XMC1000, XMC4000

32-bit microcontroller series for industrial applications

Capture Compare Unit 4 (CCU4)

AP32287

Application Note

About this document

Scope and purpose

This application note provides a brief introduction to the key features of the CCU4 module and typical application examples. It also includes hints on its usage for users who wish to develop motor control application with the XMC™ microcontroller family.

Intended audience

This document is intended for engineers who are familiar with the XMC™ microcontroller series.

Applicable products

- XMC1000
- XMC4000
- DAVE ™

References

The user's manual can be downloaded from http://www.infineon.com/XMC.

DAVE™ and its resources can be downloaded from http://www.infineon.com/DAVE

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1 Introduction to the CCU4

The CAPCOM4 (CCU40/../43) is a multi-purpose timer unit for signal monitoring/conditioning and Pulse Width Modulation (PWM) signal generation. It is designed with repetitive structures and multiple timer slices that have the same base functionality. The internal modularity of the CCU4 translates into a software friendly system for fast code development and portability between applications.

The following image shows the main functional blocks of one of the four CC4y slices on a CCU4x.

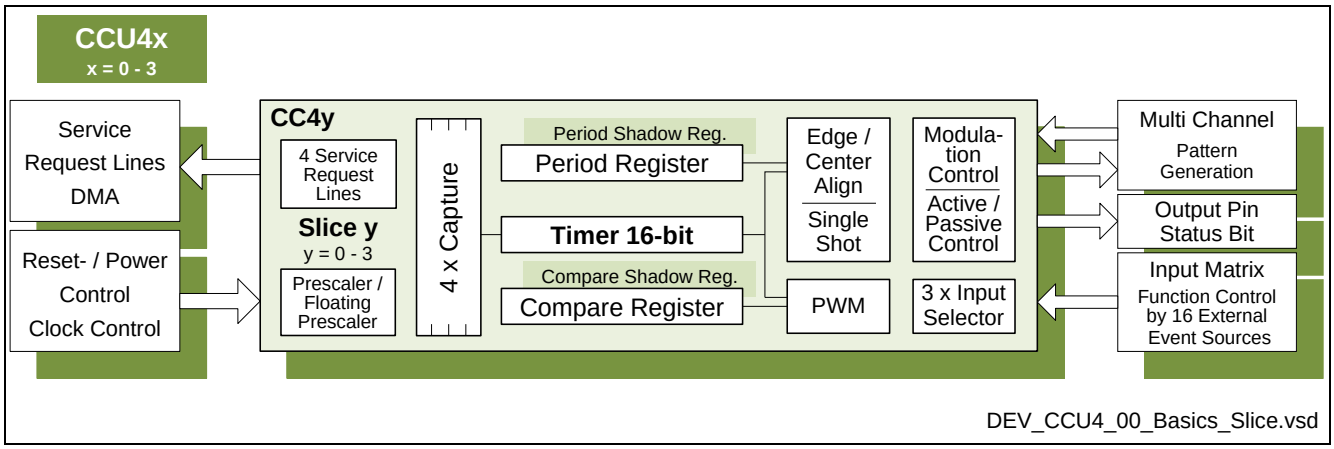

Figure 1 The timer slice block diagram

1.1 Basic timer functions

Each CCU4x has four 16-bit timer slices CC4y (y = 3-0) which can be concatenated up to 64-bits. Each slice has:

- 1 timer
- 4 capture registers
- 1 period register
- 1 compare register

Both the period and compare registers have shadow registers. Each slice can work independently in different modes, but they can also be synchronized, even to other CCU4x slices. They perform multichannel/multi-phase pattern generation with parallel updates.

Each timer slice can be configured to handle the basic functions illustrated in Figure 2 below.

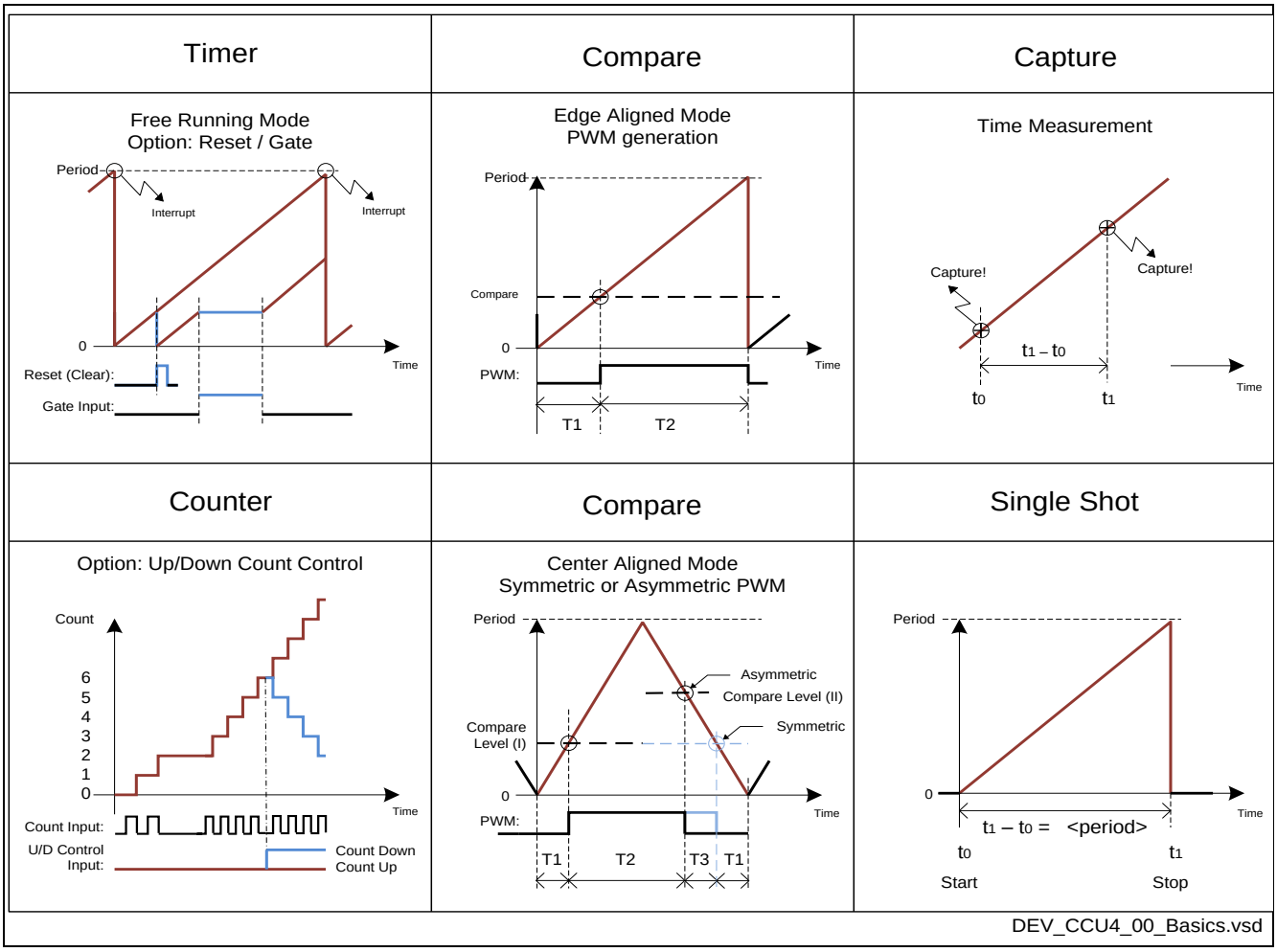

Figure 2 Basic functions of each timer slice

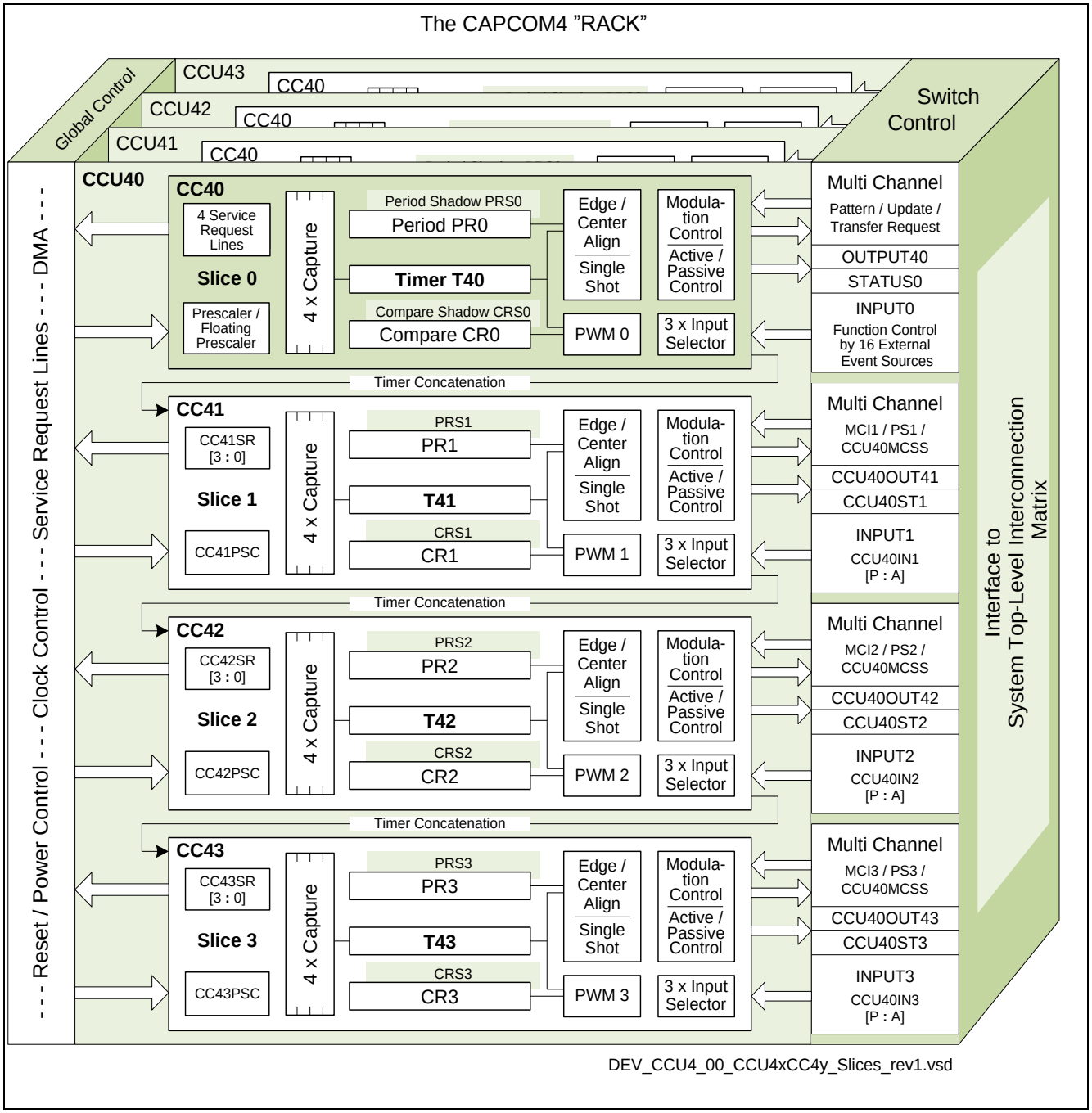

Figure 3 The four capture/compare unit CCU40-CCU43 basic system for CAPCOM4

1.2 CCU4 applications

Below are some typical application examples that demonstrate the various capabilities of the CAPCOM timer slices of the CCU4:

1. Simple time base with synchronization option by external events control
2. Power conversion system (PFC, SMPS) using single shot mode

3. Feedback sensor event monitoring and revolution by capture, count and position interface facilities (POSIF)
4. Multi-signal pattern on output pins, created by parallel multi-channel control
5. Drive & motor control with multi-phase system, phase adjustment and trap handling
6. 3-Level PWM for inverters and direct torque control (DTC) of AC motors and high precision synchronous motors
7. External events control of timer input functions by requests from external system units
8. Dithering PWM or period for DC-level precision, reduced EMI, fractional split of periods into micro step
9. Auto adjusting time base by floating prescaler for adaption of time measurement to a wide range of dynamics

The same applications are illustrated in the following figure:

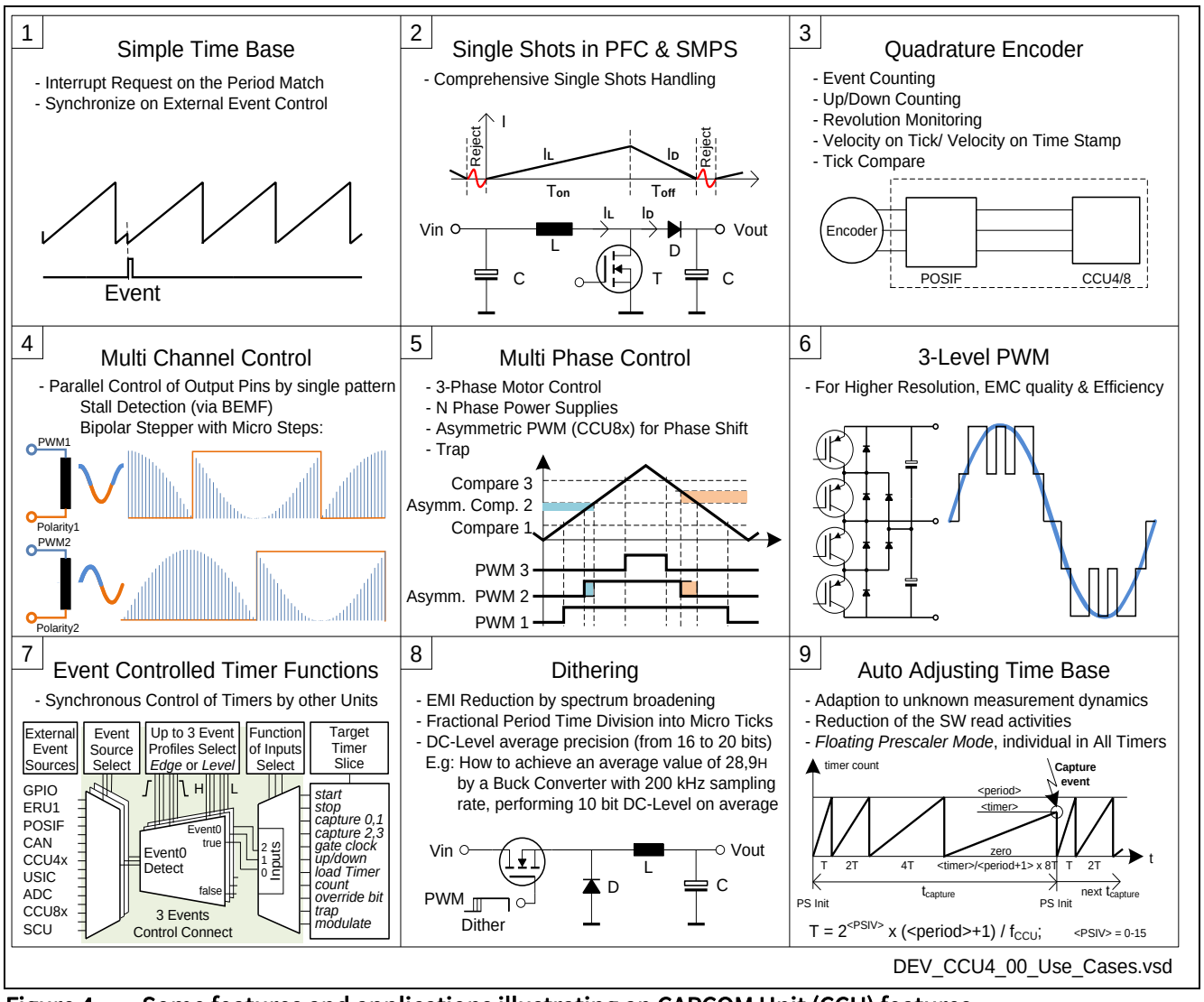

Figure 4 Some features and applications illustrating an CAPCOM Unit (CCU) features

1.3 Additional CCU4 features

Table 1 Summary of additional CCU4 features

Features	Operation
Single shot	If a slice is set in timer single shot mode (CC4yTC.TSSM), the timer and its run bit (TRB) are cleared by the period/one match that occurs next to when the TSSM bit was set. As a result, the timer is stopped.
Timer concatenation	Any timer slice can be concatenated with an adjacent timer slice by setting CC4yTC.TCE = 1.
Dithering PWM	It can be used with very slow control loops that cannot update the period/compare values in a fast manner. The precision can be maintained on a long run.
Dithering period time	Micro ticks can be used in the Interpolation between sensor pulses to achieve higher precision position monitoring.
Floating prescaler	By successive changing of the timer clock frequency periodically (no compare/capture event), the dynamic range is autonomously adapted to any time length.
External modulation	The output pin signal of a slice is modulated by external events.
Output state override	An external input signal source may override a slice's status bit (CC4yST) on an edge event by other external input signal source.
Multi-channel control	The output state of timer slices PWM signal(s) can be controlled in parallel by a single pattern.
External load	Each slice of CCU4 allows the user to select an external signal as a trigger for reloading the timer value with current compare/period register value.
Trap function	This function forces the PWM output into a predefined state, preset in the active/passive PSL bit. The power device can then be safely switched off.

1.4 CCU4 input control

1.4.1 Synchronized control of CAPCOM units on external events

External events control distribution to CCUs (including CCU8) starts for advanced applications with synchronized timer control. For example, in motor drive and power control, where 3-level inverters might require 12 synchronized PWMs. The limits are the realizable topography or timing pattern complexity range.

1.4.2 External control basics

The input functions of a slice are controlled by external sources. The external source(s), active mode(s) and input function(s) should be mapped to the 3 inputs of the slice in the CC4yINS and CC4yCMC registers. Function mode extension alternatives can be added by selecting them in the CC4yTC timer slice control register.

1.4.3 External events control

An external event control request can be an edge or level signal from a peripheral unit or a GPIO. It can be linked to the input selection stage of a CCU4xCC4y slice by using a comprehensive connection matrix. A slice with any of its 3 events setup detects a considered source-event-input profile and can be function controlled “remotely” this way.

