**), then reads the keypad sense lines. If a key is pressed in that row, the sense line will be a 0. Doing this operation for each row identifies which key had been pressed.

The keypad sense lines are multiplexed with the pushbutton switches and headers. **/CS2** controls the multiplexers, and a jumper connection across header J3 enables them. Reading address **CS2+0** returns the keypad-sense lines for the recently selected row in bits 0–5 (low order).

/CS1 and address lines A0–A2 select the keyboard-row lines. Address **CS1+6** (0x4006) is row 1 and address **CS1+7** (0x4007) is row 0. Writing a 1 to data bit 0 activates the row line.

See Appendix F, "Prototyping Board," for more information on header configurations.

Figure H-5 on page H-6 shows the configuration of the keypad multiplexers on the Protoyping Board. Note the words "menu," "item," "field," "up," "down," and "help." These correspond to the key identities in Z-World's five-key system (see Dynamic Application Frameworks manual).

The five-key system is described in detail in the ***Dynamic C Application Frameworks*** manual.

The Dynamic C library **CM71_72.LIB** provides routines to operate the LCD and keypad. These functions are described in the ***Dynamic C Function Reference*** manual.

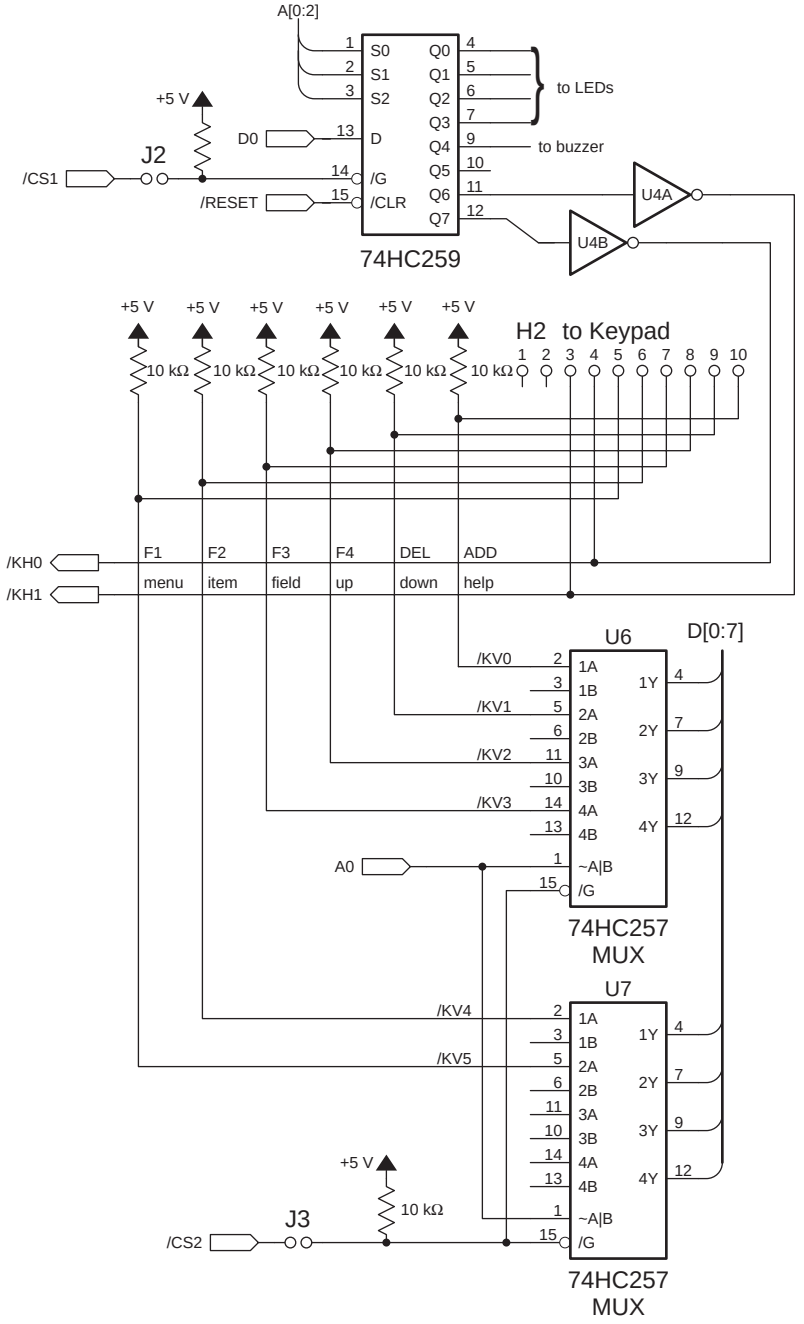

Figure H-5. Multiplexing and Reading Keypad Lines

APPENDIX I: FLASH PROGRAMMER

Appendix I provides technical details for Z-World's Flash Programmer used to program flash EPROMs for the CM7200.

Introduction

The Flash Programmer, shown in Figure I-1, is used to program the flash EPROM of CM7200s in medium to large quantities. The Flash Programmer transfers a compiled application from a "master" EPROM to a target CM7200's flash EPROM.

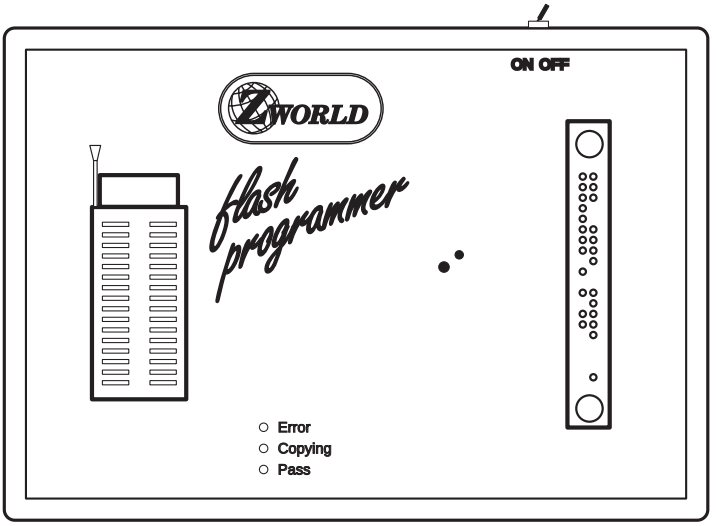

Figure I-1. Flash Programmer

The Flash Programmer socket cannot handle CM7200s that have a header installed at H1.