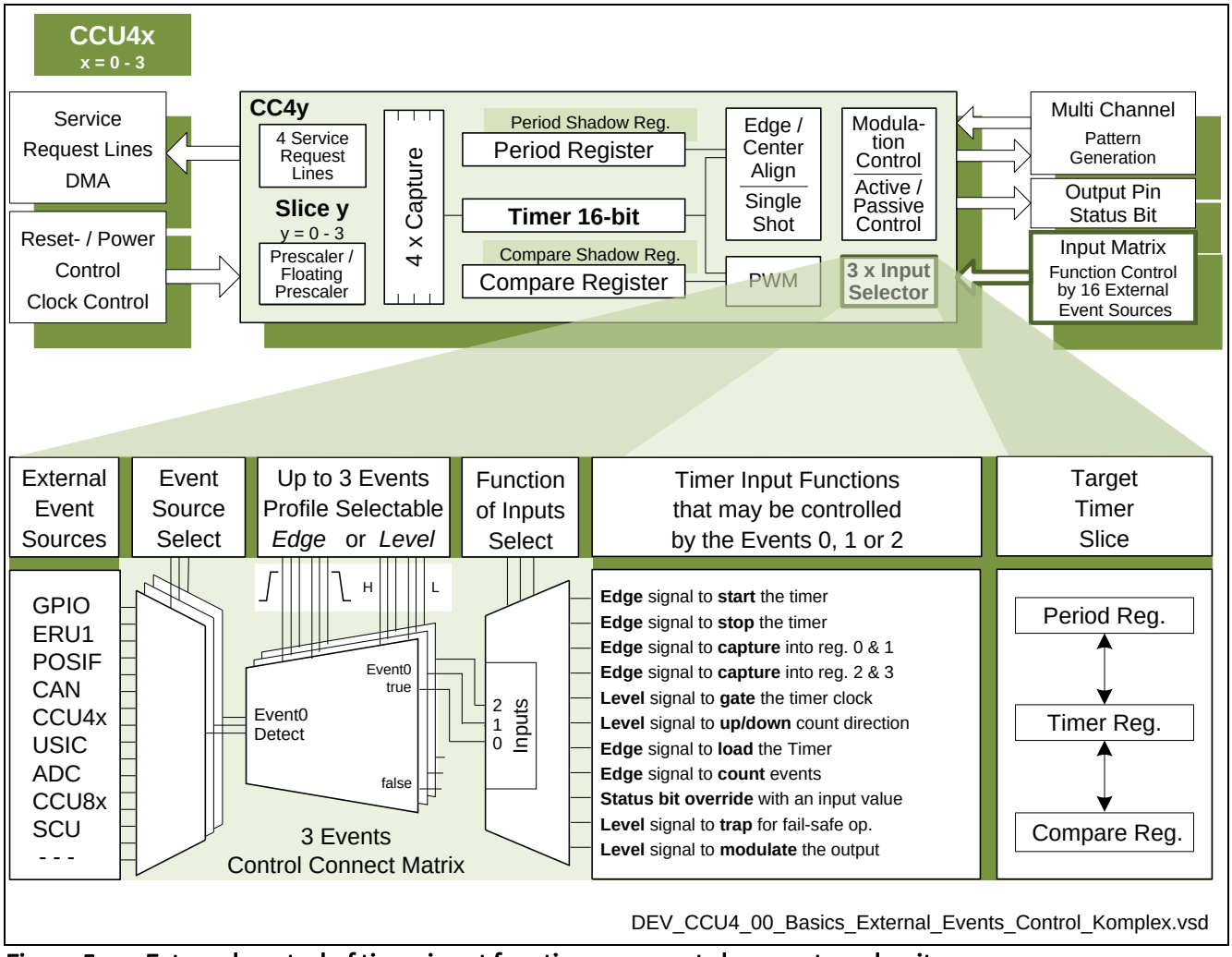

Figure 5 External control of timer input functions on events by an external units

1.4.4 External event sources

CCU4xCC4y input functions can be linked to external trigger requests from sources such as: GPIO, ERU, POSIF, CAN, CCU4x, USIC, ADC, CCU8x or SCU. Signal connections are given by the top-level interconnect matrix and the CC4yINS input select vector. The CC4yCMC register is used for function selection.

1.4.5 External event input functions

There are 11 timer input functions (e.g. ‘Start the Timer ’) each controllable by external events via 3 selectable input lines with configurable source-event profile conditions to the timer slices CC4y (y=0-3) of a CCU4x unit for start, stop, capture0-3, gate, up/down, load, count, bit override, trap and modulate output control.

There are also some extended input functions in the register CC4yTC for extended start, stop with flush/start, flush/stop or flush or extended capture mode. Together, with a read access register (ECRD), these simplify the administration of capture registers and full-flags when more than one slice is used in capture mode.

1.5 Capture basics

Each CAPCOM4 (CCU4x) has 4 timer-slices. Each slice has 4 capture value registers, split into 2 pairs that capture on selected event control input: Capt0 or Capt1, according to 2 possible pair schemes: either as 2 pairs for different events respectively to Capt0 and Capt1, or cascaded for the same event via Capt1.

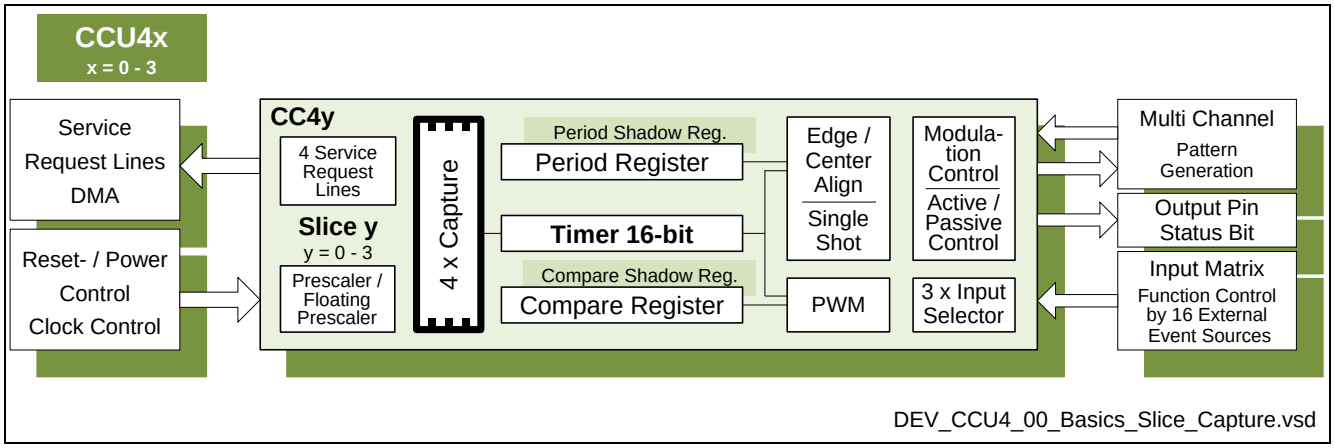

Figure 6 Timer slice with four capture registers

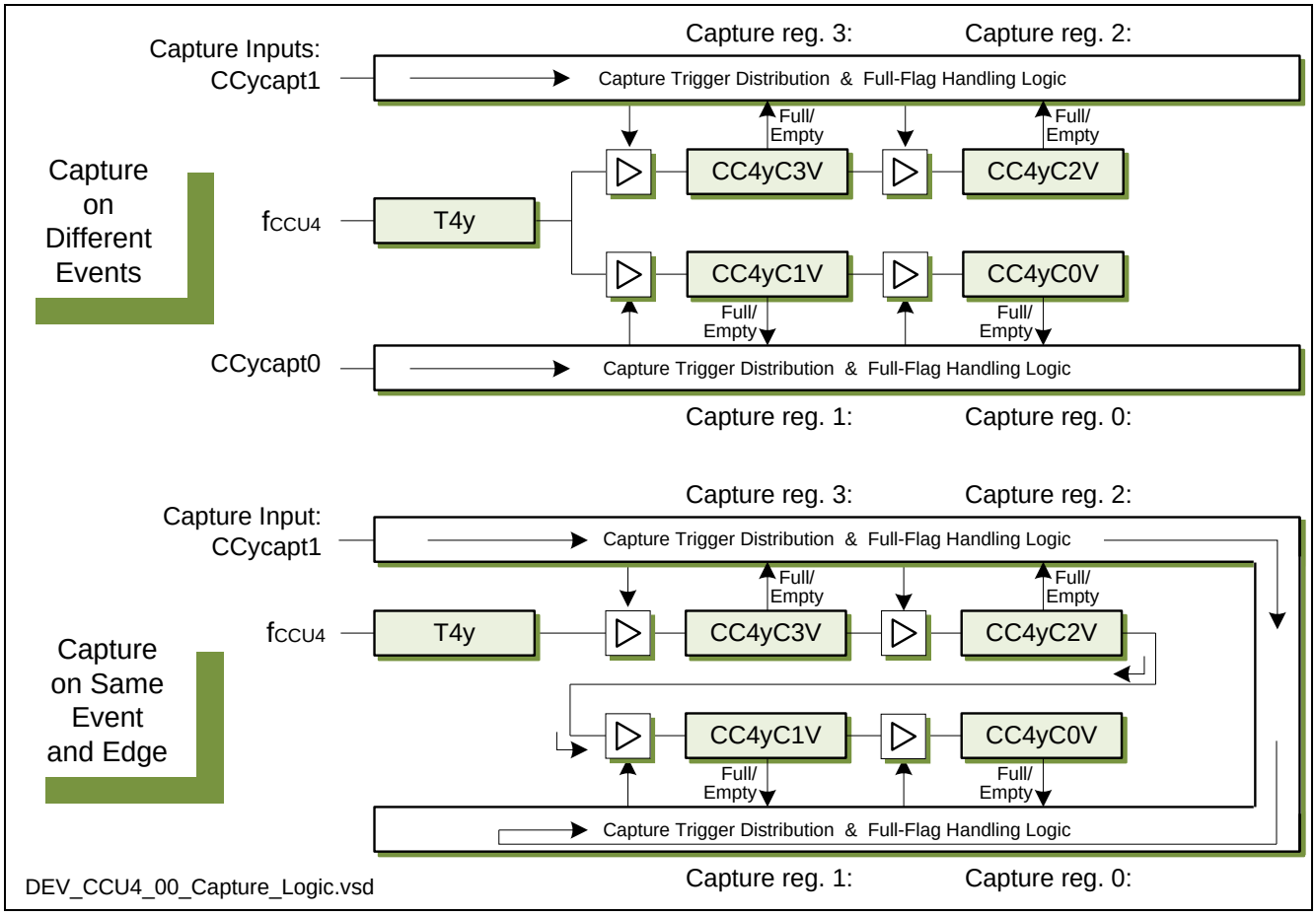

Figure 7 Basic capture mechanism – setup in two possible scheme alternatives

1.6 CCU4 output control

1.6.1 External control by timer events

A timer event can trigger external actions via the top-level interconnect matrix or on request for an interrupt. Each CAPCOM4 has four service request lines and each slice has a dedicated output signal CC4ySR[3…0], selectable to a line by CC4ySRS. This means timer slice events can request direct peripheral actions or an interrupt.

1.6.2 Top-level control of event request to/from a timer slice

Top-level control also means conditional control of event requests between a slice and other action providers. The Event Request Unit (ERU1) and the top-level interconnect matrix can combine, control and link event signals according to user defined request-to-action event patterns. For example, they can invoke I/O states, time windowing etc.

1.7 Compare basics

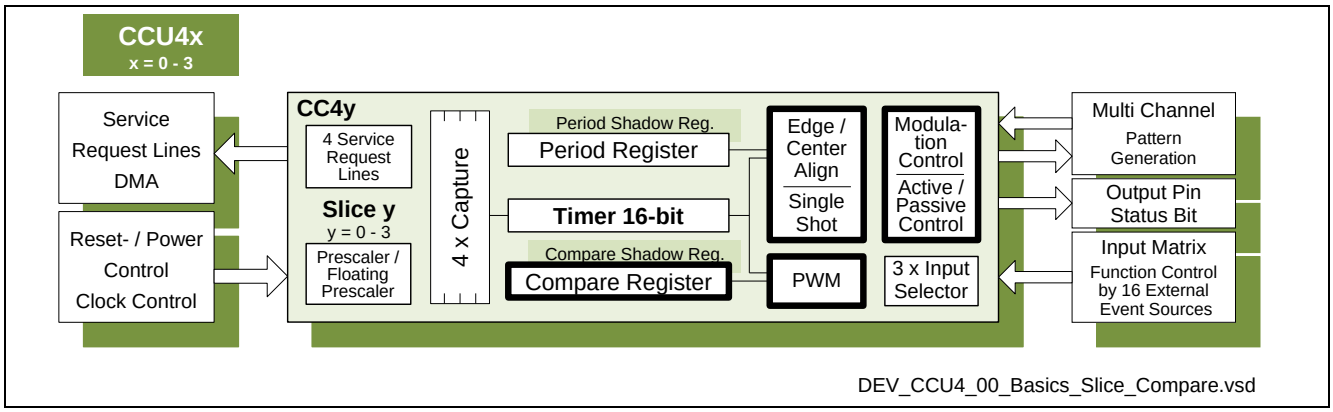

Figure 8 Timer slice compare registers and PWM related blocks

1.7.1 CCU4 shadow transfers

Whatever the slice configuration, whatever level of complexity, whatever the signal patterns, all the timer function parameters of the CAPCOM4 timers are assured coherent updates by hardware. They are updated from values in the shadow registers that, on a global preset request, are transferred simultaneously to all function registers at a period match or one match.

1.7.2 Shadow transfer of compare register values

The compare values that are targeted for an update operation have to be written into both the CC4yCRS shadow registers and the corresponding slice transfer set enable bits. For example, SySE in GCSS must be preset before period match (in edge aligned mode) or period/one match (in center aligned mode) for an update operation to be completed.

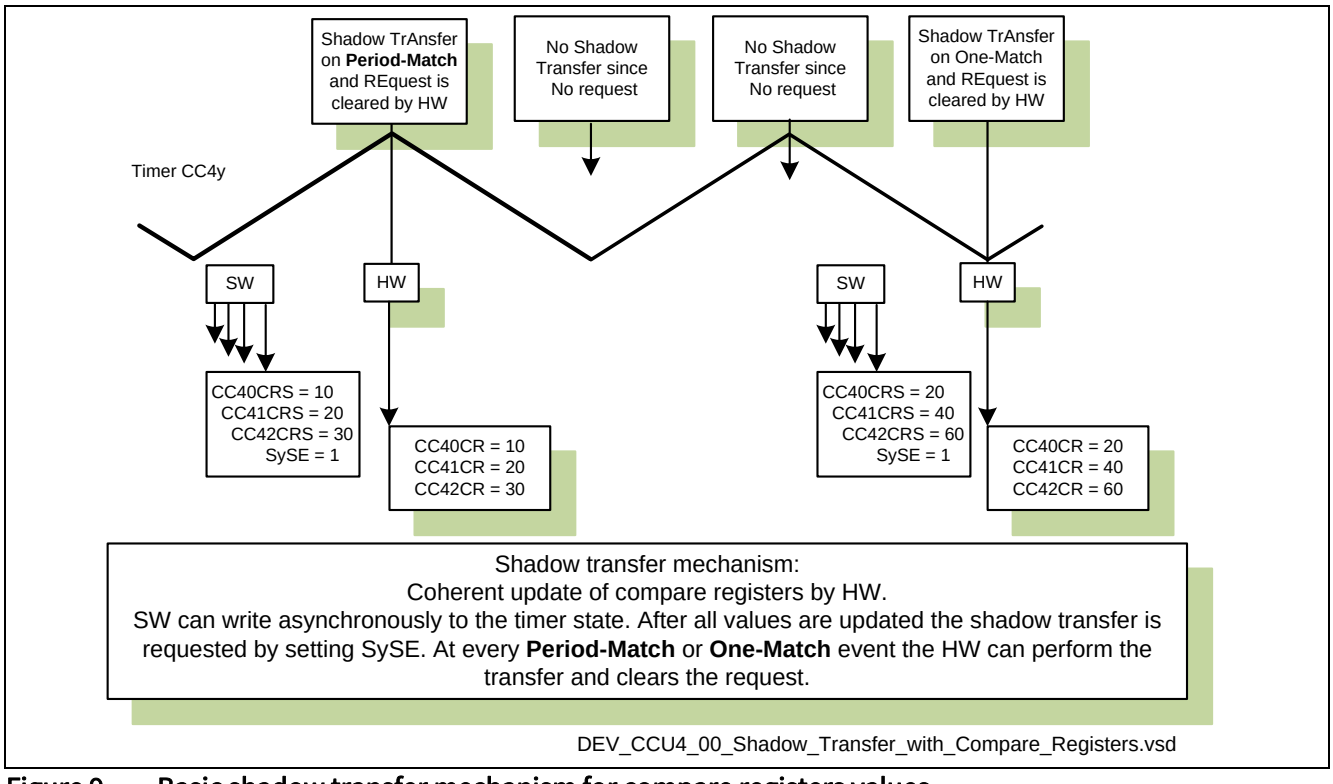

Figure 9 Basic shadow transfer mechanism for compare registers values

1.7.3 Asymmetric compare events

The benefit of shadow transfers on both period match and one match is to allow asymmetric compare events to be provided in center-aligned mode. The real-time conditions are similar to handling shadow value updates in edge-aligned mode.

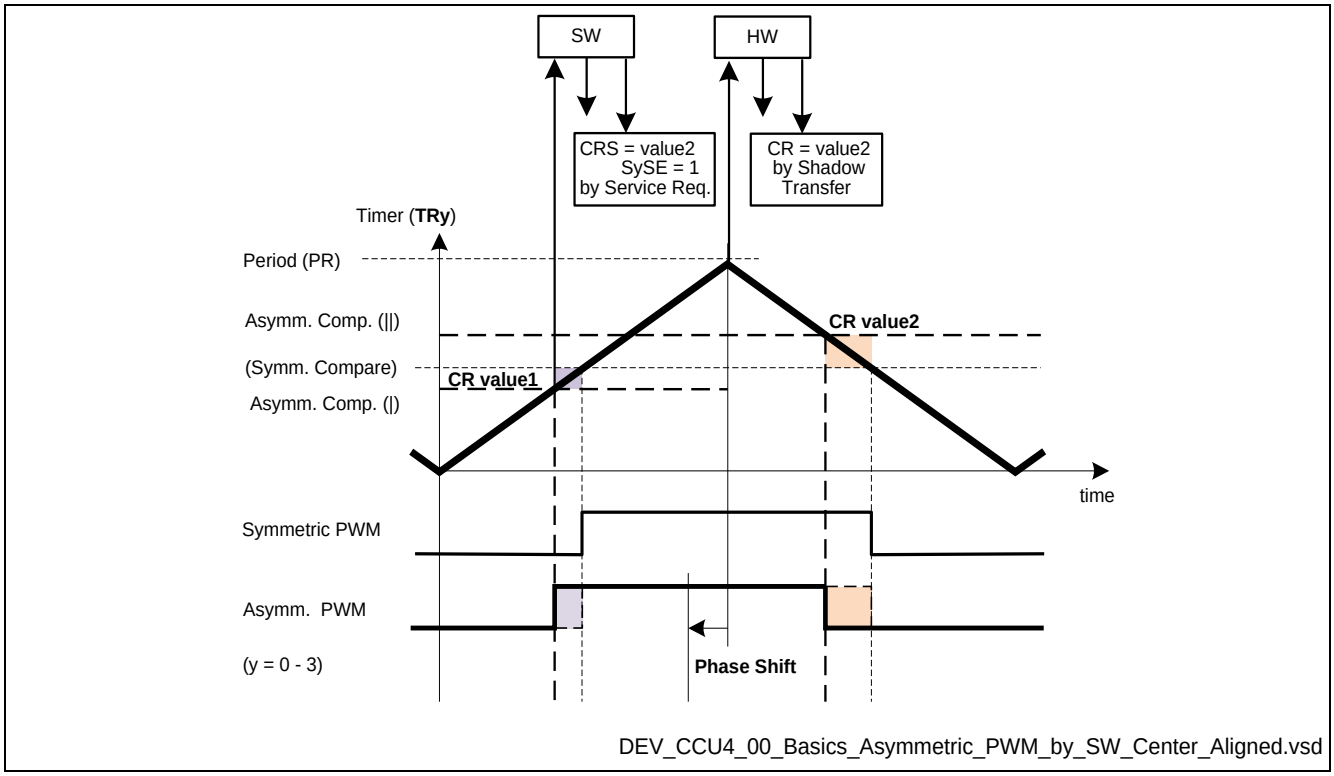

Figure 10 Asymmetric compare by shadow transfers on both period match and one match

1.7.4 Shadow transfers in general – compound shadow transfers

Beside the compare register (CR) values, there are also the timer period register (PR) and the PWM active/passive control bit (PSL) that are updated simultaneously on the SySE flag. Dithering or floating prescaler values are able to get a simultaneous update via the SyDSE and SyPSE request flags.

1.7.5 CCU4 output state and output pin PASSIVE/ACTIVE level control

The PASSIVE/ACTIVE state of a slice's internal output CCUxSTy (i.e. status bit CC4yST) is controlled by the compare level and the external modulation mode. The CC4yPSL passive/active bit PSL controls whether the external output pin state CCU4xOUTy (e.g. the PWM) is passive low / active high or vice-versa.

1.7.6 How to start a timer

There are two ways to start a timer:

- Directly by software, by setting the Timer Run Bit Set (TRBS)
- Indirectly by hardware when a specific event occurs in an external unit as determined by the top-level connection matrix for external events control for CAN, ADC, USIC, IO, CCU4/8, ERU1, POSIF etc.