During normal development, Dynamic C loads applications into a CM7200's flash EPROM. But once an application has been developed successfully, the Flash Programmer facilitates loading the application to CM7200s in production quantities. Dynamic C requires a host PC and takes about 1.5 minutes (at 19,200 bps) to load a 128K application. The Flash Programmer operates standalone and takes about 10 seconds to load the same 128K application.

Nonremovable Flash EPROM

The flash EPROM is surface-mounted on the CM7200 circuit board. This gives the CM7200 a low profile and enhanced reliability. However, this makes it much harder to remove the flash EPROM to reprogram it. The Flash Programmer reprograms the CM7200's flash EPROM with the flash EPROM remaining soldered to the board.

The Dynamic C development EPROM can also be used as a "master" with the Flash Programmer to update the CM7200's onboard BIOS. This feature will work even if the CM7200's onboard BIOS has been damaged or corrupted.

Requirements

To load a program into a CM7200's flash EPROM with the Flash Programmer, all you need is an original EPROM, of the appropriate size, containing the compiled application.

Selecting a Master EPROM

When selecting an EPROM from which to transfer an application to a CM7200's flash EPROM, keep these important points in mind.

1. The EPROM size must be larger than the size of the application size.
2. The DIP-switch configuration must match the size of the EPROM, not the size of the flash EPROM on the CM7200.
3. Even if the application will fit in the CM7200's flash EPROM, the EPROM's size must be equal to or smaller than the size of the flash EPROM. For example, if you attempt to transfer a 32K application contained in a 256K EPROM to a 128K CM7200 flash EPROM, the Flash Programmer will signal an error because the 256K EPROM is larger than the 128K flash EPROM.

In general, the safest course is to use an EPROM that is the same size as the CM7200's flash EPROM.

EPROM Sizes

The Flash Programmer supports EPROM with standard pinouts: 32K and 64K (28 pins), and 128K and 256K (32 pins). If your proposed master EPROM pinouts match the pinouts shown in Figure I-2, the EPROM will work in the Flash Programmer.

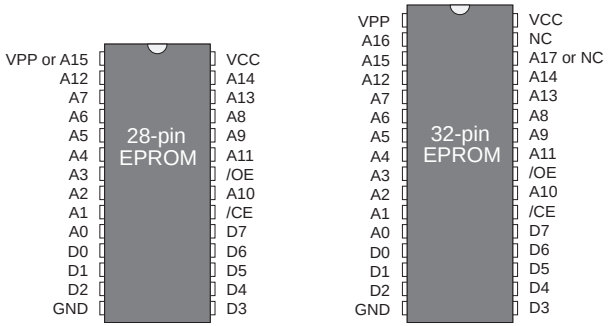

Figure I-2. EPROM Pinouts Recognized by Flash Programmer

The CM7200 currently supports 128K and 256K flash EPROM. Before copying begins, the Flash Programmer compares the size of the EPROM (as indicated on the DIP switches) with the size of the flash EPROM. If the EPROM is larger than the available target memory, no copying will occur, and the red (**Error**) LED will blink, indicating an error.

Back-Panel DIP switches

Four DIP switches (SW1–SW4) on the Flash Programmer's back-panel (see Figure I-3) set the size of the master EPROM. SW5 indicates whether the Flash Programmer will copy an application to flash EPROM or whether the Flash Programmer will copy the BIOS.

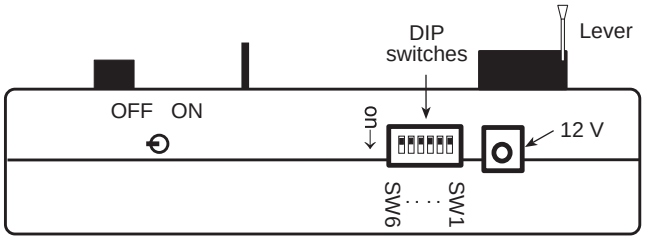

Figure I-3. Flash Programmer Side View Showing DIP Switches and Power Supply Input

Table I-1 provides the DIP switch settings.

Table I-1. Flash Programmer DIP Switch Settings for Master EPROM Size

EPROM Size	SW1	SW2	SW3	SW4	SW5	SW6
32K	on	on	off	off	copy application—off	off
64K	on	off	off	off		off
128K	off	off	off	off	copy BIOS—on	off
256K	off	off	on	off		off

Always turn off Flash Programmer's power when changing the DIP-switch settings.

Operating Procedure to Copy Application

1. Place the Flash Programmer's power switch in the off position and connect the 12 V power supply to the power jack on the Flash Programmer's rear panel as shown in Figure I-3.
2. Raise the Flash Programmer's ZIF socket's lever (see Figure I-3) to the vertical position. Place the master EPROM in the 32-pin ZIF socket of the Flash Programmer. Pin 1 of the EPROM should be in the upper part of the socket. If you are using a 28-pin EPROM, position the IC at the bottom of the socket as shown in Figure I-4 so that the top four socket pins are empty.
3. Lower the lever to the horizontal position.

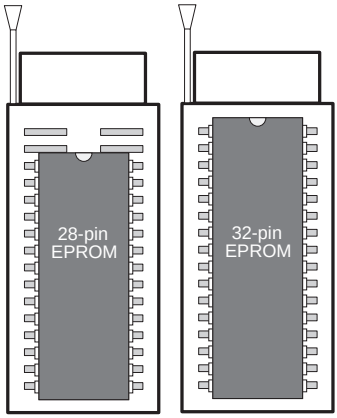

Figure I-4. Positioning 28-pin and 32-pin EPROMs in Flash Programmer ZIF Socket

4. Set the Flash Programmer's back-panel DIP switches to indicate the size of the master EPROM (see Table I-1). Switches SW4, SW5 and SW6 should be off.
5. Insert the target CM7200 in the 40-pin socket on the Flash Programmer as shown in Figure I-5.

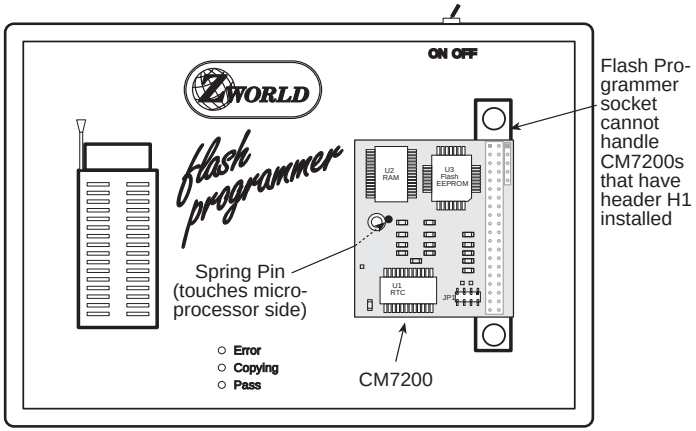

Figure I-5 Placement of CM7200 in Flash Programmer Socket

6. Make sure the Flash Programmer's spring pin shown in Figure I-5 makes contact with the CM7200 circuit board. If the spring pin does not make proper contact, the Flash Programmer will not work. Therefore, take care never to bend or otherwise damage the spring pin.
7. Turn on the power.
8. All three LEDs will light momentarily to indicate that the Flash Programmer is resetting. The yellow (middle) LED will blink to indicate data are being written to the CM7200's flash EPROM. The green (bottom) LED will blink to indicate that the written data are being verified. The green (bottom) LED will shine steadily once the copying is completed successfully. You can turn off the power and remove the programmed CM7200.
8. If the red (top) LED lights, an error has occurred. Refer to the Troubleshooting section on the next page.

BIOS Update/Recovery Mode

The Flash Programmer can be used to update the CM7200's BIOS. In the unlikely event that an accidental write to the flash memory has corrupted the BIOS, the Flash Programmer can also be used to restore this vital section of code.

To copy a new BIOS into the CM7200, first burn an EPROM with the Dynamic C file **`29xx.BIN`** (where xx is greater than or equal to 01) found in the Dynamic C **`BIOS`** subdirectory. Follow the instructions for copying a master EPROM to the CM7200 flash EPROM, but set DIP switch SW5 to the on position.

A BIOS copy takes less than two seconds because only 13K gets copied from the EPROM.

Troubleshooting

If the red (top) LED remains illuminated, an error has occurred and the copying was not successful. Table I-2 lists possible solutions to correct the problem.

Table I-2. Flash Programmer LED Error Indicators

LED	Indicates	Remedy
Blinking Red	DIP switches indicate master EPROM size is larger than flash EPROM size.	• Make sure that DIP-switch setting agrees with the size of the master EPROM. • Use an EPROM that is the same size or smaller than the CM7200's flash EPROM.
Steady Red	Verification failed.	Indicates defective CM7200. If repeated attempt to program produces steady red LED, contact Z-World for assistance.
Red, Yellow, and Green blinking once every second	Watchdog timed out.	• Make sure CM7200 is properly seated in socket. • Make sure spring pin makes contact with the CM7200. • Make sure DIP switches are set correctly. • Make sure master EPROM is properly seated in ZIP socket with lever in horizontal position.

CM7100 Compatibility

The Flash Programmer is not compatible with the CM7100. When compiling source code intended for a CM7200, be sure to use a CM7200 as the target, not a CM7100.

Never plug a CM7100 into the Flash Programmer.

Blank

APPENDIX J: SAMPLE APPLICATIONS

Appendix J presents several circuits and describes them briefly. These sample circuits demonstrate some of the ways the CM7000 can be used.

12-Bit Analog-to-Digital Converter

The circuit shown in Figure J-1 serves as an A/D converter for the CM7000.

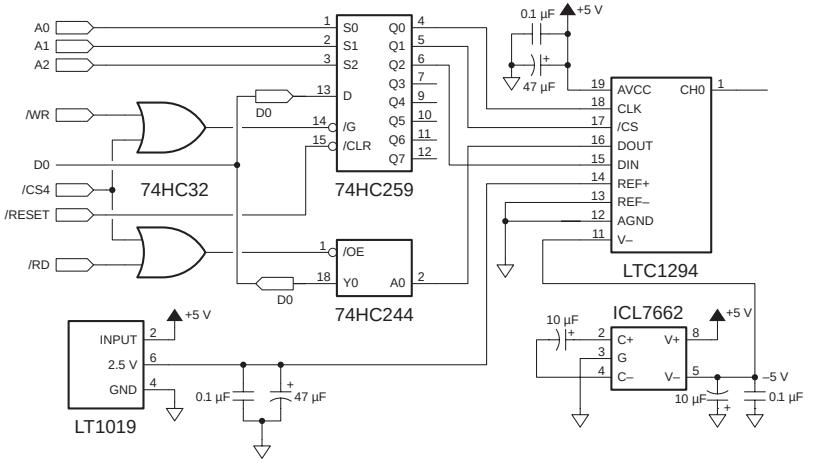

Figure J-1. Analog-to-Digital Converter Circuit

The 12-bit A/D converter chip is a Linear Technology LTC1294. It can be programmed to convert a signal at one of its inputs in either 12-bit unipolar or "11-bit + sign" bipolar mode. Its 8 channels can be configured as either eight single-ended inputs or four differential inputs.