1.7.7 Global start of CCU4

To achieve a synchronized start, the CCU4 uses either:

- A global start by software, with CCUx global start control bits in the CCUCON global start control register
- A global start by hardware, indirectly with external events control using the CC4yINS and CC4yCMC registers

The global start command enables almost an unlimited number of timers to be started, independently of the CAPCOM unit they belong to. The global start means that the timers are synchronized and all timings can be controlled in parallel, with many different kinds of generated output patterns.

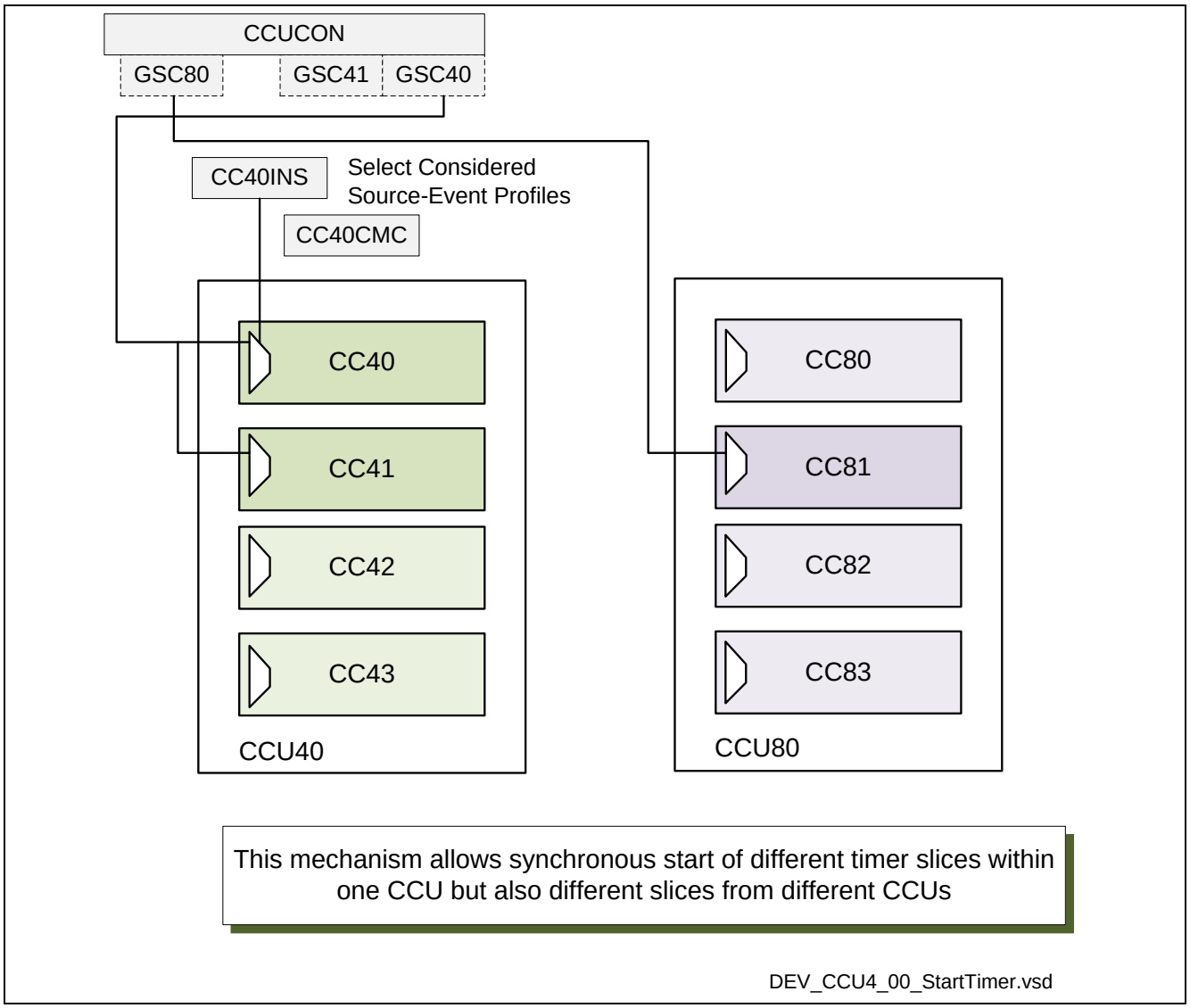

Figure 11 External event control with global start command

1.8 Example application: periodically changing the PWM duty cycle

This example uses a slice of the CCU4 (CCU40 Slice 0) to generate a PWM signal (output to P0.0). The CCU4 slice is configured in edge-aligned mode with a frequency of 1 Hz. An interrupt is generated on every compare match event, which alternates the PWM duty cycle between 33.3% and 66.7%. The CCU4 slice is started by an external start event on Event 0 connected to SCU.GSC40. It is targeted for the XMC1200.

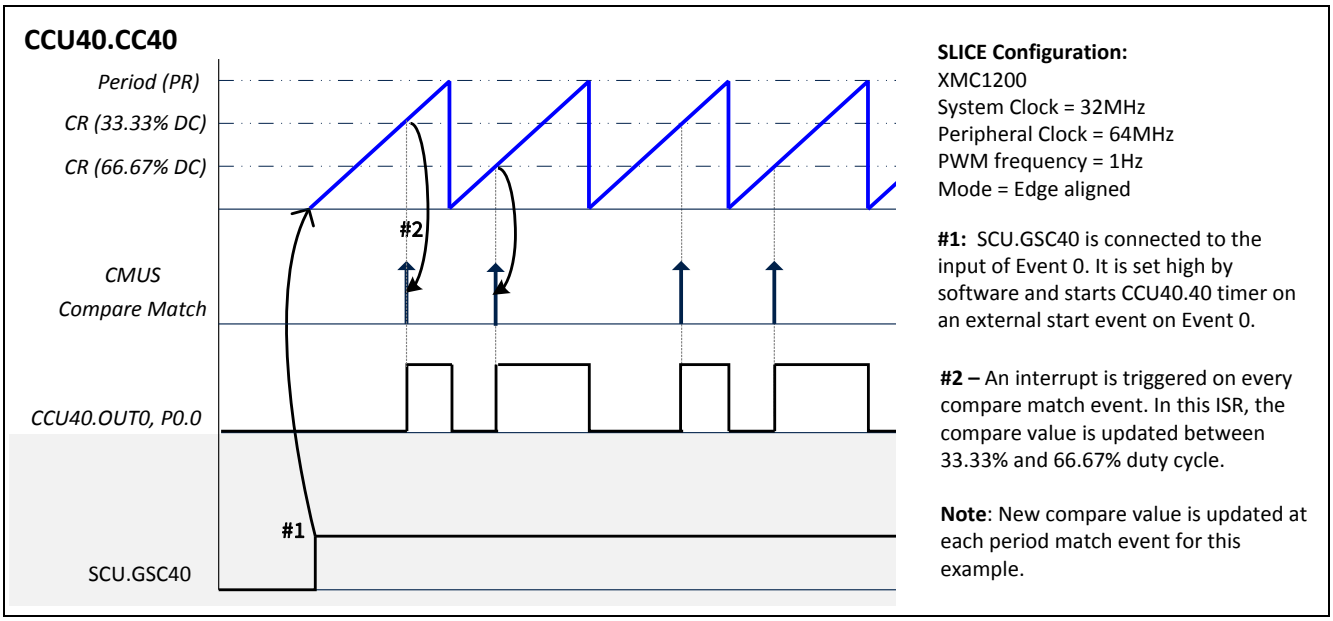

Figure 12 Example: periodic duty cycle update

1.8.1 Deriving the period and compare values

The clock relationship between f_{PWM}, f_{tclk} and f_{ccu4} is calculated as shown below:

- f_{ccu4} is the frequency of the CCU4 peripheral clock . It is the input to the PWM module.
- f_{tclk} is the timer resolution used to increment a timer counter. Each timer slice supports a dedicated prescaler value selector. In this example, a prescaler factor of 10 is chosen. This results in a prescaler value of 1024, resulting in a 16 uS resolution.
- In order for, f_{PWM} (frequency of the PWM signal) to be 1 Hz, the CCU4_CC40.PRS register is loaded with the value 62499.

Timer frequency: $f_{tclk} = \frac{f_{ccu4}}{Prescaler}$

Period value: $CCU4_{CC40}.PRS = \frac{f_{tclk}}{f_{PWM}} - 1$

Compare value: $CCU4_{CC40}.CRS = (1 - DC) * (PRS + 1)$

Table 2 Calculated prescaler factor, period and compare values

Type	Calculated value
Prescaler value	2^{10} = 1024
Period @1Hz frequency	62499
Compare value @33.33% DC	41668
Compare value @66.67% DC	20831

1.8.2 Macro and variable settings

XMC™ Lib project includes:

```
#include <xmc_ccu4.h>
#include <xmc_gpio.h>
#include <xmc_scu.h>
```

Project macro definitions:

```
#define MODULE_PTR              CCU40
#define MODULE_NUMBER           (0U)

#define SLICE0_PTR              CCU40_CC40
#define SLICE0_NUMBER           (0U)
#define SLICE0_OUTPUT           P0_0
```

Project Variables Definition:

```
volatile uint8_t count=1;
uint16_t comparevalue[]=
{
        /* Calculated based on PCLK of 64MHz */
        20831U, /* 66.67% duty cycle */
        41668U  /* 33.33% duty cycle */
};
```

1.8.3 XMC™ Lib peripheral configuration structure

XMC™ System Clock Unit (SCU) configuration:

The PWM period is calculated based on PCLK which is equivalent to 64 MHz.

```
XMC_SCU_CLOCK_CONFIG_t clock_config =
{
  .pclk_src = XMC_SCU_CLOCK_PCLKSRC_DOUBLE_MCLK,
  .rtc_src = XMC_SCU_CLOCK_RTCCLKSRC_DCO2,
   .fdiv = 0,
   .idiv = 1,
};
```

XMC™ Capture/Compare Unit 4 (CCU4) configuration:

```
XMC_CCU4_SLICE_COMPARE_CONFIG_t SLICE0_config =
{
  .timer_mode = (uint32_t) XMC_CCU4_SLICE_TIMER_COUNT_MODE_EA,
  .monoshot = (uint32_t) false,
  .shadow_xfer_clear = (uint32_t) 0,
  .dither_timer_period = (uint32_t) 0,
  .dither_duty_cycle = (uint32_t) 0,
  .prescaler_mode = (uint32_t) XMC_CCU4_SLICE_PRESCALER_MODE_NORMAL,
  .mcm_enable = (uint32_t) 0,
  .prescaler_initval = (uint32_t) 10,   /* in this case, prescaler = 2^10 */
  .float_limit = (uint32_t) 0,
```

```
  .dither_limit = (uint32_t) 0,
  .passive_level = (uint32_t) XMC_CCU4_SLICE_OUTPUT_PASSIVE_LEVEL_LOW,
  .timer_concatenation = (uint32_t) 0
};

XMC_CCU4_SLICE_EVENT_CONFIG_t SLICE0_event0_config=
{
  .mapped_input = XMC_CCU4_SLICE_INPUT_I,       /* mapped to SCU.GSC40 */
  .edge = XMC_CCU4_SLICE_EVENT_EDGE_SENSITIVITY_RISING_EDGE,
  .level = XMC_CCU4_SLICE_EVENT_LEVEL_SENSITIVITY_ACTIVE_HIGH,
  .duration = XMC_CCU4_SLICE_EVENT_FILTER_3_CYCLES
};
```

XMC™ GPIO configuration:

```
XMC_GPIO_CONFIG_t SLICE0_OUTPUT_config =
{
   .mode = XMC_GPIO_MODE_OUTPUT_PUSH_PULL_ALT4,
   .input_hysteresis = XMC_GPIO_INPUT_HYSTERESIS_STANDARD,
   .output_level = XMC_GPIO_OUTPUT_LEVEL_LOW,
};
```

1.8.4 Interrupt service routine function implementation

The CCU40 interrupt handler function is created to periodically modify the timer compare match values to achieve a PWM duty cycle between 33.3% and 66.7%.

```
void CCU40_0_IRQHandler(void)
{
    /* Clear pending interrupt */
    XMC_CCU4_SLICE_ClearEvent(SLICE0_PTR,XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP);

   /* Set new duty cycle value */
   XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, comparevalue[count]);

   count++;
   if(count==2)
   {
     count=0;
   }

   /* Enable shadow transfer for the new PWM value update */
   XMC_CCU4_EnableShadowTransfer(MODULE_PTR, XMC_CCU4_SHADOW_TRANSFER_SLICE_0);
}
```

1.8.5 Main function implementation

Before the start and execution of the timer slice software for the first time, the CCU4 must have been initialized appropriately using the following sequence:

- Set up the system clock

```
/* Ensure clock frequency is set at 64MHz (2*MCLK) */
XMC_SCU_CLOCK_Init(&clock_config);
```

- Enable clock, enable prescaler block and configure global control

```
/* Enable clock, enable prescaler block and configure global control */
XMC_CCU4_Init(MODULE_PTR, XMC_CCU4_SLICE_MCMS_ACTION_TRANSFER_PR_CR);

/* Start the prescaler and restore clocks to slices */
XMC_CCU4_StartPrescaler(MODULE_PTR);

/* Start of CCU4 configurations */
/* Ensure fCCU reaches CCU40 */
XMC_CCU4_SetModuleClock(MODULE_PTR, XMC_CCU4_CLOCK_SCU);
```

- Configure slice(s) functions, interrupts and start-up

```
/* Initialize the Slice */
XMC_CCU4_SLICE_CompareInit(SLICE0_PTR, &SLICE0_config);

/* Program duty cycle = 33.33% at 1Hz frequency */
XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, comparevalue[count]);
XMC_CCU4_SLICE_SetTimerPeriodMatch(SLICE0_PTR, 62499U);

/* Enable shadow transfer */
XMC_CCU4_EnableShadowTransfer(MODULE_PTR,       \
        (uint32_t)(XMC_CCU4_SHADOW_TRANSFER_SLICE_0|    \
                XMC_CCU4_SHADOW_TRANSFER_PRESCALER_SLICE_0));

/* Enable External Start to Event 0 */
XMC_CCU4_SLICE_ConfigureEvent(SLICE0_PTR, \
        XMC_CCU4_SLICE_EVENT_0, &SLICE0_event0_config);

XMC_CCU4_SLICE_StartConfig(SLICE0_PTR, XMC_CCU4_SLICE_EVENT_0, \
        XMC_CCU4_SLICE_START_MODE_TIMER_START_CLEAR);

/* Enable compare match events */
XMC_CCU4_SLICE_EnableEvent(SLICE0_PTR, XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP);

/* Connect compare match event to SR0 */
XMC_CCU4_SLICE_SetInterruptNode(SLICE0_PTR, \
        XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP, XMC_CCU4_SLICE_SR_ID_0);

/* Set NVIC priority */
NVIC_SetPriority(CCU40_0_IRQn, 3U);

/* Enable IRQ */
NVIC_EnableIRQ(CCU40_0_IRQn);

/* Enable CCU4 PWM output */
XMC_GPIO_Init(SLICE0_OUTPUT, &SLICE0_OUTPUT_config);


/* Get the slice out of idle mode */
XMC_CCU4_EnableClock(MODULE_PTR, SLICE0_NUMBER);
```

- Start timer running

```
/* Create a low to high transition on SCU.GSC40 to start timer */
XMC_SCU_SetCcuTriggerLow(XMC_SCU_CCU_TRIGGER_CCU40);
XMC_SCU_SetCcuTriggerHigh(XMC_SCU_CCU_TRIGGER_CCU40);
```

1.8.6 Implementation to start timer by software

Alternatively, the timer can be started directly by software, setting the Timer Run Bit Set (TRBS).

```
/* Start the TImer*/
XMC_CCU4_SLICE_StartTimer(SLICE0_PTR);
```

2 Output pattern generation with CCU4

2.1 The principal compare blocks

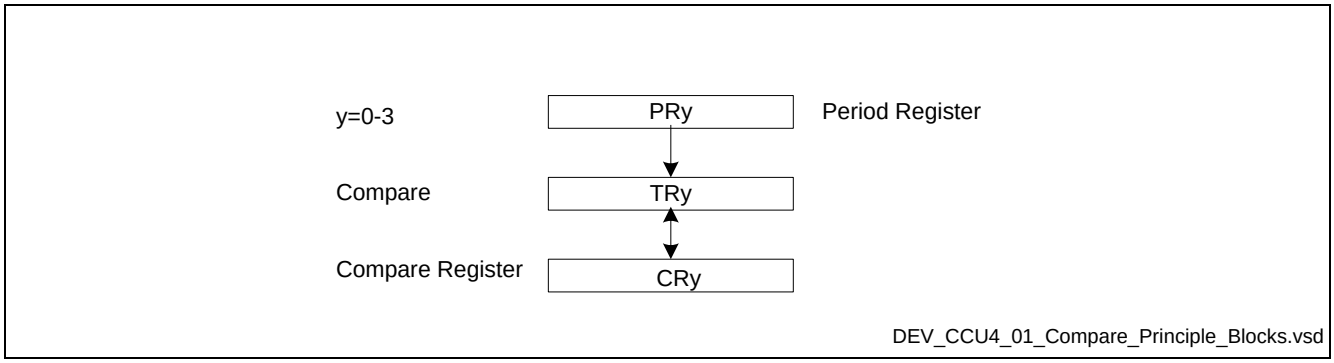

Figure 13 The compare blocks

2.1.1 PWM range 0 – 100% in up-count mode

The up-count mode of the compare rule is very simple: As long as the timer register value is equal or greater than the compare register value, the status bit (CCST or even named CCU4xSTy) is set to one. Otherwise it is set to zero. The dynamic PWM range can be set to any value from 0% to 100%.

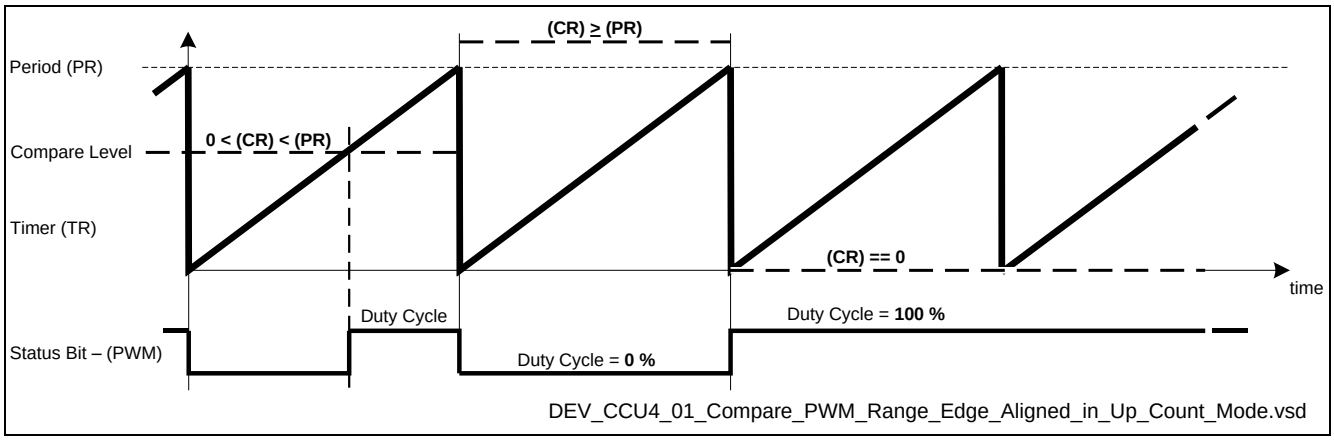

Figure 14 PWM Range in up-count mode

2.1.2 PWM range 0 – 100% in down-count mode

The down-count mode of the compare rule is the same as in up-count mode: When the timer register value is equal or greater than the compare register value, the status bit (CCST, CCU4xSTy) is set to one. Otherwise it is set to zero. The dynamic PWM range can be set to any value from 0% to 100%.