The LTC1294's reference voltage comes from the precision 2.5 V voltage reference (LT1019). The input reference and supply voltages to the LTC1294 must be free of noise and ripple.

Two input amplifier circuits perform signal conditioning. The first circuit, shown in Figure J-2, uses a high-precision instrumentation amplifier (LT1101) with selectable gain (10 or 100).

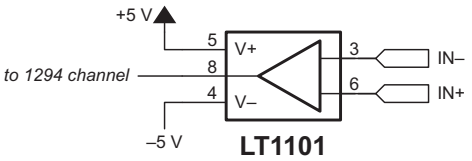

Figure J-2. High-Precision Amplifier for A/D Converter

The other amplifier circuit, shown in Figure J-3, is a difference amplifier with a predetermined offset of 2.5 V.

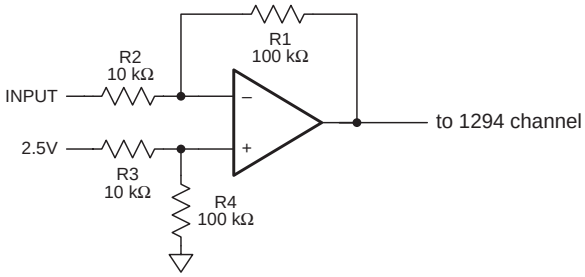

Figure J-3. Difference Amplifier for A/D Converter

The gain equation is

$$V_{OUT} = \frac{R1}{R2} \times (\text{INPUT} - 2.5\,\text{V}) \quad , \tag{J-1}$$

assuming R2 = R3 and R1 = R4. The analog input voltage range is 0 V to 2.5 V unipolar, and –2.5 V to +2.5 V bipolar.

Software controls the LTC1294 by writing to one of three **/CS4** addresses. The addressable latch (74HC259) controls the flow of information into the LTC1294 as follows.

- To control the LTC1294 clock, write to address 0x40C0.
- To control the LTC1294 chip-select, write to address 0x40C1.
- To send the input word, write to address 0x40C2.

The following sample program shows how to read the A/D converter in bipolar mode.

```
/*******************************************************
    12-bit ADC sample circuit for the CM7000
    Channel 0 single-ended bipolar
*******************************************************/
 #define CS4 0x40C0
 void set_clock(int state){   // sets the clock as 0 or 1
   if( state )
     outport(CS4,1);
   else
     outport(CS4,0);
   }
 float read_1294(){
   int j,k,control,value;
   float fvalue;              // ST  SGL0  UNI always
   control=0xC3;              // 1   1000  0   11
   value=0;
   outport(CS4+1,0);          // assert CS on the 1294
   outport(CS4+2,0);          // set the DIN bit to 0
   set_clock(0); set_clock(1);
   set_clock(0); set_clock(1);
   for(j=7;j>=0;j—){          // send control word
     set_clock(0);            // MSB first
     outport(CS4+2,control>>j);
     set_clock(1);
   }
   outport(CS4+2,0);          // set DIN to 0
   for(k=0;k<12;k++) {        // read 12 bits of the
     set_clock(0);            // 1294 MSB first
     set_clock(1);
     value=(value<<1)+(inport(CS4)&1);        // bit 0
   }
   outport(CS4+1,1);          // clear 1294 CS
   fvalue = (value*2.5) / 1024;     // convert value
   if (fvalue > 2.5 ) fvalue -= 5;
   return fvalue;
 }
 main(){
   int i;
   float ch0;
   for(;;){
     ch0=read_1294(1); printf("Ch.0 bi  = %f\n",ch0);
     ch0=read_1294(0); printf("Ch.0 uni = %f\n",ch0);
     printf("\n");
     for(i=0;i<20000;i++){};     // a delay
   }
 }
```

Optically Isolated Switch Reader

This circuit in Figure J-4 demonstrates how to read a discrete field input inexpensively by using an optical isolator. The input is a current loop powered by an external power supply that is not ground-referenced to the CM7000. When the external switch closes, current flows through the isolator's internal diode and activates the output phototransistor, pulling the input of the 74HC244 to ground. The switch activation can also generate an interrupt by connecting the output of the optical isolator to one of the interrupt lines, **/INT0** or **/INT1**.

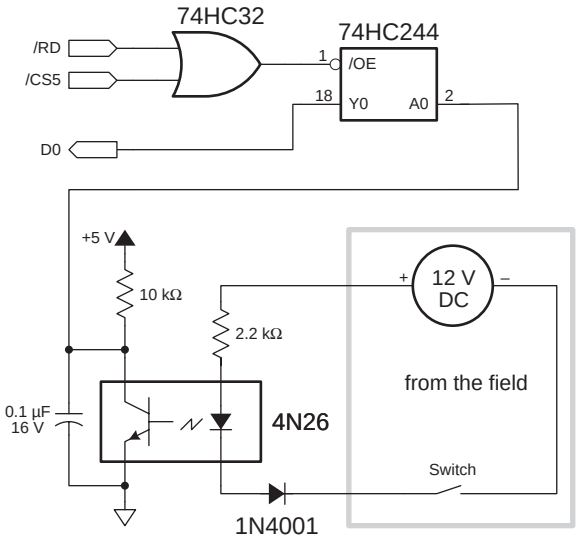

Figure J-4. Optically Isolated Switch Reader

The software to read the switch is very simple.

```
// get switch status, 0=closed  1=open
  byte sw1;
  sw1 = inport(0x4100) & 0x01;
```

Relay Circuit

The circuit shown in Figure J-5 demonstrates a simple 8-relay interface. The interface requires only three readily available ICs.