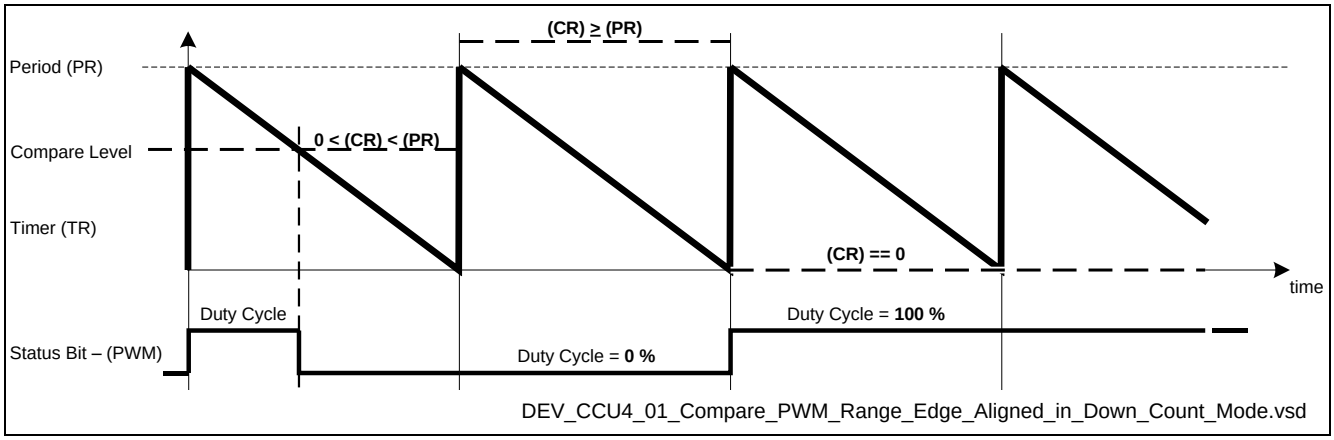

Figure 15 PWM range in down-count mode

2.1.3 PWM range 0 – 100% in center aligned mode

The center-aligned mode of the compare rule is the same as up or down count modes: when the timer register value is equal or greater than the compare register value, the Status Bit (CCST or CCU4xSTy) is set to one. Otherwise it is set to zero. The PWM value can be varied from 0% to 100%.

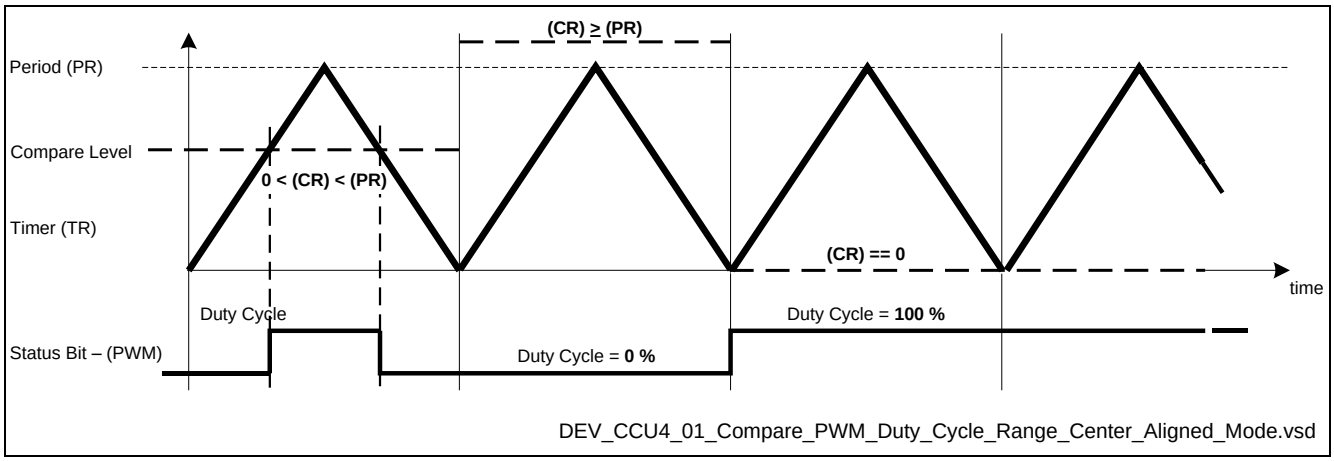

Figure 16 PWM range 0% - 100% in center aligned mode

2.1.4 Compare reload with shadow transfer rules

A reload of registers by shadow transfers from the associated shadow registers occurs according to the following rules:

- In the next clock cycle after a period match while counting up
- In the next clock cycle after a one match while counting down
- Immediately if the timer is stopped and a transfer request was triggered

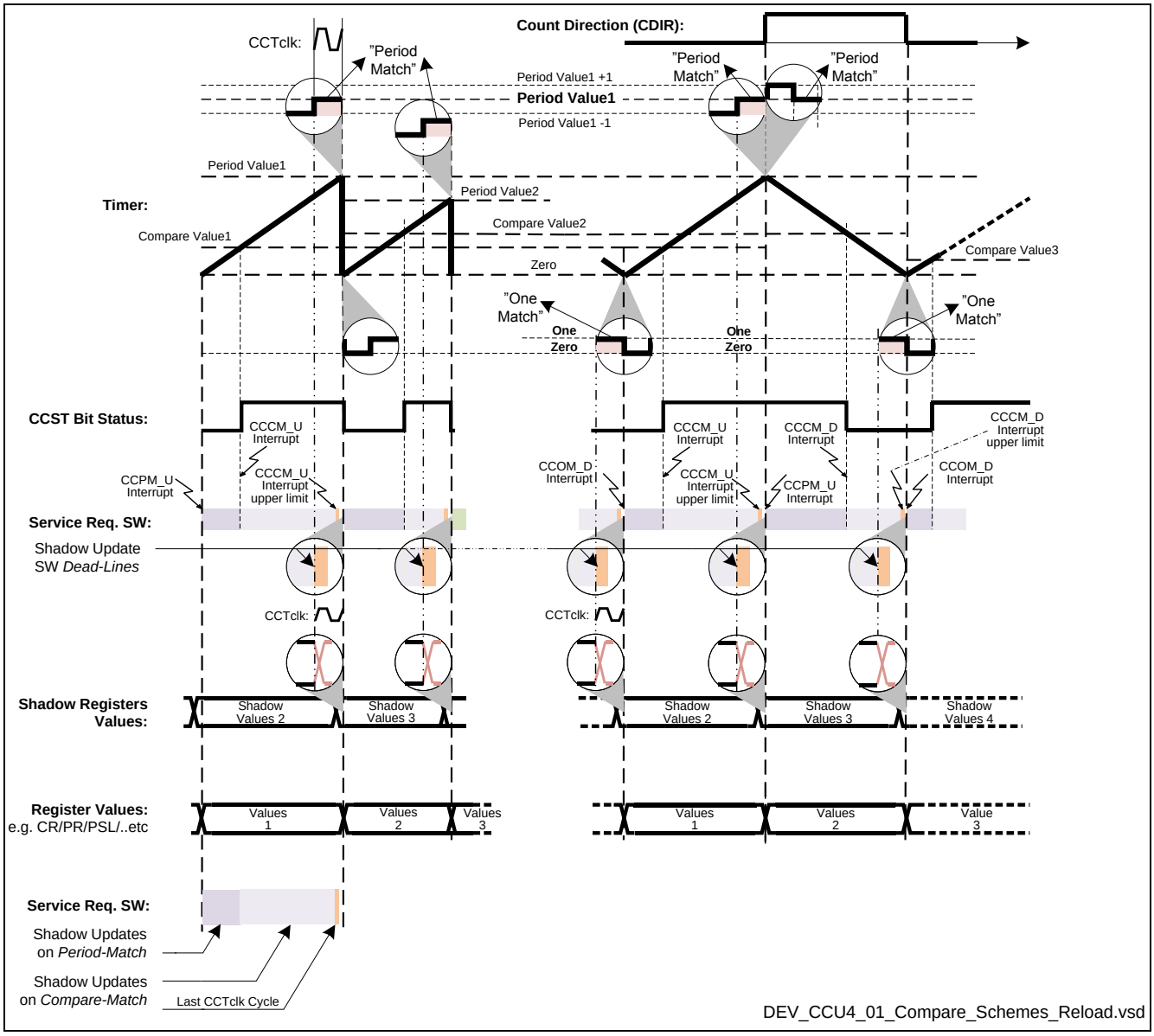

Figure 17 Compare reload scheme in detail

Whatever the slice configuration, whatever level of complexity, whatever the signal patterns, all the timer function parameters of the CAPCOM4 timers are assured coherent updates by hardware. They are updated from values in the shadow registers that, on a global preset request, are transferred simultaneously to all function registers at a period match or one match.

There is a global register, GCSS, carrying all enable-flags that have to be preset by software to selectively activate the targeted shadow transfer requests that will be cleared by hardware after the transfer. The total real-time correctness is achieved by the logic operations that are essential for safe power switching.

The compare values that are targeted for an update operation must be written into the CC4yCRS shadow register and the corresponding slice transfer set enable bit. For example, for an update operation to be completed, SySE in GCSS must be preset before period match (in edge aligned mode) or period/one match (in center aligned mode).

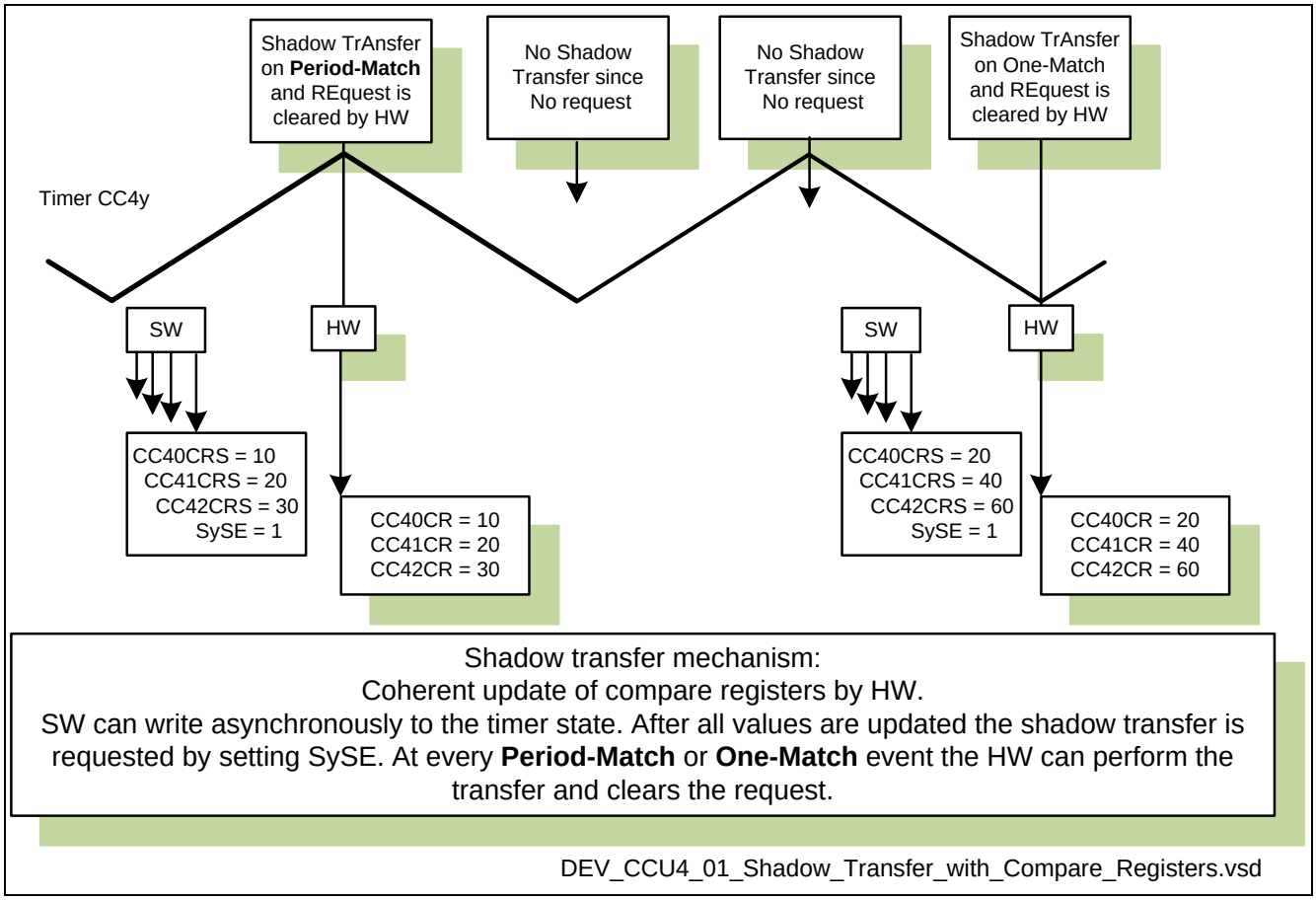

Figure 18 Shadow transfer mechanism with compare registers

Beside the compare (CR) values, there are also the timer Period Register (PR) and the PWM Active/Passive control bit (PSL) that are updated simultaneously on the SySE flag. The SyDSE and SyPSE request flags can also simultaneously update dithering or floating prescaler values.

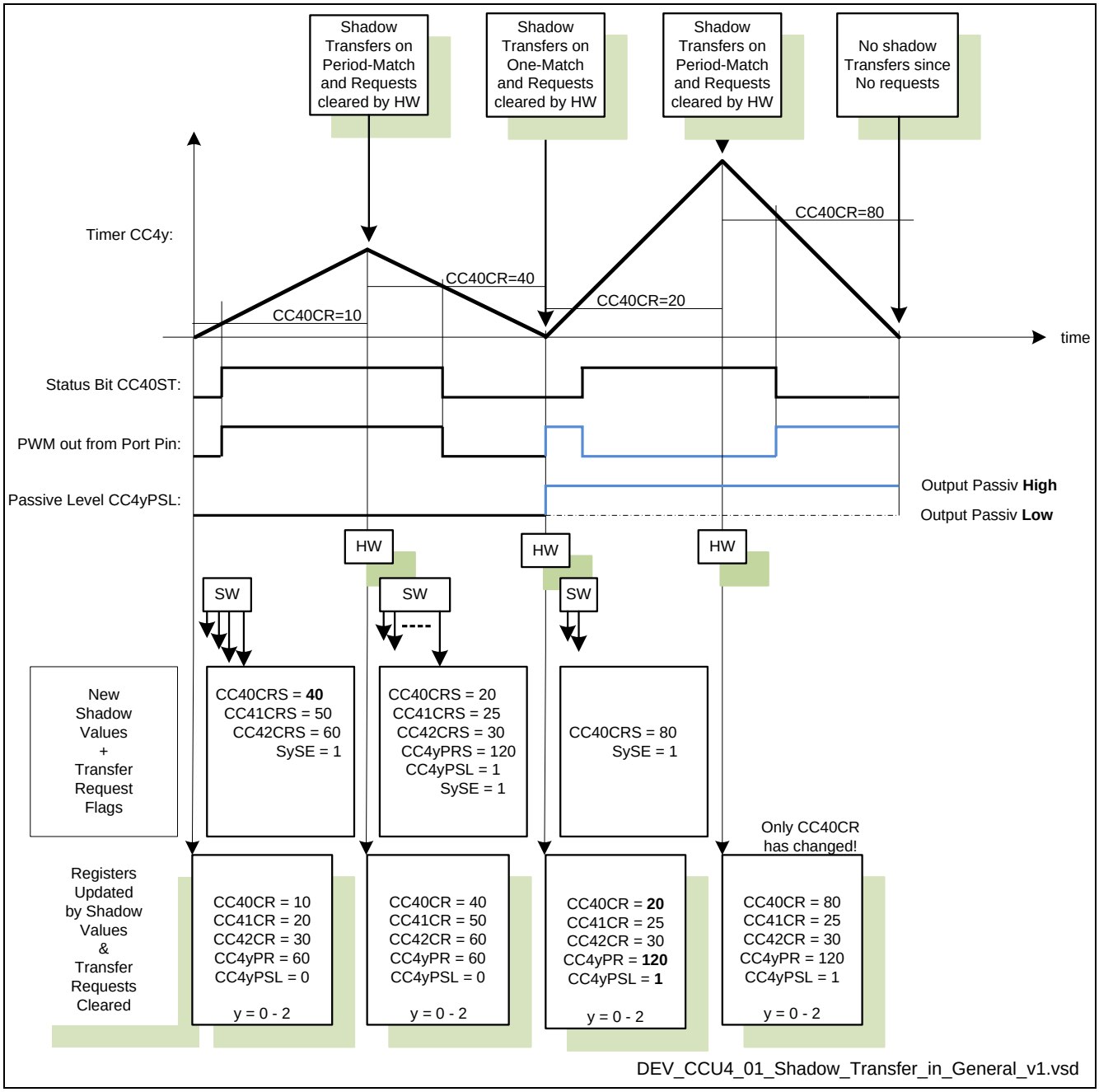

Figure 19 Compound shadow transfer mechanism with coherent update of PWM

2.1.5 CCU4 output control compare mode

The passive/active state of a slice internal output CCUxSTy (status bit CC4yST) is controlled by the compare level and external modulation mode. The CC4yPSL passive/active bit PSL controls whether the external output pin state CCU4xOUTy (for example, the PWM) should be passive low / active high or vice versa.

2.1.6 Event request in compare mode

A compare event can trigger external actions via the top-level interconnect matrix or by an interrupt. Each CAPCOM4 has four service request lines and each slice has a dedicated output signal CC4ySR[3…0], selectable to a specific line by CC4ySRS. For example, compare events can request for immediate ADC actions or interrupts.

Output pattern generation with CCU4

Top-level control also means conditional control of event requests between a slice and other action providers. The Event Request Unit (ERU1) can be combined with the top-level interconnect matrix to control and link event signals according to user defined request-to-action event patterns. For example, ADC triggering combined on I/O events.

A slice interface to ERU1 and to the top-level interconnect matrix can be represented by a simplified scheme. To complete the picture of the possible interaction, this scheme also shows how operations can be extended to involve DMA transfers (by the GPDMA), triggered by a handler (DLR) on the service request lines (SRn).

If an application requires ADC conversion to start on timer events under specific conditions rather than directly via a top-level interconnect matrix path, then the ERU1 is able to offer an alternate signal path. This may involve dependence on a port pin, a time window from a second timer, or a certain sequence of event patterns.