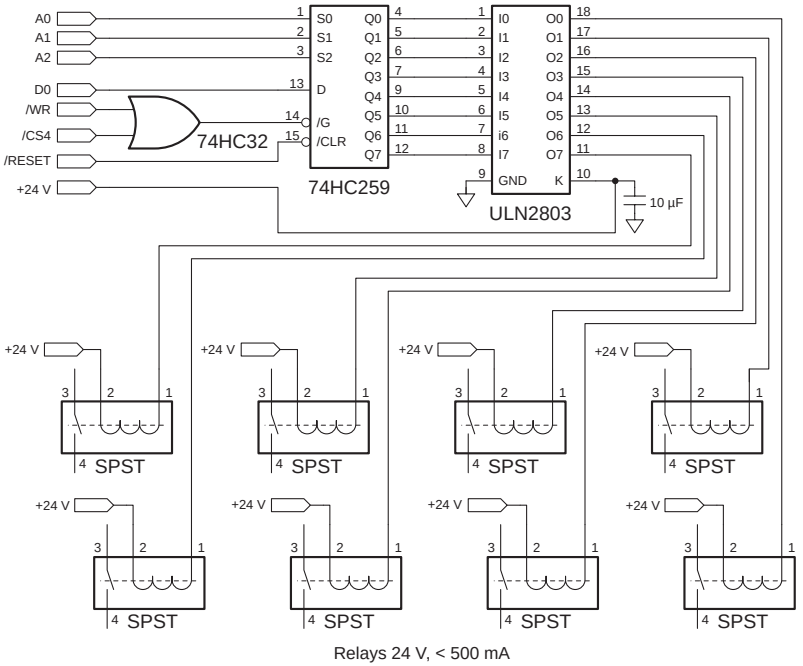

Figure J-5. Eight-Relay Interface Circuit

Each relay occupies a unique I/O address, and is activated or deactivated by writing a 1 or 0, respectively, to that address. Because **/CS4** is used, relay 1 is at address 0x40C0, relay 2 is at 0x40C1, and so on.

The software to operate the relays is very simple.

```
outport(0x40C0,1);     // Energize relay 1
outport(0x40C4,0);     // Deenergize relay 5
```

Although the ULN2803 sinking driver has a maximum current drive capability of 500 mA per channel, its thermal resistance from junction to case is 55°C/W. Table J-1 describes the heating characteristics of the ULN2803 at various currents The part is rated for a maximum junction temperature of 125°C. It is a good idea to limit the coil current to less then 150 mA per relay when operating all eight relays simultaneously (which will produce a 66°C junction temperature rise).

Table J-1. ULN2803 Charactreristics at Selected Currents

Channel Current (mA)	V_{CE} (V)	Power (W/Channel)	Junction Temperature Rise (°C/channel)
100	0.9	0.09	4.95
200	1.1	0.22	12.1
300	1.25	0.375	20.6
400	1.35	0.54	29.7
500	1.45	0.725	39.9

24-Bit Parallel I/O

The 24-bit parallel I/O circuit shown in Figure J-6 demonstrates how to get a large number of parallel I/O with the CM7000. The 82C55 provides 24 bits of TTL-compatible I/O.

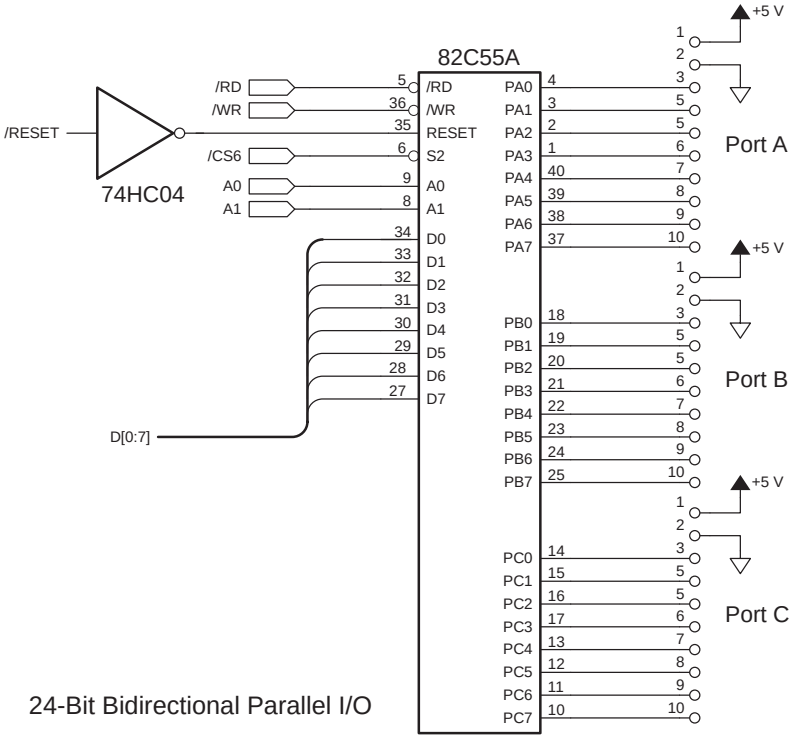

Figure J-6. 24-bit Parallel I/O Circuit

The 82C55 has four registers located at I/O addresses 0x4140 through 0x4143 in this example.

The sample program below shows how to operate the ports.

```
// Setup ports: A=out. B=in. C[0-3]=in. C[4-7]=out.
  outport(0x4143,0x83);
  outport(0x4140,0x55);    // Write to port A
  pb = inport(0x4141);     // Read from port B
  pc = inport(0x4142);     // Read port C, bits 0-3
```

Even though the 82C55 is a CMOS part internally, the output drivers adhere only to TTL levels. Therefore, pull these outputs up when interfacing to CMOS inputs.