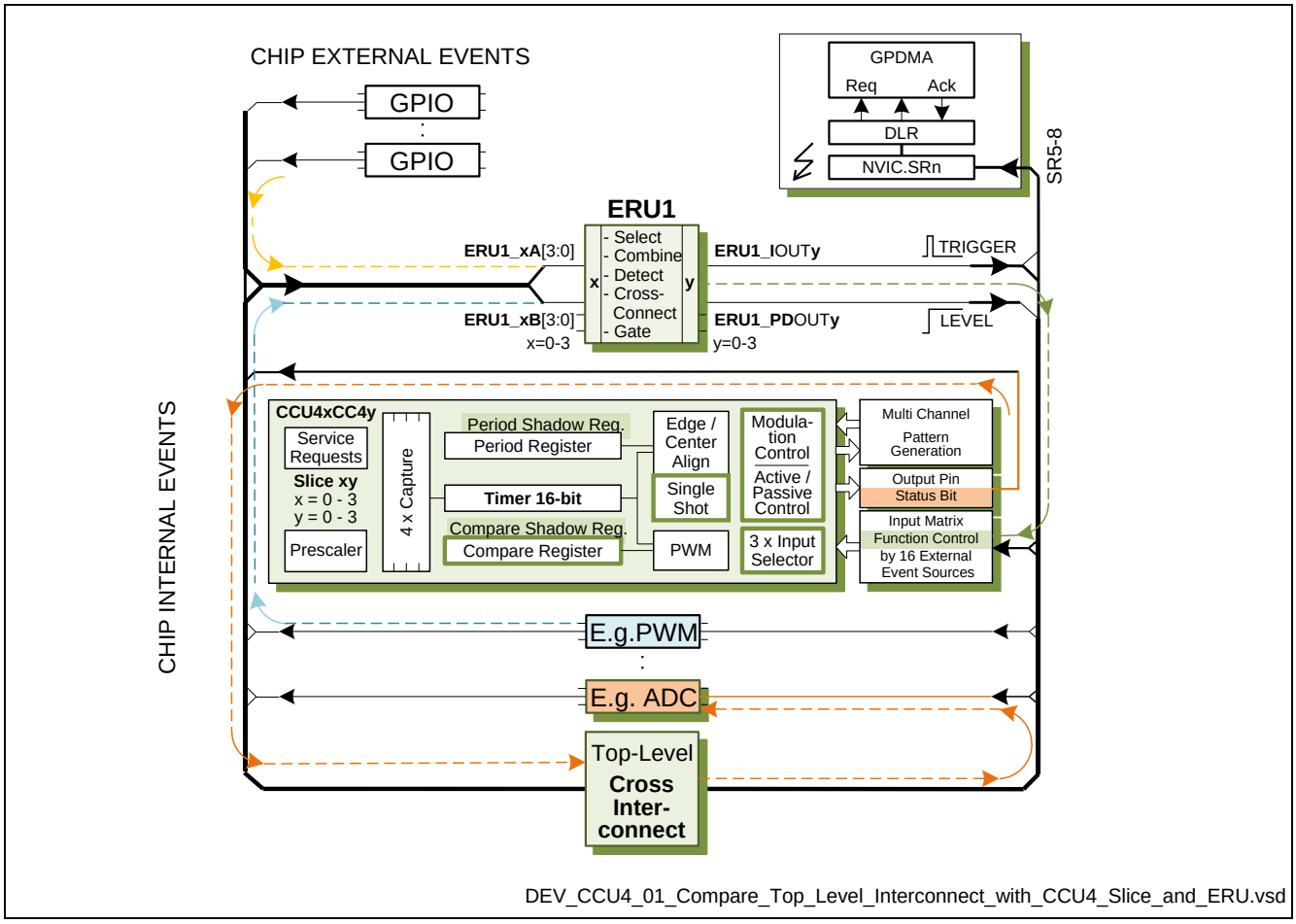

Figure 20 Using CCU4 and ERU1 for delayed ADC start controlled by an IO

The above example shows CCU4xCC4y is a single shot delay timer. The status bit (red) is delayed and set by the compare event, and delays an ADC-start when triggered by a PWM timer (blue) on a GPIO state (orange). The ERU1 combines, detects and links it all as a trigger (green) via the delay timer and the top-level interconnect matrix to the ADC.

2.2 Example application: CCU4 as Digital-to-Analog Converter (DAC)

Many embedded microcontroller applications require the generation of analog signals. Sometimes, a dedicated DAC IC is used for this purpose. In fact, PWM signals can often be used to create DC and AC analog signals with CCU4. CCU4 can be used as a form of signal modulation where data is represented by the ratio of the ON time (T_1) to the period (also known as the duty cycle). In this example, the CCU4 timer is used to generate a sinusoidal waveform of 1 kHz.

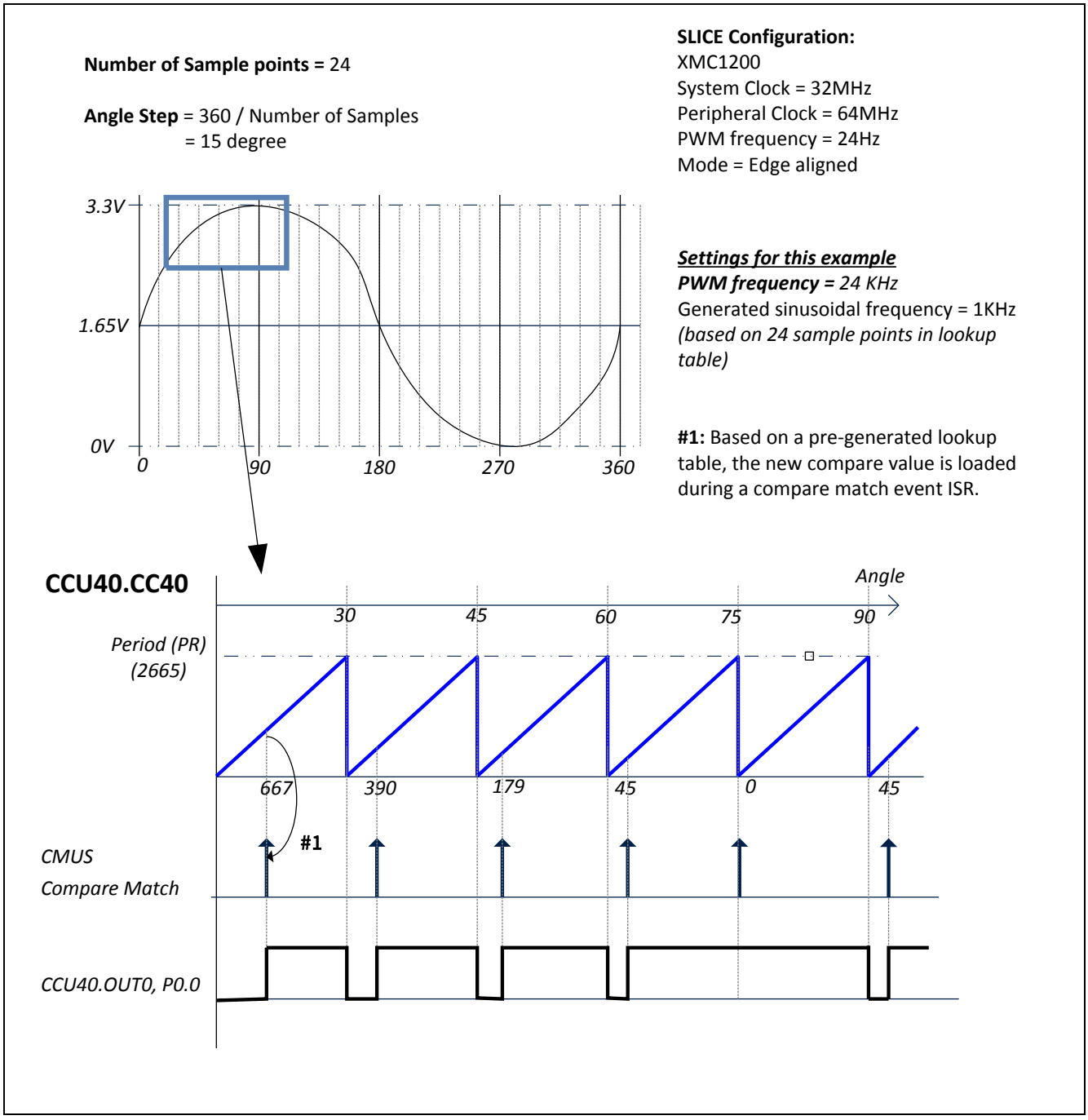

Figure 21 Example: generating a sinusoidal waveform

2.2.1 Theory of operation

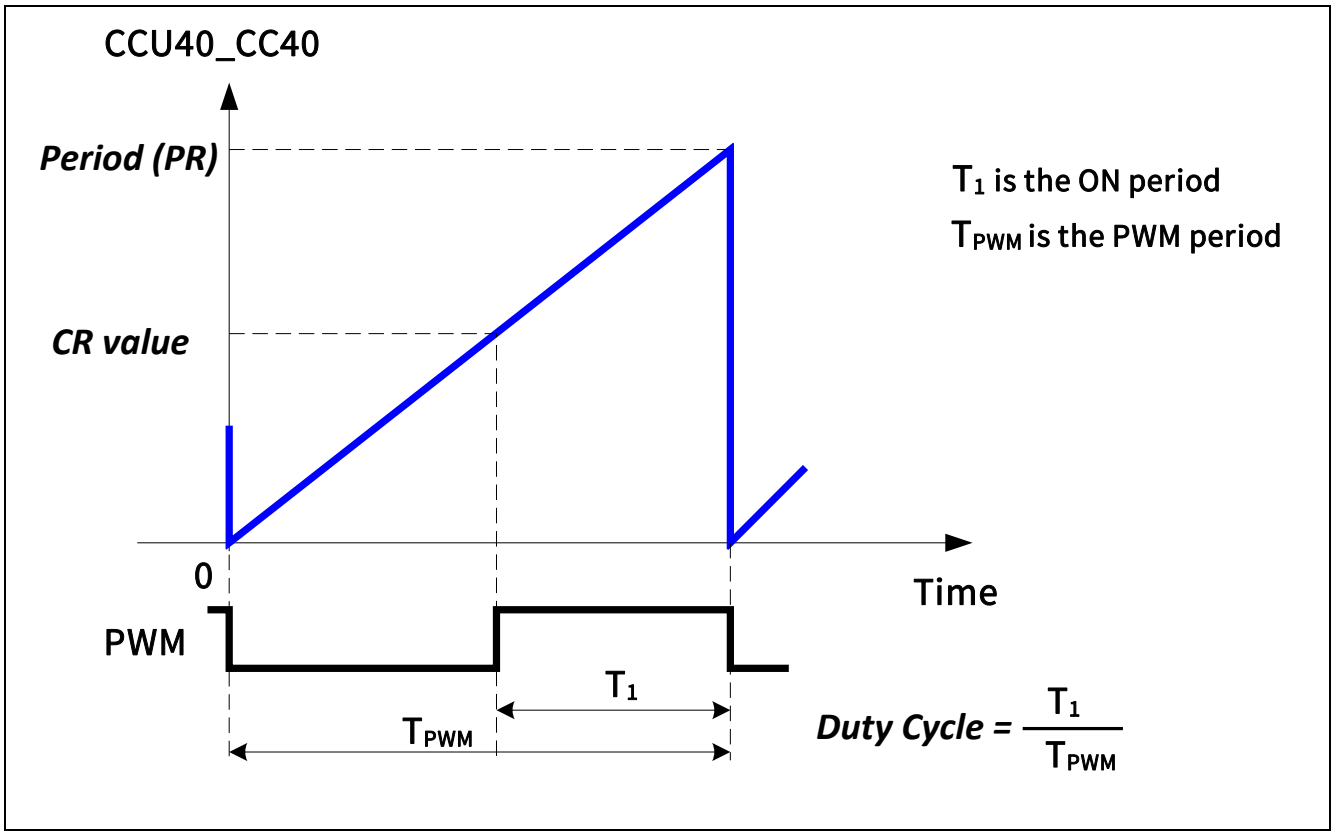

Figure 22 CCU4 PWM signal with variable duty cycle

A given ON time (T_1) corresponds to an average DC voltage, which is linearly proportional to the duty cycle. In the implementation of DAC using CCU4, the duty cycle can be varied while fixing the period value, or vice versa. Theoretically if the duty cycle of CCU4 is varied with time, the signal is filtered, the output of the filter is an analog signal. In fact, passing the CCU4 PWM signal through a low-pass filter (LPF) removes a reasonable amount of ripple. A simple RC low-pass filter circuit or built-in LPF function in signal measurement equipment could be used to eliminate the inherent noise components.

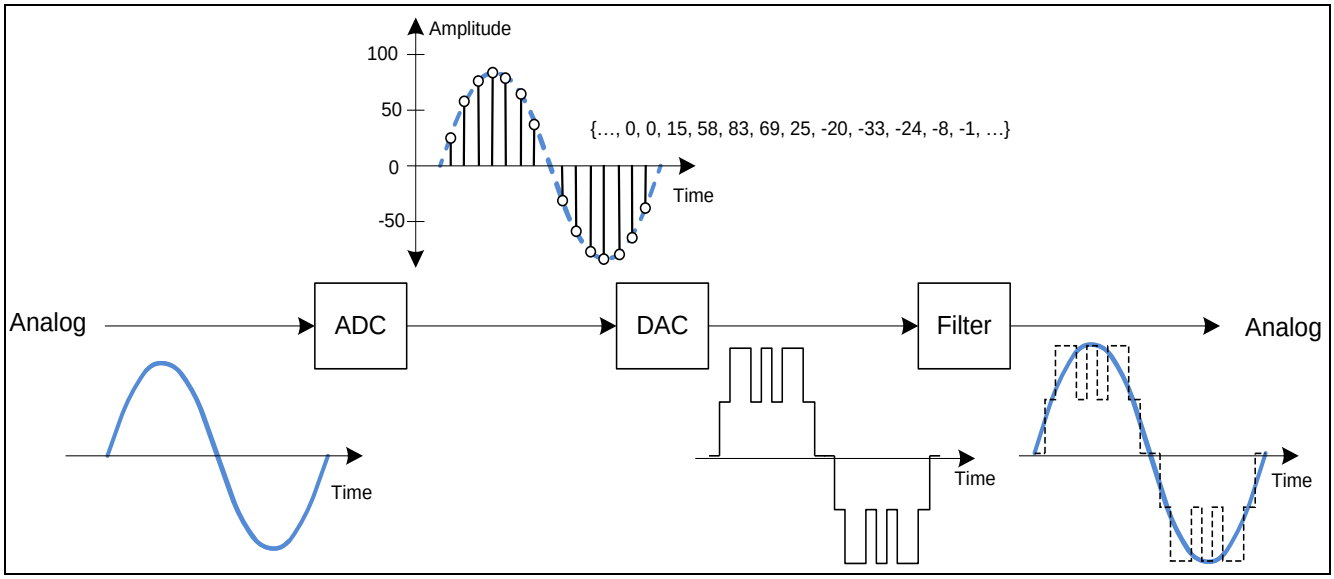

Figure 23 Process involves ADC to DAC conversion

2.2.2 Deriving the period value

In this example, the frequency of the sinusoidal waveform generated is fixed at 1 kHz with 24 sample points. Therefore, the PWM frequency is fixed at 24 kHz. The clock relationship between f_{PWM}, f_{tclk} and f_{ccu4} is calculated as shown below:

- f_{ccu4} is the frequency of the CCU4 peripheral clock. It is the input to the PWM module.
- f_{tclk} is the timer resolution used to increment a timer counter. Each timer slice supports a dedicated prescaler value selector.
- In order for, f_{PWM} (frequency of the PWM signal) to be 24 kHz, the CCU4_CC40.PRS register is loaded with the value 2667.

Timer frequency: $f_{tclk} = \frac{f_{ccu4}}{Prescaler}$

Period value: $CCU4_{CC40}.PRS = \frac{f_{tclk}}{f_{PWM}} - 1$

Table 3 Calculated prescaler factor and period values

Type	Calculated value
Prescaler value	$2^0 = 1$
Period @24 kHz frequency	2665

2.2.3 Generating a look-up table

DAC resolution is the smallest increment in the analog output voltage that corresponds to an increment in the DAC digital count. In other words, the finest increment of output voltage level is directly proportional to incrementing the CCU4 PWM duty cycle value.

In general, the resolution increases with the increase of sample points in the PWM signal.

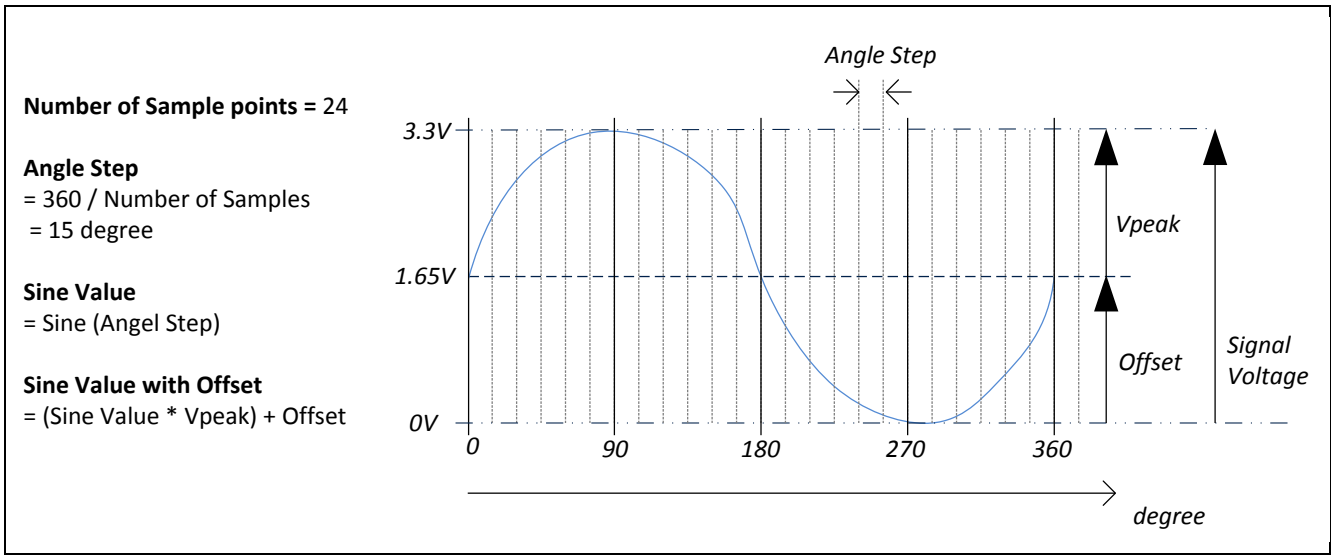

Figure 24 Deriving the sine value with reference to signal voltage

Output pattern generation with CCU4

In this example, the sinuoisodal waveform is divided into 24 sample points. Each change in PWM duty cycle is the equivalent of one DAC sample.The CCU4 period is fixed at 24 kHz. The calculation for the look-up table is as shown below:

Signal frequency: Signal frequency = $f_{PWM} * Number\ of\ Samples$

Duty cycle: $DC = \frac{Sine\ Value\ with\ offset}{Signal\ Voltage}$

Compare value: $CCU4_{CC40}.CRS = (1 - DC) * (PRS + 1)$

Table 4 Calculated look-up table for compare values

Angle step (degree)	Sine value	Sine value with offset	Duty cycle (%)	Compare value (CRS)
0 or 360	0.000	1.650	50.00	1333
15	0.259	2.077	62.94	988
30	0.500	2.475	75.00	667
45	0.707	2.817	85.36	390
60	0.866	3.079	93.30	179
75	0.966	3.244	98.30	45
90	1.000	3.300	100.00	0
105	0.966	3.244	98.30	45
120	0.866	3.079	93.30	179
135	0.707	2.817	85.36	390
150	0.500	2.475	75.00	667
165	0.259	2.077	62.94	988
180	0.000	1.650	50.00	1333
195	-0.259	1.223	37.06	1678
210	-0.500	0.825	25.00	2000
225	-0.707	0.483	14.64	2276
240	-0.866	0.221	6.70	2487
255	-0.966	0.056	1.70	2621
270	-1.000	0.000	0.00	2666
285	-0.966	0.056	1.70	2621
300	-0.866	0.221	6.70	2487
315	-0.707	0.483	14.64	2276
330	-0.500	0.825	25.00	2000

345	-0.259	1.223	37.06	1678

2.2.4 Circuit diagram and signals

To achieve DAC conversion, the output of CAPCOM4 (CCU40.OUT0) is internally connected to the pull-up register. The RC low pass filter can be added externally as shown in Figure 25. Another option is to use the internal RC filter that is built into many oscilloscopes.