8-Bit Digital-to-Analog Converter

The 8-bit digital-to-analog converter (DAC) circuit shown in Figure J-7 demonstrates a way to add an 8-bit DAC to a CM7000-based system. An 8-bit latch at address 0x4100 drives the DAC. The output is a unipolar analog signal from 0 V to 5 V whose value is

$$V_{OUT} = \frac{\text{digital value}}{256} \times 5.0\ \text{V}\ . \qquad \text{(J-2)}$$

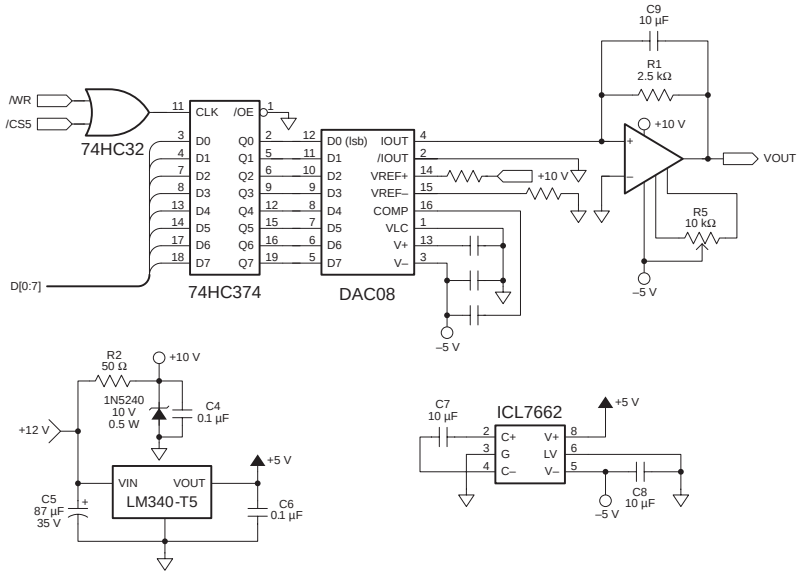

Figure J-7. 8-bit Digital-to-Analog Converter Circuit

In this case the DAC08 will draw current at a rate of (10 V/5 kΩ) × (digital value/256) into the I_{OUT} pin. This current flows through R1 and provides the output voltage range at the amplifier output. The LM741 has an offset up to 15 mV (¾ bit). R5 can null this offset or be left out.

Different amplifier configurations can create different output ranges, including bipolar operation.

This circuit illustrates a way to get inexpensive voltage regulation using a Zener diode. The +10 V can supply 40 mA before the voltage drop across R2 is greater then 2 V. The LM741 can source up to 25 mA, so this current this suffices (the DAC08 uses an additional 2 mA). R2 is required to keep the power dissipated in the zener diode from exceeding 500 mW (10 V × 40 mA = 400 mW).

The following sample program shows how to use the digital-to-analog converter circuit with a CM7000.

```
// Sawtooth Wave Example
  int i,k;
  for(k=0;k<1000;k++){  // do 1000 sawtooth cycles
    for(i=0;i<255;i++){
      outport(0x4100,i); // ramp up
      delay(...);       // delay determines slope
    }
    outport(0x4100,0)   // back to 0
  }
```

SRAM Interface

The circuit in Figure J-8 demonstrates a simple way to add more memory to a system. You can obtain 14 address lines using data bits 0–7, address lines 0–5, and two chip selects. First, the 74HC374 latches the data bits written with **/CS4**. Then, the SRAM is written or read using address lines and **/CS5**.

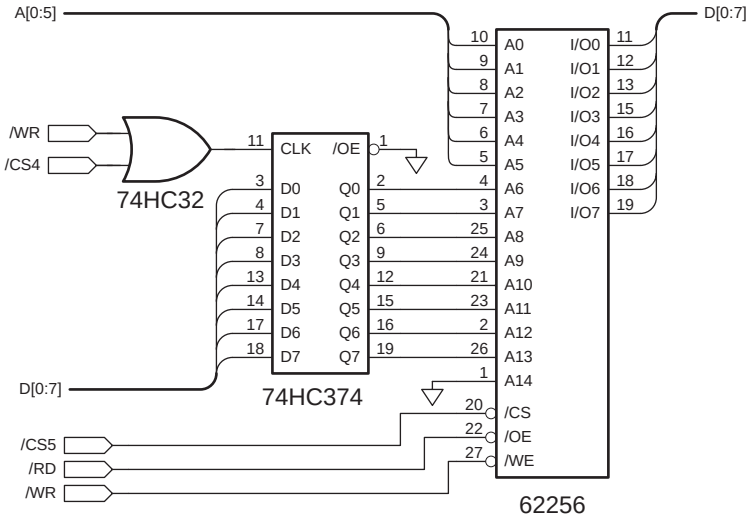

Figure J-8. Adding SRAM to CM7000 System

Protection Circuits

The circuits described here have been proven in the field. Nevertheless, they are not the only way, nor necessarily the best way, to protect a controller from unwanted natural and man-made interference in a particular application.

Z-World does not guarantee that these circuits will protect personnel and equipment. Ensuring such protection is the buyer's responsibility.

Digital-Noise Filter

Analog Devices (Norwood, MA) recommends the simple power-rail filter shown in Figure J-9 to help keep digital noise out of sensitive analog circuitry.

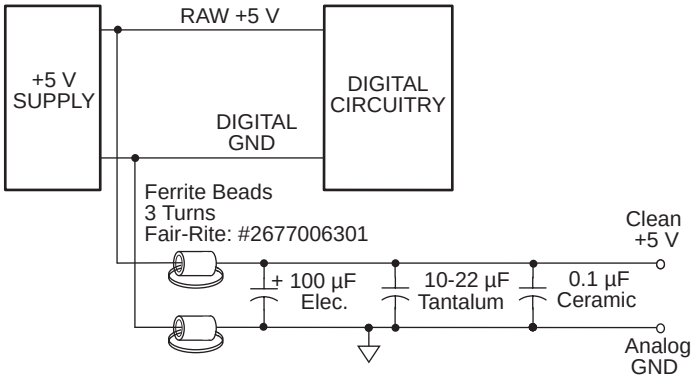

Figure J-9. Digital-Noise Filter

Serial-Port Protection

Maxim (Sunnyvale, CA) notes that a serial port provides an open door for overvoltages and overcurrents from the outside world. The extra components in the circuit in Figure J-10 will protect a serial port against even 117 V AC.