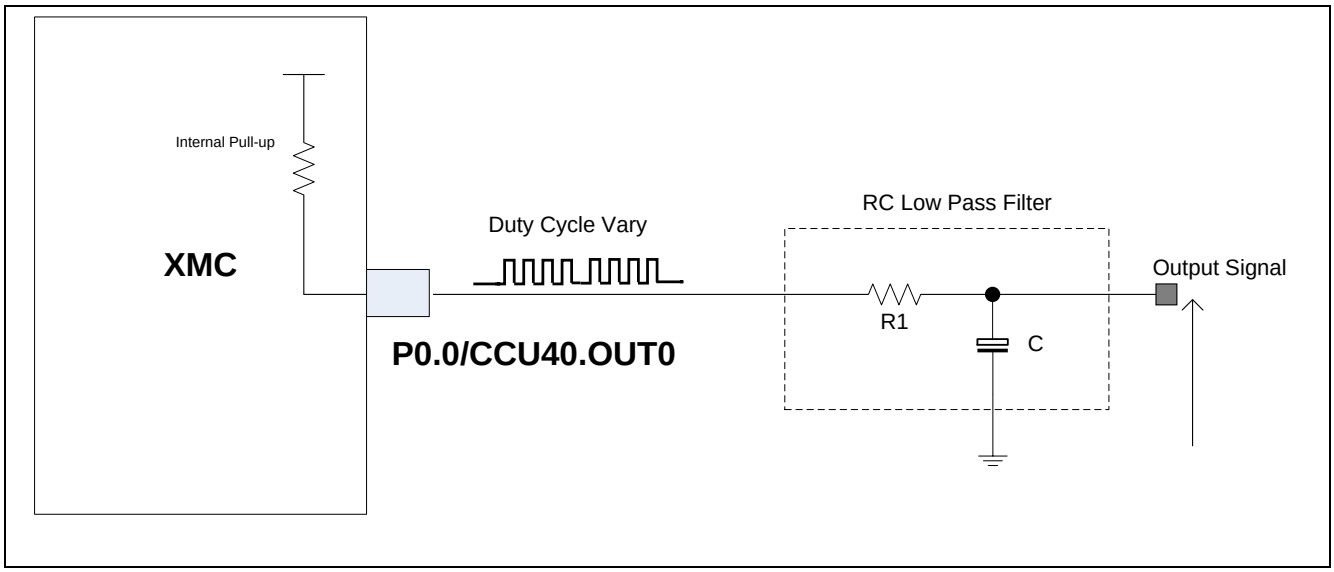

Figure 25 Low pass RC circuit with XMC CCU40.OUT0 to attenuate high frequency

2.2.5 Macro and variable settings

XMC™ Lib project includes:

```
#include <xmc_ccu4.h>
#include <xmc_gpio.h>
#include <xmc_scu.h>
```

Project macro definitions:

```
#define MODULE_PTR              CCU40
#define MODULE_NUMBER           (0U)

#define SLICE0_PTR              CCU40_CC40
#define SLICE0_NUMBER           (0U)
#define SLICE0_OUTPUT           P0_0
```

Project variables definition:

```
volatile uint8_t count=0;
uint16_t comparevalue[24]=      /* sine table for duty cycle*/
{
                1333U,
                988U,
                667U,
                390U,
                179U,
                45U,
```

```
                0U,
                45U,
                179U,
                390U,
                667U,
                988U,
                1333U,
                1678U,
                2000U,
                2276U,
                2487U,
                2621U,
                2666U,
                2621U,
                2487U,
                2276U,
                2000U,
                1678U,
};
```

2.2.6 XMC™ Lib peripheral configuration structure

XMC™ System Clock Unit (SCU) configuration:

PWM period is calculated based on PCLK which is equivalent to 64 MHz.

```
XMC_SCU_CLOCK_CONFIG_t clock_config =
{
  .pclk_src = XMC_SCU_CLOCK_PCLKSRC_DOUBLE_MCLK,
  .rtc_src = XMC_SCU_CLOCK_RTCCLKSRC_DCO2,
   .fdiv = 0,
   .idiv = 1,
};
```

XMC™ Capture/Compare Unit 4 (CCU4) configuration:

```
XMC_CCU4_SLICE_COMPARE_CONFIG_t SLICE0_config =
{
  .timer_mode = (uint32_t) XMC_CCU4_SLICE_TIMER_COUNT_MODE_EA,
  .monoshot = (uint32_t) false,
  .shadow_xfer_clear = (uint32_t) 0,
  .dither_timer_period = (uint32_t) 0,
  .dither_duty_cycle = (uint32_t) 0,
  .prescaler_mode = (uint32_t) XMC_CCU4_SLICE_PRESCALER_MODE_NORMAL,
  .mcm_enable = (uint32_t) 0,
  .prescaler_initval = (uint32_t) 0,    /* in this case, prescaler = 2^0 = 1 */
  .float_limit = (uint32_t) 0,
  .dither_limit = (uint32_t) 0,
  .passive_level = (uint32_t) XMC_CCU4_SLICE_OUTPUT_PASSIVE_LEVEL_LOW,
  .timer_concatenation = (uint32_t) 0
};
```

XMC™ GPIO configuration:

```
XMC_GPIO_CONFIG_t SLICE0_OUTPUT_config =
{
   .mode = XMC_GPIO_MODE_OUTPUT_PUSH_PULL_ALT4,
   .input_hysteresis = XMC_GPIO_INPUT_HYSTERESIS_STANDARD,
   .output_level = XMC_GPIO_OUTPUT_LEVEL_LOW,
};
```

2.2.7 Interrupt service routine function implementation

The CCU40 interrupt handler function is created to update the timer compare match values to achieve a sine signal.

```
void CCU40_0_IRQHandler(void)
{
    /* Clear pending interrupt */
    XMC_CCU4_SLICE_ClearEvent(SLICE0_PTR,XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP);

   /* Set new duty cycle value */
   XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, comparevalue[count]);

   count++;
   if(count==24)
   {
     count=0;
   }

   /* Enable shadow transfer for the new PWM value update */
   XMC_CCU4_EnableShadowTransfer(MODULE_PTR, XMC_CCU4_SHADOW_TRANSFER_SLICE_0);
}
```

2.2.8 Main function implementation

Before the start and execution of timer slice software for the first time, the CCU4 must be initialized appropriately using the following sequence:

- Set up the system clock

```
/* Ensure clock frequency is set at 64MHz (2*MCLK) */
XMC_SCU_CLOCK_Init(&clock_config);
```

- Enable clock, enable prescaler block and configure global control

```
/* Enable clock, enable prescaler block and configure global control */
XMC_CCU4_Init(MODULE_PTR, XMC_CCU4_SLICE_MCMS_ACTION_TRANSFER_PR_CR);

/* Start the prescaler and restore clocks to slices */
XMC_CCU4_StartPrescaler(MODULE_PTR);

/* Start of CCU4 configurations */
/* Ensure fCCU reaches CCU40 */
```

```
XMC_CCU4_SetModuleClock(MODULE_PTR, XMC_CCU4_CLOCK_SCU);
```

- Configure slice(s) functions, interrupts and start-up

```
/* Initialize the Slice */
XMC_CCU4_SLICE_CompareInit(SLICE0_PTR, &SLICE0_config);

/* Program 100kHz frequency */
XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, comparevalue[count]);
XMC_CCU4_SLICE_SetTimerPeriodMatch(SLICE0_PTR, 2665U);

/* Enable shadow transfer */
XMC_CCU4_EnableShadowTransfer(MODULE_PTR,       \
        (uint32_t)(XMC_CCU4_SHADOW_TRANSFER_SLICE_0|    \
                XMC_CCU4_SHADOW_TRANSFER_PRESCALER_SLICE_0));

/* Enable compare match event */
XMC_CCU4_SLICE_EnableEvent(SLICE0_PTR, XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP);

/* Connect compare match event to SR0 */
XMC_CCU4_SLICE_SetInterruptNode(SLICE0_PTR, \
        XMC_CCU4_SLICE_IRQ_ID_COMPARE_MATCH_UP, XMC_CCU4_SLICE_SR_ID_0);

/* Set NVIC priority */
NVIC_SetPriority(CCU40_0_IRQn, 3U);

/* Enable IRQ */
NVIC_EnableIRQ(CCU40_0_IRQn);

/* Enable CCU4 PWM output */
XMC_GPIO_Init(SLICE0_OUTPUT, &SLICE0_OUTPUT_config);

/* Get the slice out of idle mode */
XMC_CCU4_EnableClock(MODULE_PTR, SLICE0_NUMBER);
```

- Start timer running

```
/* Start the TImer*/
XMC_CCU4_SLICE_StartTimer(SLICE0_PTR);
```

3 Advanced signal measurement

3.1 Capture mode

3.1.1 Slice timer setup in capture mode

Each CCU4x has 4 timer-slices. Each slice has 4 capture value registers, split into 2 pairs that capture on selected event control input either Capt0 or Capt1, according to 2 possible pair schemes: either as 2 pairs for different events for Capt0 with respect to Capt1, or cascaded for the same event via Capt1.

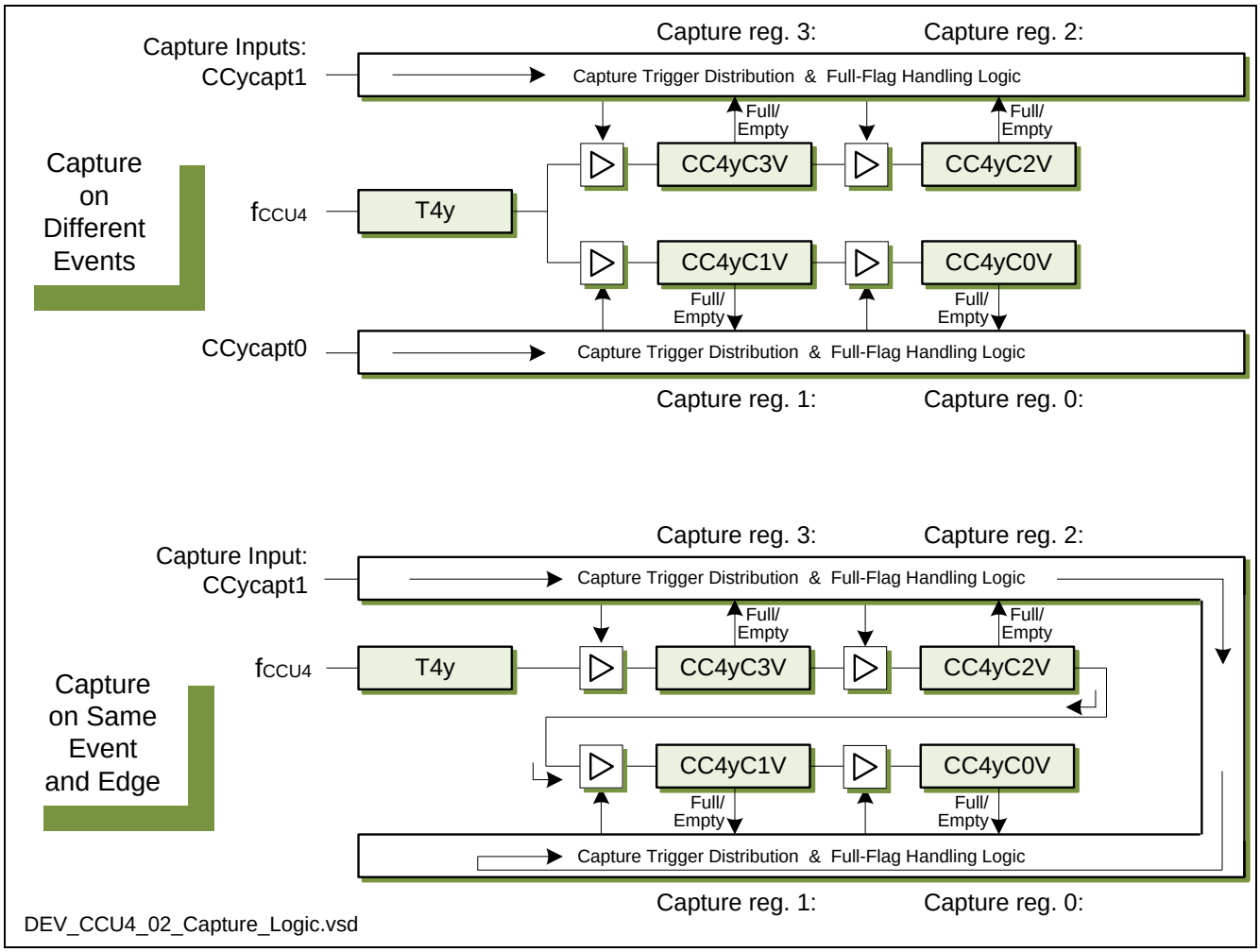

Figure 26 Slice capture logic

3.1.2 The capture algorithm

Each capture register has a full-flag that is set on a capture to the register and cleared on a read from the register.

At a capture input event (Capt1 or Capt0), each register captures data from the next higher indexed register only if that higher register is full and also a lower indexed register is empty. The timer is seen as the highest index.

Continuous capturing without any effect from any full-flags is enabled by changing the bit CC4yTC.CCS = 1. When set, registers capture data on the capture input events without taking account of the full flag status.

3.1.3 Capture by externals events control

This scenario involves linking the Capture0 or the Capture1 register pairs to an external trigger request from any of the following: GPIO, ERU, POSIF, CAN, CCU4x, USIC, ADC, CCU8x or SCU. A connection pin table is given by the top-level interconnection matrix.

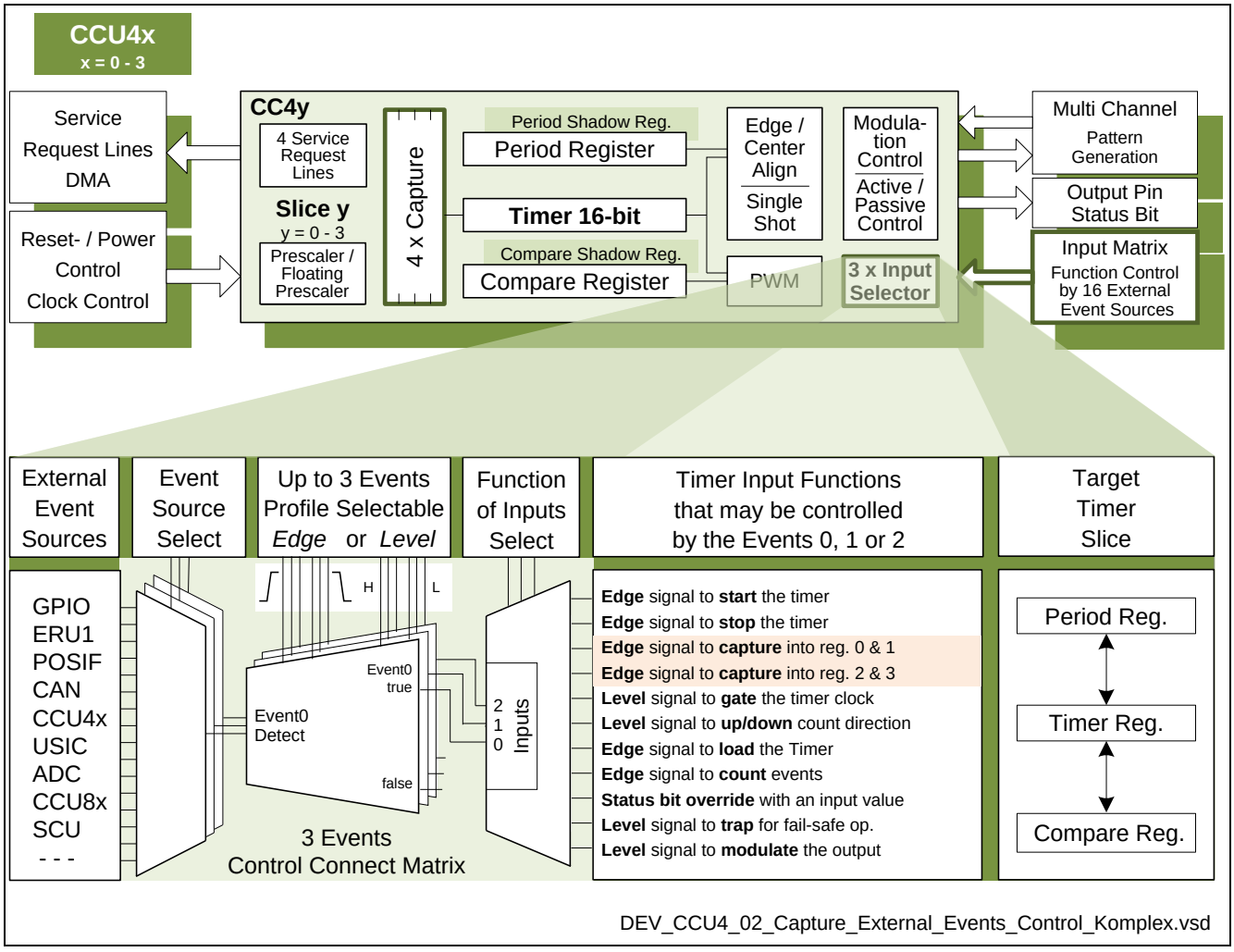

Figure 27 Capture by external events control

3.1.4 Timer inputs from capture

There are 3 selectable input lines with configurable source-event-condition profiles available for capture by external event control functions, extendable in the CC4yTC register. There is also a read access register (ECRD) that simplifies the administration of capture registers and full-flags, when more than 1 slice is used in capture mode.

3.1.5 External control by capture events

A capture event can trigger external actions via the top-level interconnect matrix or request for an interrupt. Each CAPCOM4 has four service request lines and each slice has a dedicated output signal CC4ySR[3…0] selectable to a line by using CC4ySRS. For example, a capture event may request action from some other unit for an interrupt.

3.1.6 Top-level control of event requests to/from a timer in capture mode

Top-level control means conditional control of event requests between a slice and other action providers. The event request unit (ERU1) and the top-level interconnect matrix may combine, control and link event signals according to user defined request-to-action event patterns. For example, capture on timer and other event status.

3.2 Example application: CCU4 capture mode to measure PWM duty cycle

Each timer slice can make use of two or four capture registers. By using only two capture registers, one event is linked to a capture trigger. To use four capture registers, both capture triggers need to be mapped to an event - it can be same signal with different edge selections or two different signals. The CC4yTC.SCE needs to be set to 1, which enables the linking of the 4 capture registers. The internal slice mechanism for capturing is the same for the capture trigger one or capture trigger zero.

In this example, based on XMC1200, a PWM signal is generated on the CCU40.40 slice for 24 kHz frequency with a 33.33% duty cycle. The PWM output is generated on Port 0.0. This signal shall be connected manually to P0.1, which is the external capture input for CCU40.41 slice. This slice is configured as a capture slice, where the timer is cleared on capture event 0 (which is the rising edge of the input signal). On the rising edge event, a capture event stores the timer value to capture register 1 (C1V). This is the timer value corresponding to the period for the whole signal. On a falling edge event, a capture event stores the timer value to capture register 3 (C3V), corresponding to the duty cycle for the input signal.