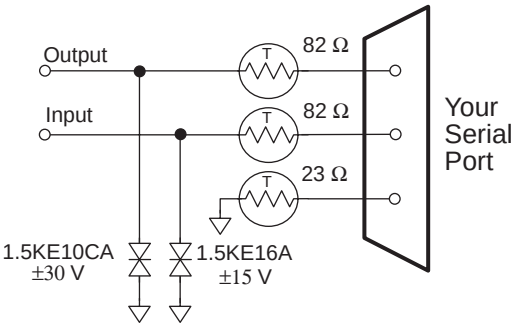

Figure J-10. Serial Port Protection

The solid-state Tranzorbs shunt overload currents to ground initially. Then, after about 0.2 seconds, the positive-temperature-coefficient (PTC) resistors heat up, cutting off current flow. The circuit will reset itself when the overload stops.

General Semiconductor (Tempe, AZ) and General Instruments (Hicksville, NY) sell Tranzorbs. Midwest Components (Muskegon, MI) makes PTC resistors.

Digital I/O Protection

Motorola's Automotive Product Division (Phoenix, AZ) recommends the three circuits in Figure J-11 to protect low-speed digital-I/O lines against transients. All three circuits use a 100 kHz low-pass filter formed by a 0.01 μF capacitor and a 5.1 kΩ resistor along with various clamping components.

The first, and simplest, circuit uses a zener diode to clamp positive-going transients and a Schottky diode to clamp negative-going transients. However, the Schottky diode exhibits 50 mA leakage at 125°C and its forward voltage rises to –0.47 V at temperatures below –40°C, which is too close to the –0.50 V maximum most HCMOS inputs can tolerate.

This second circuit's Schottky diodes clamp both positive- and negative-going voltage transients.

This third circuit uses only silicon diodes, avoiding the problems Schottky diodes contribute at temperature extremes but forgoing their lower forward voltages.

Suppliers of Board-Level Protection Devices

Advanced Thermal Prod
Box 249
St Marys, PA 15857
(814) 834-1541

AVX Corp
Box 867
yrtle Beach, SC 29577
(803) 448-9411

General Semiconductor
2001 W Tenth Pl
Tempe, AZ 85281
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Harris Corp
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Inresco Inc
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Motorola Inc
Power Prod Div
5005 E McDowell Rd
Phoenix, AZ 85008
(602) 244-3035

Philips Components
Box 760
Mineral Wells, TX
76067
(817) 325-7871

Teccor Electronics
1801 Hurd Dr
Irving, TX 75038
(214) 580-1515

World Products
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Sonoma, CA 95476
(707) 996-5201

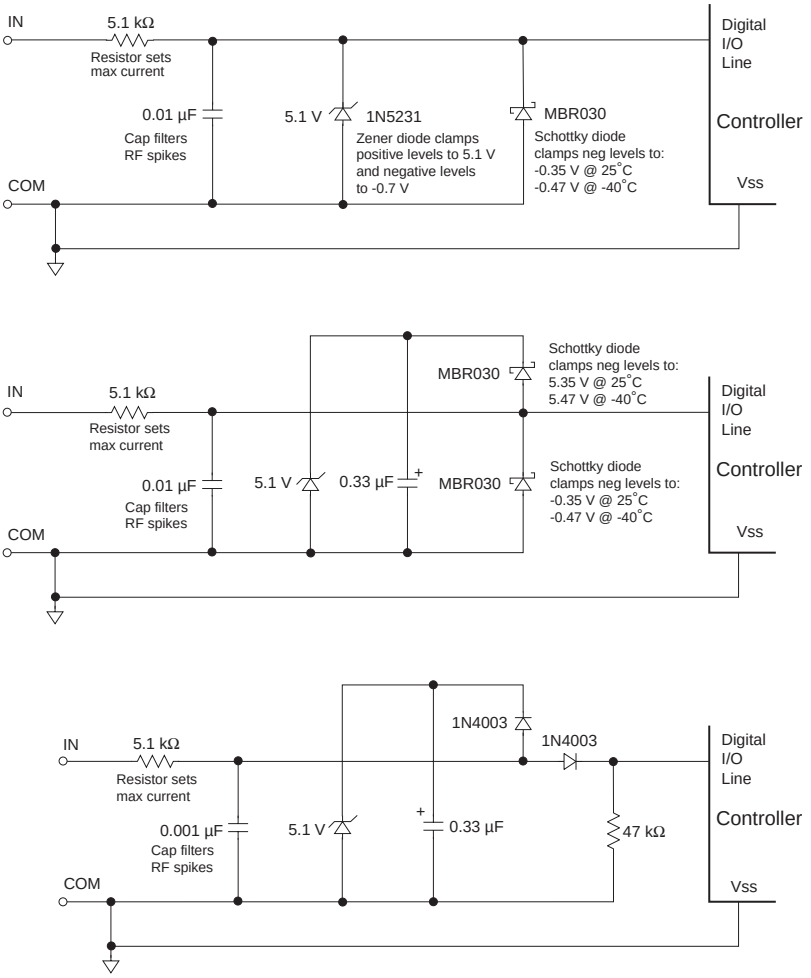

Figure J-11. Digital I/O Protection Circuits

APPENDIX K: SAMPLE PROGRAMS

Appendix K presents sample programs included in the special EPROM with the Evaluation Kit and other sample programs to illustrate the development of applications for the CM7000.