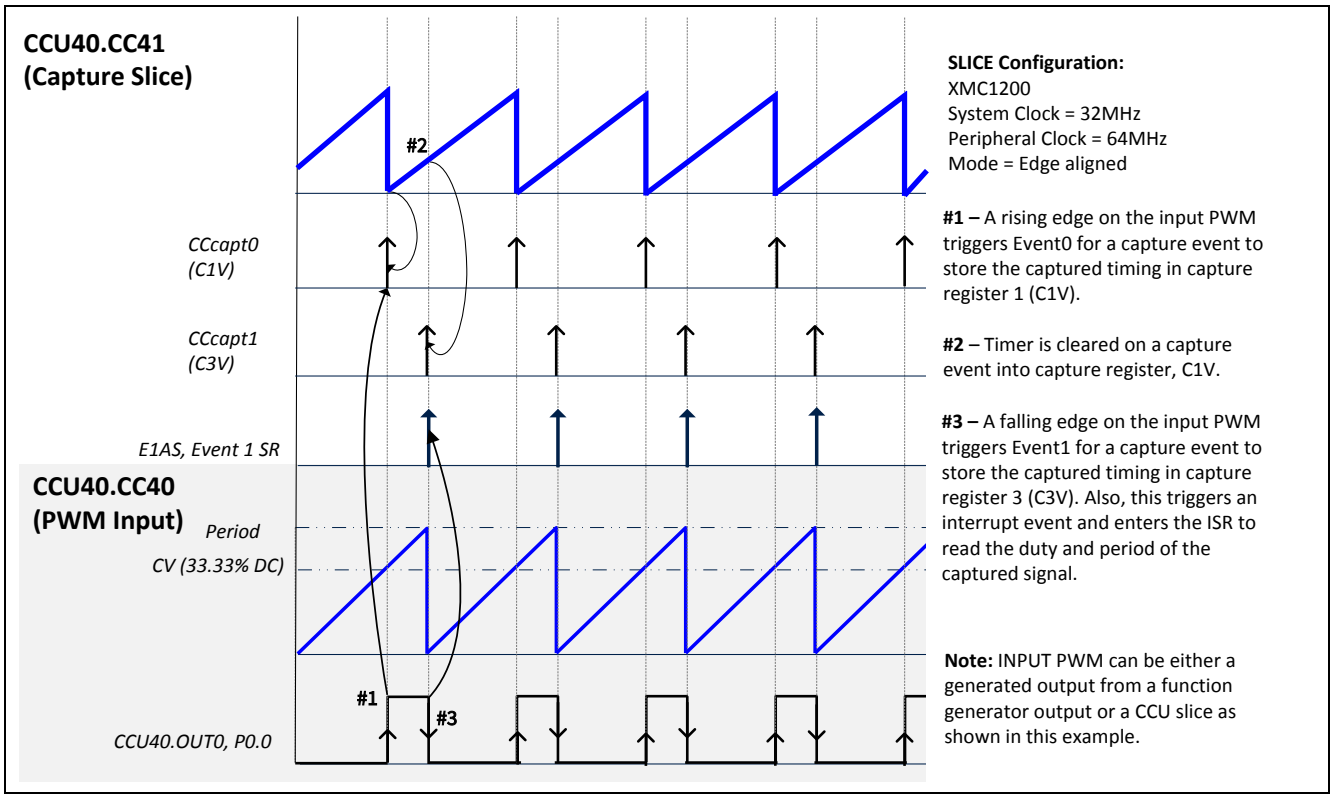

Figure 28 Example: using the CCU4 in capture mode to measure a duty cycle of a signal

3.2.1 Macro and variable settings

XMC™ Lib project includes:

```
#include <xmc_ccu4.h>
#include <xmc_gpio.h>
#include <xmc_scu.h>
```

Project macro definitions:

```
#define MODULE_PTR              CCU40
#define MODULE_NUMBER           (0U)

#define SLICE0_PTR              CCU40_CC40
#define SLICE0_NUMBER           (0U)
#define SLICE0_OUTPUT           P0_0

#define CAPTURE_SLICE_PTR       CCU40_CC41
#define CAPTURE_SLICE_NUMBER    (1U)
```

Project variables definition:

```
volatile uint32_t duty;
volatile uint32_t period;
```

3.2.2 XMC™ Lib peripheral configuration structure

XMC™ System Clock Unit (SCU) configuration:

PWM period is calculated based on PCLK which is equivalent to 64 MHz:

```
XMC_SCU_CLOCK_CONFIG_t clock_config =
{
  .pclk_src = XMC_SCU_CLOCK_PCLKSRC_DOUBLE_MCLK,
  .rtc_src = XMC_SCU_CLOCK_RTCCLKSRC_DCO2,
   .fdiv = 0,
   .idiv = 1,
};
```

XMC™ Capture/Compare Unit 4 (CCU4) configuration for PWM input:

```
XMC_CCU4_SLICE_COMPARE_CONFIG_t SLICE0_config =
{
  .timer_mode           = (uint32_t) XMC_CCU4_SLICE_TIMER_COUNT_MODE_EA,
  .monoshot             = (uint32_t) false,
  .shadow_xfer_clear    = (uint32_t) 0,
  .dither_timer_period  = (uint32_t) 0,
  .dither_duty_cycle    = (uint32_t) 0,
  .prescaler_mode       = (uint32_t) XMC_CCU4_SLICE_PRESCALER_MODE_NORMAL,
  .mcm_enable           = (uint32_t) 0,
  .prescaler_initval    = (uint32_t) 0, /* range: 0 to 15; 2^prescaler */
  .float_limit          = (uint32_t) 0,
  .dither_limit         = (uint32_t) 0,
  .passive_level        = (uint32_t) XMC_CCU4_SLICE_OUTPUT_PASSIVE_LEVEL_LOW,
```

```
  .timer_concatenation  = (uint32_t) 0
};
```

XMC™ Capture/Compare Unit 4 (CCU4) configuration for capture:

```
/* Capture Slice configuration */
XMC_CCU4_SLICE_CAPTURE_CONFIG_t capture_config =
{
   .fifo_enable         = false,
/* Clear only when timer value has been captured in C1V and C0V */
   .timer_clear_mode = XMC_CCU4_SLICE_TIMER_CLEAR_MODE_CAP_LOW,
   .same_event          = false,
   .ignore_full_flag    = true,
   .prescaler_mode      = XMC_CCU4_SLICE_PRESCALER_MODE_NORMAL,
   .prescaler_initval   = (uint32_t) 0,
   .float_limit         = (uint32_t) 0,
   .timer_concatenation = (uint32_t) 0
};

XMC_CCU4_SLICE_EVENT_CONFIG_t capture_event0_config =  //off time capture
{
  .mapped_input = XMC_CCU4_SLICE_INPUT_C,               //CAPTURE on P0.1
  .edge         = XMC_CCU4_SLICE_EVENT_EDGE_SENSITIVITY_RISING_EDGE,
  .level        = XMC_CCU4_SLICE_EVENT_LEVEL_SENSITIVITY_ACTIVE_HIGH,
  .duration     = XMC_CCU4_SLICE_EVENT_FILTER_7_CYCLES
};

XMC_CCU4_SLICE_EVENT_CONFIG_t capture_event1_config =  //on time capture
{
  .mapped_input = XMC_CCU4_SLICE_INPUT_C,               //CAPTURE on P0.1
  .edge         = XMC_CCU4_SLICE_EVENT_EDGE_SENSITIVITY_FALLING_EDGE,
  .level        = XMC_CCU4_SLICE_EVENT_LEVEL_SENSITIVITY_ACTIVE_HIGH,
  .duration     = XMC_CCU4_SLICE_EVENT_FILTER_7_CYCLES
};
```

XMC™ GPIO configuration:

```
XMC_GPIO_CONFIG_t SLICE0_OUTPUT_config =
{
   .mode                = XMC_GPIO_MODE_OUTPUT_PUSH_PULL_ALT4,
   .input_hysteresis    = XMC_GPIO_INPUT_HYSTERESIS_STANDARD,
   .output_level        = XMC_GPIO_OUTPUT_LEVEL_LOW,
};
```

3.2.3 Interrupt service routine function implementation

The CCU40 interrupt handler function reads the captured values to calculate the duty cycle on Event 1:

```
/* Interrupt handler - at event 1 to read the captured value for the duty cycle and period
of the input signal */

void CCU40_2_IRQHandler(void)
{
```

```
        uint32_t capturedvalue1;
        uint32_t capturedvalue3;

        /* Clear pending interrupt */
        XMC_CCU4_SLICE_ClearEvent(CAPTURE_SLICE_PTR, XMC_CCU4_SLICE_IRQ_ID_EVENT1);

        Capturedvalue1 = XMC_CCU4_SLICE_GetCaptureRegisterValue(CAPTURE_SLICE_PTR,1U);
        Capturedvalue3 = XMC_CCU4_SLICE_GetCaptureRegisterValue(CAPTURE_SLICE_PTR,3U);

        /* Captured value for the period and duty cycle of the signal */
        period = capturedvalue1 & CCU4_CC4_CV_CAPTV_Msk;
        duty = capturedvalue3 & CCU4_CC4_CV_CAPTV_Msk;
}
```

3.2.4 Main function implementation

Before the start and execution of timer slice software for the first time, the CCU4 must have been initialized appropriately using the following sequence:

- Set up the system clock

```
/* Ensure clock frequency is set at 64MHz (2*MCLK) */
XMC_SCU_CLOCK_Init(&clock_config);
```

- Enable clock, enable prescaler block and configure global control

```
/* Enable clock, enable prescaler block and configure global control */
XMC_CCU4_Init(MODULE_PTR, XMC_CCU4_SLICE_MCMS_ACTION_TRANSFER_PR_CR);

/* Start the prescaler and restore clocks to slices */
XMC_CCU4_StartPrescaler(MODULE_PTR);

/* Start of CCU4 configurations */
/* Ensure fCCU reaches CCU40 */
XMC_CCU4_SetModuleClock(MODULE_PTR, XMC_CCU4_CLOCK_SCU);
```

- Configure slice(s) Functions, interrupts and start-up:

```
/* Initialize the Slice */
XMC_CCU4_SLICE_CompareInit(SLICE0_PTR, &SLICE0_config);
XMC_CCU4_SLICE_CaptureInit(CAPTURE_SLICE_PTR, &capture_config);


/* Program duty cycle[33.3%] and frequency [24 KHz] */
XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, 1777);
XMC_CCU4_SLICE_SetTimerPeriodMatch(SLICE0_PTR, 2665U);

/* Enable shadow transfer for PWM and Capture Slices */
XMC_CCU4_EnableShadowTransfer(MODULE_PTR, \
        (uint32_t)(XMC_CCU4_SHADOW_TRANSFER_SLICE_0| \
        XMC_CCU4_SHADOW_TRANSFER_SLICE_1));

/* Configure events */
XMC_CCU4_SLICE_Capture0Config(CAPTURE_SLICE_PTR, XMC_CCU4_SLICE_EVENT_0);
```

```
XMC_CCU4_SLICE_Capture1Config(CAPTURE_SLICE_PTR, XMC_CCU4_SLICE_EVENT_1);

XMC_CCU4_SLICE_ConfigureEvent(CAPTURE_SLICE_PTR, \
        XMC_CCU4_SLICE_EVENT_0, &capture_event0_config);
XMC_CCU4_SLICE_ConfigureEvent(CAPTURE_SLICE_PTR, \
        XMC_CCU4_SLICE_EVENT_1, &capture_event1_config);

/* Enable events */
XMC_CCU4_SLICE_EnableEvent(CAPTURE_SLICE_PTR, XMC_CCU4_SLICE_IRQ_ID_EVENT1);

/* Connect capture on event 1 to SR2 */
XMC_CCU4_SLICE_SetInterruptNode(CAPTURE_SLICE_PTR, \
        XMC_CCU4_SLICE_IRQ_ID_EVENT1, XMC_CCU4_SLICE_SR_ID_2);

/* Configure NVIC */
/* Set priority */
NVIC_SetPriority(CCU40_2_IRQn, 3U);

/* Enable IRQ */
NVIC_EnableIRQ(CCU40_2_IRQn);

/*Enable CCU4 PWM output*/
XMC_GPIO_Init(SLICE0_OUTPUT, & SLICE0_OUTPUT_config);


/* Get the slices out of idle mode */
XMC_CCU4_EnableClock(MODULE_PTR, SLICE0_NUMBER);
XMC_CCU4_EnableClock(MODULE_PTR, CAPTURE_SLICE_NUMBER);
```

- Start timer running:

```
XMC_CCU4_SLICE_StartTimer(SLICE0_PTR);
XMC_CCU4_SLICE_StartTimer(CAPTURE_SLICE_PTR);
```

4 Event trigger delay by single shot

4.1 Introduction

A timer in single shot mode has a specific role for applications where a certain delay has to be invoked between trigger events and operations that should be triggered. For example, noise rejection in shunt current signal measurement. Any CAPCOM4 timer could be setup in this mode to co-operate with other timers, ADC, or other modules.

4.1.1 Timer setup in single shot mode

A slice can be set into Timer Single Shot Mode (TSSM). Both the timer and its run bit (TRB) is cleared by a timer period end that occurs after the TSSM bit is set, and the timer is stopped. A time frame, for example, a single shot delay, is set by the timer start conditions, selected counting mode and the period (PR) value.

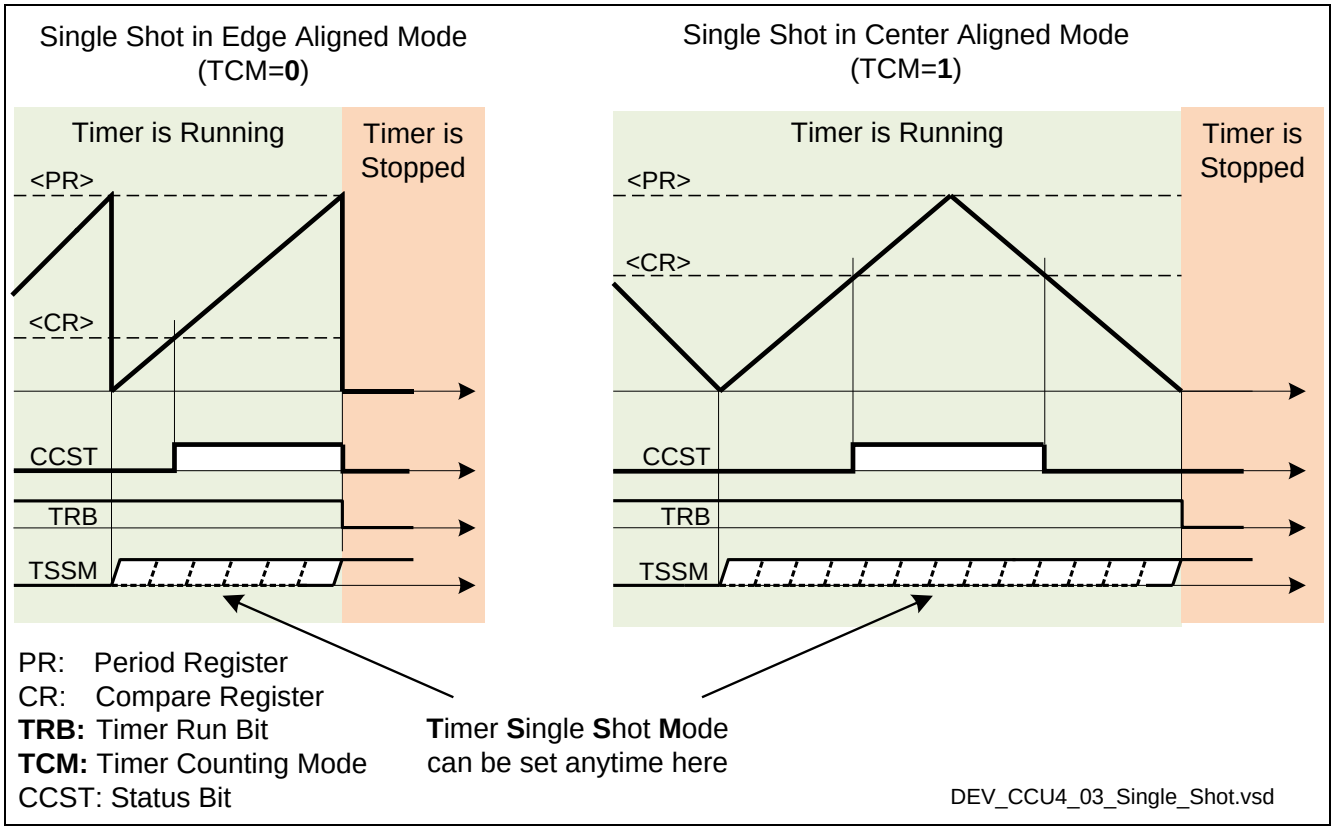

Figure 29 Timer in Single Shot Mode(TSSM) for edge aligned and center aligned mode

4.1.2 Using timer single shot delay for noise rejection

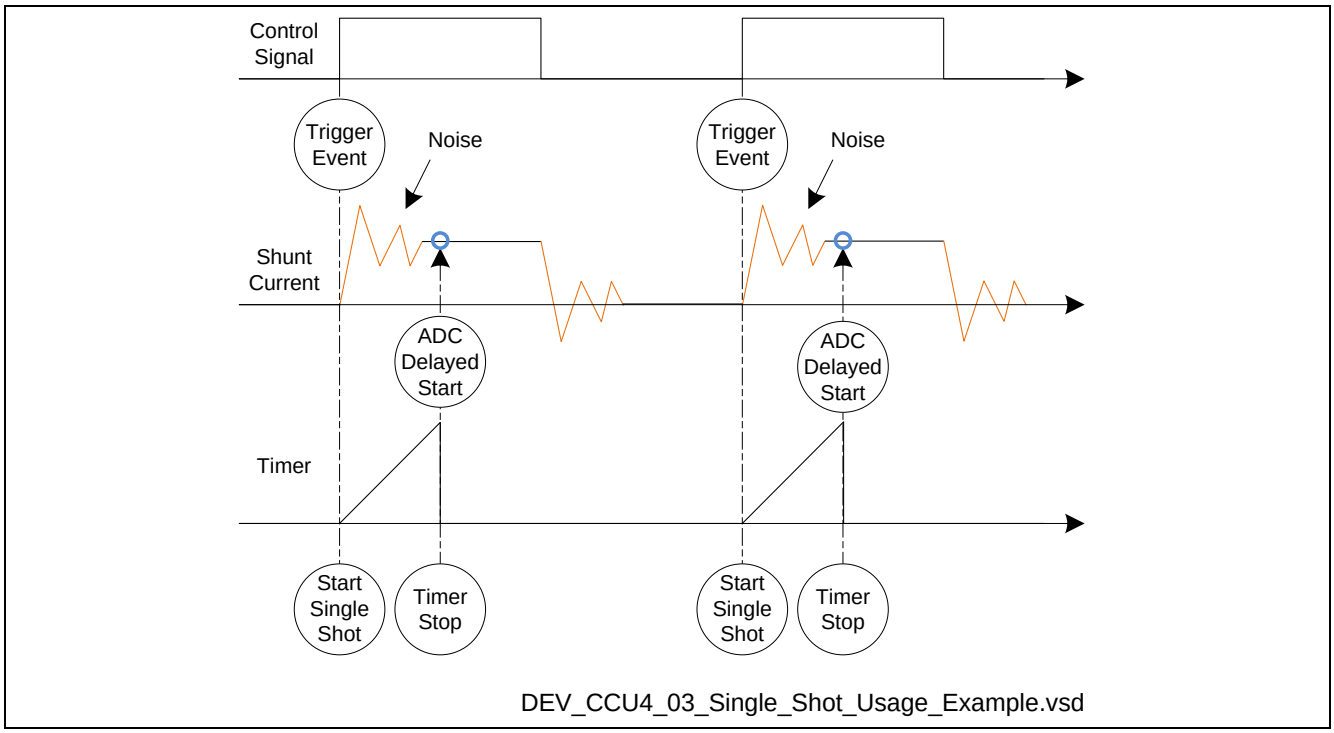

Figure 30 Timer in single shot mode for noise rejection in shunt-current measurement

4.1.3 Timer-start in single shot mode by external event control

A timer-start in single shot mode can be linked to external triggers from sources such as: GPIO, ERU, POSIF, CAN, CCU4x, USIC, ADC, CCU8x or SCU. Pin connections are given by the top-level interconnect matrix and the CC4yINS[P:A] input select vector and function select by the CC4yCMC register.

4.1.4 Timer inputs for start and stop facilities

A timer has 3 selectable function inputs with configurable source-event-condition profiles. These 3 function inputs can each have up to 16 sources for external events control, such as timer start or stop. The extended functions such as flush/start, flush/stop or flush only can also be added in single-shot mode via the CC4yTC register.

Event trigger delay by single shot

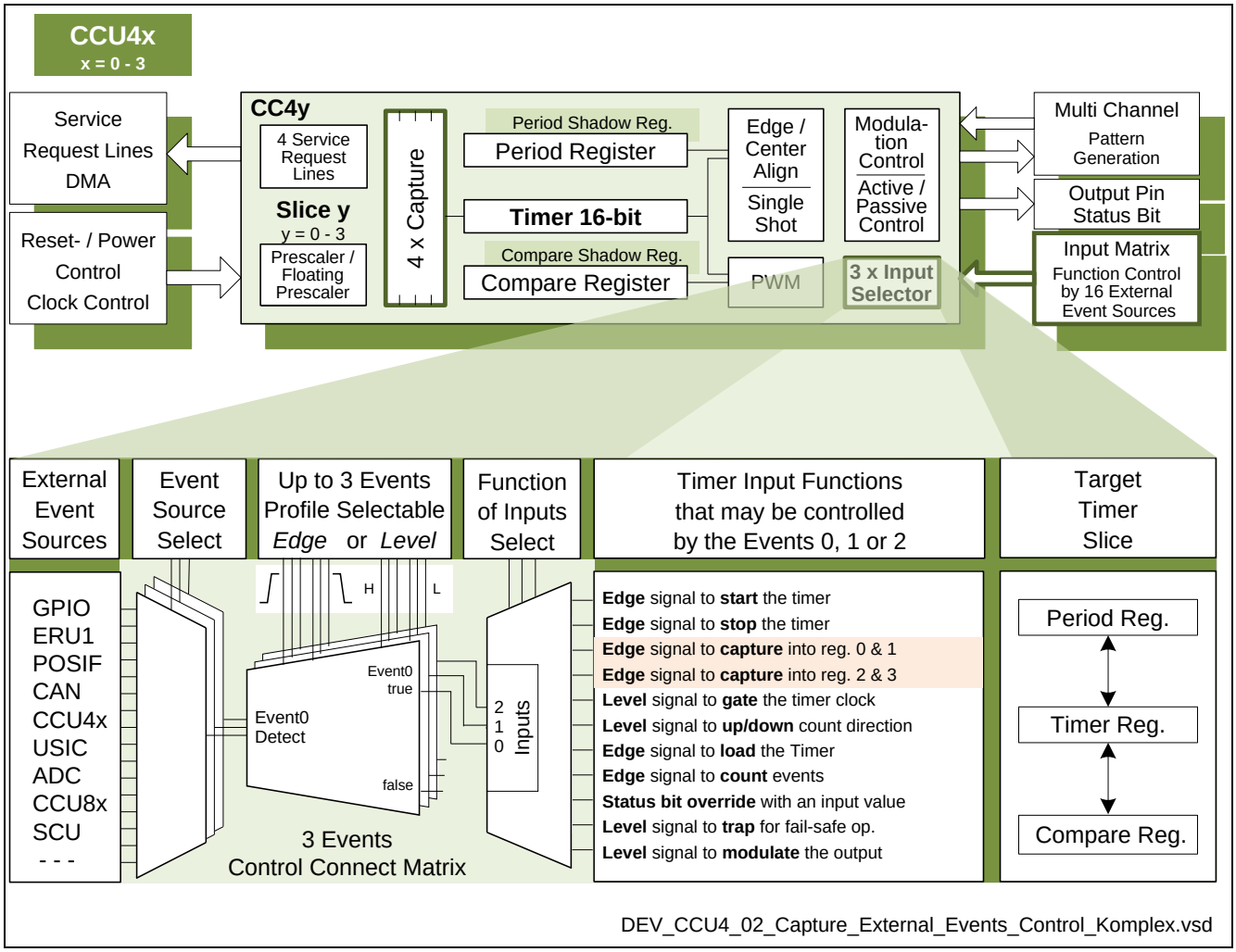

Figure 31 Single shot triggering on external events

4.1.5 External control by single-shot events

Single-shot events trigger external actions via the top-level interconnection matrix or they can request an interrupt. Each CAPCOM4 has four service request lines and each slice has a dedicated output signal CC4ySR[3…0] selectable to a line via CC4ySRS. Therefore, single-shot can act as a delayed trigger for ADC actions or interrupts.

4.1.6 Top-level control of event request to/from a timer in single-shot mode

Top-level control also means conditional control of event requests between a slice and other action providers. The Event Request Unit (ERU1) and the top-level interconnect matrix could combine, control and link event signal according to user defined request-to-action event patterns, such as ADC triggering limited by time windows.

4.2 Example use case: triggering ADC conversion using CCU4 single shot

In this example, based on the XMC1200, a push button is connected to P0.0 to simulate a trigger event used to start a timer in single shot mode. This starts the timer and a period match event is generated at the end of the timer count. This triggers an ADC queue conversion request. A conversion takes place on the selected pin once it is triggered. The result is stored in the ADC result register corresponding to selected channel. An interrupt is generated after the completion of a conversion.

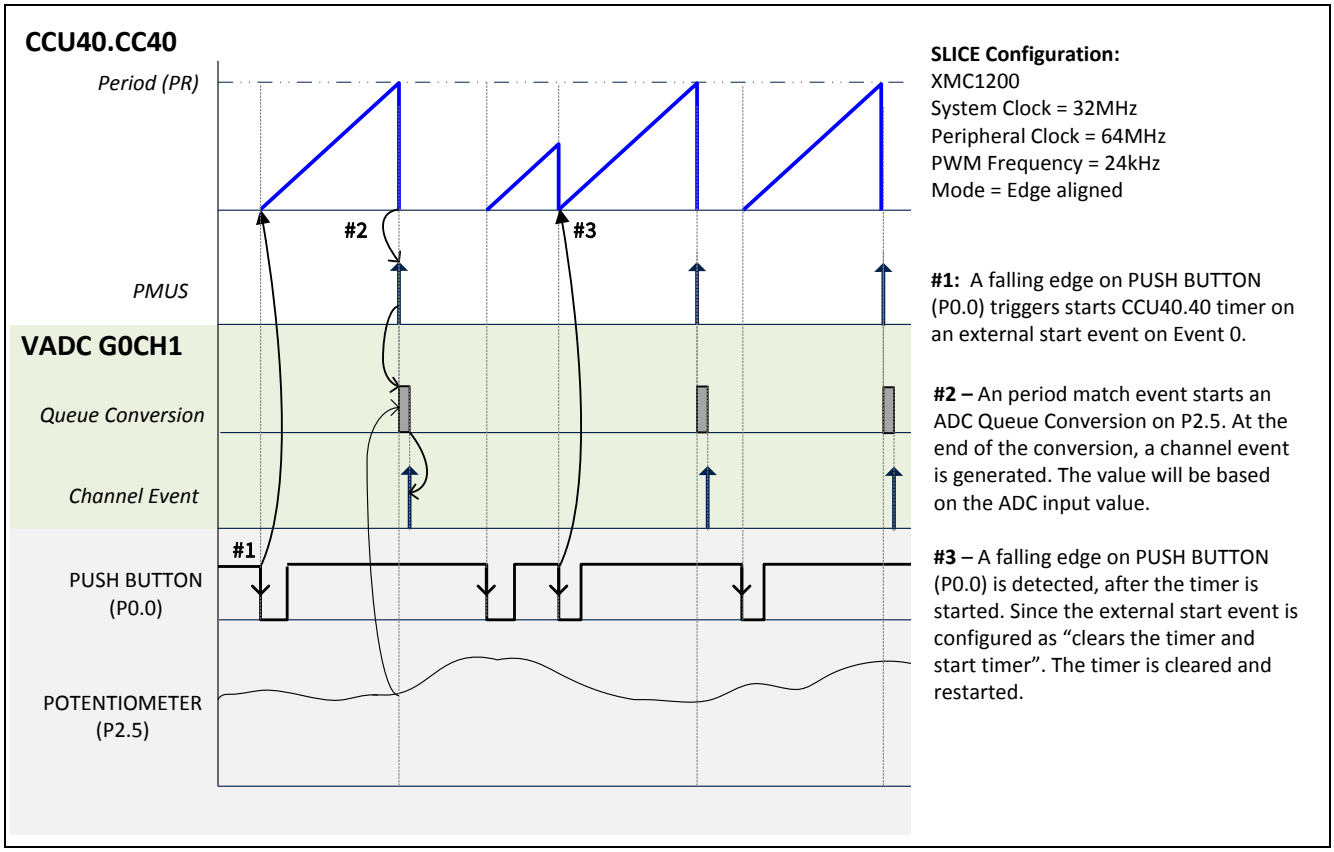

Figure 32 Example: triggering an ADC conversion using CCU4 single shot

4.2.1 Macro and variable settings

XMC™ Lib project includes:

```
#include <xmc_ccu4.h>
#include <xmc_vadc.h>
```

Project macro definitions:

```
/* CCU4 Macros*/
#define MODULE_PTR              CCU40
#define MODULE_NUMBER           (0U)

#define SLICE0_PTR              CCU40_CC40
#define SLICE0_NUMBER           (0U)


/* VADC Macros */
```

Event trigger delay by single shot

```
#define RES_REG_NUMBER                  (0)
#define CHANNEL_NUMBER                  (7U)
#define VADC_GROUP_PTR                  (VADC_G1) /* P2.5 */
#define VADC_GROUP_ID                   (1)
#define IRQ_PRIORITY                    (10U)
```

4.2.2 XMC™ Lib peripheral configuration structure

XMC™ System Clock Unit (SCU) configuration:

PWM period is calculated based on PCLK which is equivalent to 64 MHz:

```
XMC_SCU_CLOCK_CONFIG_t clock_config =
{
  .pclk_src = XMC_SCU_CLOCK_PCLKSRC_DOUBLE_MCLK,
  .rtc_src = XMC_SCU_CLOCK_RTCCLKSRC_DCO2,
   .fdiv = 0,
   .idiv = 1,
};
```

XMC™ Versatile Analog-to-Digital Converter (VADC) configuration:

```
XMC_VADC_GLOBAL_CONFIG_t g_global_handle =
{
 .disable_sleep_mode_control = false,
 .clock_config = {
                        .analog_clock_divider   = 3,
                        .msb_conversion_clock   = 0,
                        .arbiter_clock_divider  = 1
                  },
 .class0 = {
                .conversion_mode_standard       = XMC_VADC_CONVMODE_12BIT,
                .sample_time_std_conv           = 3U,
                .conversion_mode_emux           = XMC_VADC_CONVMODE_12BIT,
                .sampling_phase_emux_channel    = 3U
                        },
 .class1 = {
                .conversion_mode_standard       = XMC_VADC_CONVMODE_12BIT,
                .sample_time_std_conv           = 3U,
                .conversion_mode_emux           = XMC_VADC_CONVMODE_12BIT,
                .sampling_phase_emux_channel    = 3U
                        },
 .data_reduction_control = 0,
 .wait_for_read_mode     = true,
 .event_gen_enable       = false,
 .boundary0              = 0,
 .boundary1              = 0
  };


/* Initialization data of a VADC group */
```

Event trigger delay by single shot

```
XMC_VADC_GROUP_CONFIG_t g_group_handle =
{
        .class0 = {
                .conversion_mode_standard       = XMC_VADC_CONVMODE_12BIT,
                .sample_time_std_conv           = 3U,
                .conversion_mode_emux           = XMC_VADC_CONVMODE_12BIT,
                .sampling_phase_emux_channel    = 3U
                        },
 .class1 = {
                .conversion_mode_standard       = XMC_VADC_CONVMODE_12BIT,
                .sample_time_std_conv           = 3U,
                .conversion_mode_emux           = XMC_VADC_CONVMODE_12BIT,
                .sampling_phase_emux_channel    = 3U
                        },
 .arbitration_round_length        = 0x0U,
 .arbiter_mode                    = XMC_VADC_GROUP_ARBMODE_ALWAYS,
 .boundary0                       = 0, /* Boundary-0 */
 .boundary1                       = 0, /* Boundary-1 */
 .emux_config = {
                .emux_mode                = XMC_VADC_GROUP_EMUXMODE_SWCTRL,
                .stce_usage               = 0,
                .emux_coding              = XMC_VADC_GROUP_EMUXCODE_BINARY,
                .starting_external_channel = 0,
                .connected_channel        = 0
                                }
                                        };

/* Identifier of the hardware group */
XMC_VADC_GROUP_t *g_group_identifier =VADC_GROUP_PTR;

/* Channel configuration data */
XMC_VADC_CHANNEL_CONFIG_t g_channel_handle =
{
  .channel_priority             = 1U,
  .input_class                  = XMC_VADC_CHANNEL_CONV_GROUP_CLASS1,
  .alias_channel                = (uint8_t)-1,
  .bfl                          = 0,
  .event_gen_criteria           = XMC_VADC_CHANNEL_EVGEN_ALWAYS,
  .alternate_reference          = XMC_VADC_CHANNEL_REF_INTREF,
  .result_reg_number            = (uint8_t) RES_REG_NUMBER,
  .sync_conversion              = false,                          /* Sync Feature disabled*/
  .result_alignment             = XMC_VADC_RESULT_ALIGN_RIGHT,
  .use_global_result            = false,
  .broken_wire_detect_channel   = false,
  .broken_wire_detect           = false
};

/* Result configuration data */
XMC_VADC_RESULT_CONFIG_t g_result_handle = {
        .post_processing_mode   = XMC_VADC_DMM_REDUCTION_MODE,
        .data_reduction_control = 0,
        .part_of_fifo           = false,        /* No FIFO */
```

Event trigger delay by single shot

```
        .wait_for_read_mode     = true,         /* WFS */
        .event_gen_enable       = false         /* No result event */
};

/* Queue hardware configuration data */
XMC_VADC_QUEUE_CONFIG_t g_queue_handle =
{
  .req_src_priority     = (uint8_t)3, /* Highest Priority = 3, Lowest = 0 */
  .conv_start_mode      = XMC_VADC_STARTMODE_WFS,
  .external_trigger     = (bool) true, /* External trigger enabled*/
  .trigger_signal       = XMC_CCU_40_SR2,
  .trigger_edge         = XMC_VADC_TRIGGER_EDGE_FALLING,
  .gate_signal          = XMC_VADC_REQ_GT_A,
  .timer_mode           = (bool) false, /* No timer mode */
};

/* Queue Entry */
XMC_VADC_QUEUE_ENTRY_t g_queue_entry =
{
 .channel_num           = CHANNEL_NUMBER,
 .refill_needed         = true, /* Refill is needed */
 .generate_interrupt    = true, /* Interrupt generation is needed */
 .external_trigger      = true  /* External trigger is required */
};
```

XMC™ Capture/Compare Unit 4 (CCU4) configuration:

```
XMC_CCU4_SLICE_COMPARE_CONFIG_t SLICE0_config =
{
  .timer_mode           = (uint32_t) XMC_CCU4_SLICE_TIMER_COUNT_MODE_EA,
  .monoshot             = (uint32_t) true,
  .shadow_xfer_clear    = (uint32_t) 0,
  .dither_timer_period  = (uint32_t) 0,
  .dither_duty_cycle    = (uint32_t) 0,
  .prescaler_mode       = (uint32_t) XMC_CCU4_SLICE_PRESCALER_MODE_NORMAL,
  .mcm_enable           = (uint32_t) 0,
  .prescaler_initval    = (uint32_t) 0,
  .float_limit          = (uint32_t) 0,
  .dither_limit         = (uint32_t) 0,
  .passive_level        = (uint32_t) XMC_CCU4_SLICE_OUTPUT_PASSIVE_LEVEL_LOW,
  .timer_concatenation  = (uint32_t) 0
};
```

```
XMC_CCU4_SLICE_EVENT_CONFIG_t SLICE0_event0_config =
{
  .mapped_input = XMC_CCU4_SLICE_INPUT_C,               //P0.0
  .edge = XMC_CCU4_SLICE_EVENT_EDGE_SENSITIVITY_FALLING_EDGE,
  .level = XMC_CCU4_SLICE_EVENT_LEVEL_SENSITIVITY_ACTIVE_HIGH,
```

```
  .duration = XMC_CCU4_SLICE_EVENT_FILTER_7_CYCLES
};
```

4.2.3 Interrupt service routine function implementation

The ADC interrupt handler function is created to read the ADC conversion result. In this example, the ADC result is stored to a local variable:

```
void VADC0_G1_0_IRQHandler(void)
{
        XMC_VADC_RESULT_SIZE_t result;

        /* Read the result register */
        result = XMC_VADC_GROUP_GetResult(g_group_identifier,RES_REG_NUMBER);

        /* Clear result event */
        XMC_VADC_GROUP_ClearResultEvent(g_group_identifier,RES_REG_NUMBER);

        /* Acknowledge the interrupt */
        XMC_VADC_GROUP_QueueClearReqSrcEvent(g_group_identifier);

        result = result;

        /* Application specific code using ADC result can added */
}
```

4.2.4 Main function implementation

Before the start and execution of timer slice software for the first time, the CCU4 must be initialized appropriately using the following sequence:

- Set up the system clock

```
/* Ensure clock frequency is set at 64MHz (2*MCLK) */
XMC_SCU_CLOCK_Init(&clock_config);
```

- Enable clock, enable prescaler block and configure global control

```
/* Enable clock, enable prescaler block and configure global control */
XMC_CCU4_Init(MODULE_PTR, XMC_CCU4_SLICE_MCMS_ACTION_TRANSFER_PR_CR);

/* Start the prescaler and restore clocks to slices */
XMC_CCU4_StartPrescaler(MODULE_PTR);

/* Start of CCU4 configurations */
/* Ensure fCCU reaches CCU40 */
XMC_CCU4_SetModuleClock(MODULE_PTR, XMC_CCU4_CLOCK_SCU);
```

- Configure slice(s) functions, interrupts and start-up:

```
/* Initialize the Slice */
XMC_CCU4_SLICE_CompareInit(SLICE0_PTR, &SLICE0_config);
```

```
/* Program duty cycle[33.3%] and frequency [24 KHz] */
XMC_CCU4_SLICE_SetTimerCompareMatch(SLICE0_PTR, 1777);
XMC_CCU4_SLICE_SetTimerPeriodMatch(SLICE0_PTR, 2665U);


/* Enable shadow transfer for PWM Slice */
XMC_CCU4_EnableShadowTransfer(MODULE_PTR, \
        (uint32_t)XMC_CCU4_SHADOW_TRANSFER_SLICE_0);

/* Configure events - external Start */
XMC_CCU4_SLICE_ConfigureEvent(SLICE0_PTR, \
        XMC_CCU4_SLICE_EVENT_0, &SLICE0_event0_config);

XMC_CCU4_SLICE_StartConfig(SLICE0_PTR, \
        XMC_CCU4_SLICE_EVENT_0, XMC_CCU4_SLICE_START_MODE_TIMER_START_CLEAR);

/* Enable events */
XMC_CCU4_SLICE_EnableEvent(SLICE0_PTR, XMC_CCU4_SLICE_IRQ_ID_EVENT0);

/* Connect event to SR2 to trigger an ADC conversion*/
XMC_CCU4_SLICE_SetInterruptNode(SLICE0_PTR, \
        XMC_CCU4_SLICE_IRQ_ID_EVENT0, XMC_CCU4_SLICE_SR_ID_2);

/* Get the slice out of idle mode */
XMC_CCU4_EnableClock(MODULE_PTR, SLICE0_NUMBER);
```

- Configure the ADC:

```
/* Initialize the VADC global registers */
      XMC_VADC_GLOBAL_Init(VADC, &g_global_handle);

      /* Configure a conversion kernel */
      XMC_VADC_GROUP_Init(g_group_identifier, &g_group_handle);

      /* Configure the queue request source of the aforesaid conversion kernel */
      XMC_VADC_GROUP_QueueInit(g_group_identifier, &g_queue_handle);

      /* Configure a channel belonging to the aforesaid conversion kernel */
      XMC_VADC_GROUP_ChannelInit(g_group_identifier,CHANNEL_NUMBER, &g_channel_handle);

      /* Configure a result resource belonging to the aforesaid conversion kernel */
      XMC_VADC_GROUP_ResultInit(g_group_identifier, RES_REG_NUMBER, &g_result_handle);

      /* Add the channel to the queue */
      XMC_VADC_GROUP_QueueInsertChannel(g_group_identifier, g_queue_entry);


      /* Set priority of NVIC node meant to e connected to Kernel Request source event */
      NVIC_SetPriority(VADC0_G1_0_IRQn, IRQ_PRIORITY);

      /* Connect RS Event to the NVIC nodes */
```

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```
XMC_VADC_GROUP_QueueSetReqSrcEventInterruptNode(g_group_identifier, \
        XMC_VADC_SR_GROUP_SR0);

/* Configure NVIC */
/* Set priority */
NVIC_SetPriority(VADC0_G1_0_IRQn, 3U);

/* Enable IRQ */
NVIC_EnableIRQ(VADC0_G1_0_IRQn);

/* Enable the analog converters */
XMC_VADC_GROUP_SetPowerMode(g_group_identifier, XMC_VADC_GROUP_POWERMODE_NORMAL);

/* Perform calibration of the converter */
XMC_VADC_GLOBAL_StartupCalibration(VADC);
```

5 Revision history

Current version is revision 1.1, 2016-02

Page or reference	Description of change
V1.0, 2015-07	
	Initial version
V1.1, 2016-02	
	Updated Section 3.2 for capturing the duty and period of input signal

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