Sample Programs on Special EPROM

The special EPROM that comes with the Evaluation Kit contains eight sample programs. Select a sample program to run by configuring the jumpers on the Prototyping Board according to Table K-1.

See "CM7100 Method 1—Prototyping Board" in "Chapter 2, "Getting Started," for complete details on how to set up the CM7110. Appendix F, "Prototyping Board," provides more information on the Prototyping Board.

Table K-1. Prototyping Board Jumper Settings for Sample Programs in Special EPROM

Operation	Header Configuration
Run sample program 1.	Jumper header J6.
Run sample program 2.	Jumper header J7.
Run sample program 3.	Jumper headers J6 and J7.
Run sample program 4.	Jumper header J8.
Run sample program 5.	Jumper headers J6 and J8.
Run sample program 6.	Jumper headers J7 and J8.
Run sample program 7.	Jumper headers J6, J7, and J8.
Run sample program 8.	Jumper header J9.
Run program in RAM.	No headers jumpered.

Header J3 on the Prototyping Board must be jumpered to run the sample programs in the special EPROM or in RAM.

The source code for the sample programs is included on the diskette containing the trial version of Dynamic C in the **DCB\SAMPLES\CM71_72** directory.

The eight sample programs are described below.

- Sample Program 1—**SC1LAD.C** translates the inverse of the state of the pushbutton switches to the LEDs on the Prototyping Board. An LED is on when the adjacent pushbutton switch is pressed down, and goes off when the pushbutton switch is not pushed down. The software actuates the beeper for 100 ms every time a pushbutton switch is pushed down.

- Sample Program 2—**SC1LED.C** changes the blinking rate of the LEDs on the Prototyping Board. Press the pushbutton switch adjacent to an LED to increase the blinking rate of that LED (the maximum rate is 10 flashes/second). The blinking rate decreases when the adjacent push-button switch is not pressed (the minimum rate is 1 flash/second).
- Sample Program 3—**SC1SEQ.C** selects an LED blink sequence. Press any of the pushbutton switches to select another pattern. The software actuates the beeper for 100 ms when a selection is detected.
- Sample Program 4—**SC1TIM0.C** uses the periodic interrupt by Timer 0 to modulate the on/off time of the LEDs. The LEDs grow brighter, then dimmer, as the program runs.
- Sample Program 5—**SC1PTTRN.C** continuously displays an LED pattern using the four LEDs. The program starts by displaying a default pattern with all the LEDs alternately on, then off. Set a new pattern by pressing any pushbutton. The LEDs will blink four more times and stop. As soon as the beeper sounds, press any sequence with the pushbutton switches. The beeper will sound after a pause, which means the pattern has been accepted. The software will resume blinking the LEDs according to the new pattern.
- Sample Program 6—**SC1Z0232.C** uses Serial Port 0 of the Z180 as a simple diagnostic port connected to a dumb terminal. Set the PC termianl or communication program for 9600 bps, 8 data bits, 1 stop bit, and no parity. Connect a cable from the termianl's COM port to H5 on the Prototyping Board, being careful to match the arrow on the 10-pin connector to pin 1 on header H5.

  The sample program provides the following menu.

  ```
  'a' Toggle LEDs.
  'b' Beep for 1 second.
  'f' Move time adjust field.
  'u' Increment time adjust field.
  'd' Decrement time adjust field.
  Type your choice.
  ```

  Press any of the menu's key choices and observe the response.
- Sample Program 7—**SC1LCD.C** use the LCD/Keypad Module (optional accessory) on the Prototyping Board. The LCD displays the time and date. Use the **FIELD** key to scroll across the date-time display, and use the arrow keys to change the date or time displayed. The function keys **F1**–**F4** toggle the LEDs on or off.

- Sample Program 8—**SC1Z1232.C** demonstrates RS-232 communication between Serial Port 1 of the Z180 and a dumb terminal. Set the PC termianl or communication program for 9600 bps, 8 data bits, 1 stop bit, and no parity. Connect a cable from the termianl's COM port to H5 on the Prototyping Board, being careful to match the arrow on the 10-pin connector to pin 1 on header H5.

  The sample program provides the following message.

  ```
  This program shows the use of Z180 port 1 for
  RS-232 communication.  Type a short string,
  terminated with <CR>, and the same string is
  sent back from the CM7000.
  ```

  The prompt **>** follows the message. Type anything followed by a return.

Other Sample Programs

These sample programs listed in Table K-2 are included on the diskette containing the trial version of Dynamic C in the **DCB\SAMPLES\CM71_72** directory.

Table K-2. Other CM7100 Sample Programs

Name	Description
SC15KEY.C	"Five-key" menuing program for the Prototyping Board with an LCD/Keypad module installed.
SC1DM232.C	Uses DMA0 to receive and transmit data from and to Serial Port 0 of the Z180.
SC1DMAPW.C	Uses DMA0 and DMA1 to generate pulse widths on LED 2 and LED 4.
SC1NMI.C	Demonstrates power failure interrupt and brownout monitoring.
SC1RTC.C	Continuously displays time and date to the Dynamic C **STDIO** window.
SC1RTK.C	Demonstrates the real-time kernel (RTK).
SC1WDOG.C	Demonstrates how to monitor watchdog timeouts at startup.

All the sample programs referred to in this appendix are also available in the regular Dynamic C **SAMPLES\CM71_72** directory.

Symbols

A

B

C

D

E

F

H

I

J

P

R

S

T

U

V

W

X

Z

Z-World
2900 Spafford Street
Davis, California 95616-6800 USA

Telephone: (530) 757-3737
Facsimile: (530) 753-5141
Web Site: http://www.zworld.com
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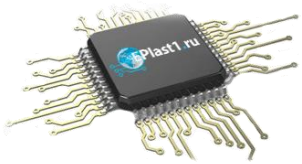

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